# **FEILAN JIANG**

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### **EXPERIENCE**

#### ML and Computer Vision Intern

#### **Microsoft Corporation**

Redmond, WA (Remote Internship)

 Using image processing and deep learning to automate key manufacturing quality checks

#### Infrastructure Engineering Intern

#### **Uber ATG**

🛗 Sep. 2019 - Dec. 2019

San Francisco, CA

• Developed an AWS pipeline for storing and searching thousands of calibration files, helping to enable one-touch calibration for any LiDAR test sensor

# Localization and Mapping Developer

Avidbots Corp.

🛗 Jan. 2019 - Apr. 2019

- Created an automated ROS LiDAR calibration system used to prepare dozens of floorscrubbing robots for the company's clients
- Prototyped a custom visual SLAM algorithm to assist with cleaning-plan start-pose correction and map symmetry-breaking

#### **ADAS Software Developer**

#### **BlackBerry QNX**

May 2018 - Aug. 2018

Ottawa, ON

- Enhanced a LiDAR driver with a point-cloud merging feature that shortens each library usage by up to 100 lines of C++ code
- Created and deployed an object-detection demo to showcase the ADAS stack's pointcloud downsampling and segmentation capabilities

# **PROJECTS & ACTIVITIES**

## Future Undergraduate Student Researcher %

• Research areas are perception and navigation in the self-driving space

# WATonomous Perception Team Member %

- Currently a computer vision engineer on a student team developing a level-4 autonomous vehicle for the SAE AutoDrive challenge
- Implemented a traditional computer vision-based lane detection system in OpenCV and ROS

#### Autonomous Mobile Robot %

- Developing a mobile robot that is controlled by hand gestures and uses the ROS navigation stack
- Currently experimenting with navigation technologies such as path-planning, SLAM, and obstacle avoidance

# **SKILLS**



### **LANGUAGES**

C++	~4 Years
Python	~3 Years
С	~2 Years
JavaScript	~1.5 Years

### **EDUCATION**

BASc Mechatronics Eng. University of Waterloo

## Sep. 2016 - Apr. 2021

### **INTERESTS**

