



FEI LIU

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Research Focus

Robotics in system modeling, control, dynamics, physical-based simulation, constrained optimization, haptic teleoperation and mechatronics, in particular autonomy for manipulation, surgical and biomedical applications.

Bio

Fei Liu is a postdoctoral researcher at the Contextual Robotics Institute at University of California San Diego (UCSD). He is currently working on robotic autonomy for manipulation, surgical and biomedical applications, with semantic modeling, real-to-sim simulation, and advanced control techniques. Before that, he served as a research associate and postdoctoral scholar both at the Biorobotics Institute at Scuola Superiore Sant'Anna (SSSA), and the Center for Micro-BioRobotics at Italian Institute of Technology (IIT) in Italy. He finished his Ph.D. at Laboratory Ampère at INSA de Lyon, a top French grande école and engineering university. Right after his PhD dissertation, he also worked for a start-up company (ROBO Medical Co., Ltd.), as a senior control engineer and project manager for the creation of a robot for endoscopic submucosal dissection (ESD) surgery. During the last few years, he has experiences in several robotic areas, including modeling, control, dynamics, planning, simulation, and optimization. I also have knowledge of sensor perception, signal processing, and computer vision. He has authored a number of journal and conference papers that have advanced and impacted on both the academic and industrial worlds.

Education

Institut National des Sciences Appliquées de Lyon ( INSA de Lyon) **Sep. 2013 – Sep. 2016**

Ph.D. in Robotics

Lyon, France

- Thesis title : Dual-user Haptic Training System
- Supervisors : Prof. Arnaud Lelevé, Prof. Tanneguy Redarce, Dr. Damien Eberard

Institut National des Sciences Appliquées de Lyon ( INSA de Lyon) **Sep. 2012 – Aug. 2013**

Master of Science in Robotics

Lyon, France

- Thesis title : Teleoperation System Using Port-Hamiltonian Approach
- Supervisor : Prof. Arnaud Lelevé

Northwestern Polytechnical University ( NWPU, 985 & 211 Rank) **Sep. 2008 – Jul. 2012**

Bachelor of Science in Automation

Xi'an, China

Speciality: Automation and Inertial Navigation

Working Appointments

Postdoctoral Scholar


Dec. 2019 – present

 *Advanced Robotics and Controls Lab, University of California San Diego*

San Diego, CA, USA

Advisor: Prof. [Michael Yip](#)

Research Associate Scholar

 *Biorobotics Institute, Scuola Superiore Sant'Anna*
Advisor: Prof. Filippo Cavallo

Apr. 2019 – Nov. 2019

Pisa, Italy


Postdoctoral Scholar

Center for Micro-BioRobotics, IIT@SSSA, Italian Institute of Technology

Mar. 2018 – Mar. 2019

Pisa, Italy

Senior Control Engineer & Project Director

 *ROBO Medical Technology Co., Ltd*

Oct. 2016 – Feb. 2018


Shenzhen, China

Publications







Dissertation and Thesis:


- [PhD] Fei Liu, Dual-user Haptic Training System,  archives-ouvertes.fr/tel-01514992, Ph.D. Dissertation, INSA de Lyon, 2017.
- [Master] Fei Liu, Cooperative Haptic Hands-on Minimally Invasive Surgery (MIS) Trainer, M.Sc. Thesis, INSA de Lyon, 2013.

To-submit/Internal-reviews:

- [TS-J1] **Fei Liu**, Florian Richter, Fei Yin, Chong He, Cédrec Girerd, Michael C. Yip. Continuum Robot Shape Reconstruction and Tracking from Monocular Endoscopic Image Sequences. *IEEE Robotics and Automation Letters (RAL)*, To submit.
- [TS-J2] Zhaowei Yu, Dimitri A. Schreiber, **Fei Liu**, Alexander M. Grant, Michael C. Yip. An Underwater Remote Teleoperation Robot Arm with Rolling Diaphragm Actuation and End Effector Force Reconstruction. *IEEE/ASME Transactions on Mechatronics (T-MECH)*, To submit.  [Google Drive](#)

Journal Articles (★ shares the first author.):









- [J1] **Fei Liu**★, Mingen Li★, Jingpei Lu, Entong Su, Michael C. Yip. Parameter Identification and Motion Control for Articulated Rigid Body Robots Using Differential Position-based Dynamics. *IEEE Transactions on Robotics (T-RO)*. In revision.  [arXiv: 2201.05753](https://arxiv.org/abs/2201.05753)
- [J2] **Fei Liu**★, Entong Su★, Jingpei Lu, Mingen Li, Michael C. Yip. Differentiable Robotic Manipulation of Deformable Rope-like Objects Using Compliant Position-based Dynamics. *IEEE Robotics and Automation Letters (RAL)*. **Revised**  [arXiv: 2202.09714](https://arxiv.org/abs/2202.09714)
- [J3] Xiao Liang, Shan Lin, **Fei Liu**, Dimitri Schreiber, Michael C. Yip. ORRN: An ODE-based Recursive Registration Network for Deformable Respiratory Motion Estimation with Lung 4DCT Images. *IEEE Transactions on Biomedical Engineering (T-BME)*, **Revised**  [Google Drive](#)
- [J4] Florian Richter, Shihao Shen, **Fei Liu**, Jingbin Huang, Emily K. Funk, Ryan K. Orosco, Michael C. Yip. Autonomous Robotic Suction to Clear the Surgical Field for Hemostasis Using Image-Based Blood Flow Detection. *IEEE Robotics and Automation Letters (RAL)*, 2021.  [DOI: 10.1109/LRA.2021.3056057](https://doi.org/10.1109/LRA.2021.3056057)
Nominated for Best Paper Award at ICRA
- [J5] Sarmad Mehrdad★, **Fei Liu**★, Minh Tu Pham, Arnaud Lelevé, S. Farokh Atashzar. Review of Advanced Medical Telerobots. *Applied Sciences*, 2020.  [DOI: 10.3390/app11010209](https://doi.org/10.3390/app11010209)
- [J6] Angel R. Licona, **Fei Liu**, David Pinzon, Ali Torabi, Pierre Boulanger, Arnaud Lelevé, Richard Moreau, Minh Tu Pham, Mahdi Tavakoli, Troy McDaniel. Applications of Haptics in Medicine. *Haptic Interfaces for Accessibility, Health, and Enhanced Quality of Life*, Nov. 2019.  [DOI: 10.1007/978-3-030-34230-2_7](https://doi.org/10.1007/978-3-030-34230-2_7)

- [J7] **Fei Liu**, Angel Ricardo Licon, Arnaud Lelevé, Damien Eberard, Minh Tu Pham, Tanneguy Redarce. An Energy-Based Approach for n-dof Passive Dual-user Haptic Training Systems. *Robotica*, 2019.  DOI: [10.1017/S0263574719001309](https://doi.org/10.1017/S0263574719001309)

Conference Proceedings (★ shares the first author.):

- [C1] Jingpei Lu★, **Fei Liu**★, Michael C. Yip. Image-based Pose Estimation and Shape Reconstruction for Robot Manipulators and Soft, Continuum Robots via Differentiable Rendering. *IEEE International Conference on Robotics and Automation (ICRA) 2023*. **Recent Accepted**  [Google Drive](#)
- [C2] Neelay Joglekar, **Fei Liu**, Ryan Orosco, Michael C. Yip. Suture Thread Spline Reconstruction from Endoscopic Images for Robotic Surgery with Reliability-driven Keypoint Detection. *IEEE International Conference on Robotics and Automation (ICRA) 2023*. **Recent Accepted**  [arXiv: 2209.13657](#)
- [C3] **Fei Liu**★, Zihan Li★, Yuhai Han, Jingpei Lu, Florian Richter, Michael C. Yip. Real-to-Sim Registration of Deformable Soft-Tissue with Position-Based Dynamics for Surgical Robot Autonomy. *IEEE International Conference on Robotics and Automation (ICRA) 2021*.  DOI: [10.1109/ICRA48506.2021.9561177](https://doi.org/10.1109/ICRA48506.2021.9561177)
- [C4] Jingbin Huang★, **Fei Liu**★, Florian Richter, Michael C. Yip. Model-Predictive Control of Blood Suction for Surgical Hemostasis using Differentiable Fluid Simulations. *IEEE International Conference on Robotics and Automation (ICRA)*, 2021.  DOI: [10.1109/ICRA48506.2021.9561624](https://doi.org/10.1109/ICRA48506.2021.9561624)
- [C5] Yunhai Han, **Fei Liu**, Michael C. Yip. A 2D Surgical Simulation Framework for Tool-Tissue Interaction. *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS) Workshop on Cognitive Robotic Surgery*, 2020.  [arXiv: 2010.13936](#)
- [C6] Jacob J. Johnson, Linjun Li, **Fei Liu**, Ahmed H. Qureshi, Michael C. Yip. Dynamically constrained motion planning networks for non-holonomic robots. *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, 2020.  DOI: [10.1109/IROS45743.2020.9341283](https://doi.org/10.1109/IROS45743.2020.9341283)
- [C7] Sajiv Shah, Ayaan Haque, **Fei Liu**. Simulated Data Generation Through Algorithmic Force Coefficient Estimation for AI-Based Robotic Projectile Launch Modeling. *The 6th Asia-Pacific Conference on Intelligent Robot Systems (ACIRS)*, 2021.  [arXiv: 2105.12833](#)
- [C8] Angel Ricardo Licon Rodriguez, **Fei Liu**, Arnaud Lelevé, Damien Eberard, Minh Tu Pham. Collaborative Hands-on Training on Haptic Simulators. *7th International Conference on Mechatronics and Control Engineering*, Nov. 2018.  DOI: [10.1145/3332305.3332318](https://doi.org/10.1145/3332305.3332318)
- [C9] **Fei Liu**, Arnaud Lelevé, Damien Eberard, Tanneguy Redarce. An Energy Based Approach for Passive Dual-user Haptic Training Systems. *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, Oct. 2016.  DOI: [10.1109/IROS.2016.7759771](https://doi.org/10.1109/IROS.2016.7759771)
- [C10] **Fei Liu**, Arnaud Lelevé, Damien Eberard, Tanneguy Redarce. A Dual-user Teleoperation System with Online Authority Adjustment for Haptic Training. *37th Annual International Conference of the IEEE Engineering in Medicine and Biology Society (EMBC)*, Aug. 2015.  DOI: [10.1109/EMBC.2015.7318574](https://doi.org/10.1109/EMBC.2015.7318574)
- [C11] **Fei Liu**, Arnaud Lelevé, Damien Eberard, Tanneguy Redarce. A Dual-user Teleoperation System with Adaptive Authority Adjustment for Haptic Training. *4th International Workshop on Medical and Service Robots*, Jul. 2015.  DOI: https://doi.org/10.1007/978-3-319-30674-2_13
- [C12] **Fei Liu**, Yinan Sang, Jie He, Jie Fan, Ruichao Li, Xiongyi Cui, Haoyu Li, Jie Chen. Northwestern Polytechnical University Team Entry for the 2012 AUVSI International Aerial Robotics Competition. *International Aerial Robotics Competition (IARC) Symposium*, Aug. 2012.  [Paper Link](#)
- [C13] **Fei Liu**, Haoyu Li, Li Li. Modeling of the Snowboard Course, International Mathematical Contest in Modeling (MCM) Symposium, Apri. 2011

Selected Patents (part of)

- [P1] **Fei Liu**, Michael C. Yip, Florian Richter. Real-to-Simulation Matching of Deformable Soft Tissue and Other Objectss with Position-based Dynamics for Robot Control.  [PCT/US22/22820](#). 2022. *Submitted for application*.
- [P2] Jialin Yang, Qinghao Hu, Jianxiao Chen, **Fei Liu**, Fei Long. Flexible Mechanical Arm and Surgical Equipment.  [CN 215651505 U](#). 2021. *Active*.
- [P3] Jialin Yang, Qinghao Hu, Jianxiao Chen, **Fei Liu**, Fei Long, Luchen Shen, Liyang Lin. Main Hand Control Unit and Auxiliary Robot for Digestive Tract Operation.  [CN 216603056 U](#). 2021. *Active*.
- [P4] Jialin Yang, Qinghao Hu, Jianxiao Chen, **Fei Liu**, Fei Long, Luchen Shen, Liyang Lin. Main Operator and Force Feedback Device.  [CN 215273291 U](#). 2021. *Active*.
- [P5] Jialin Yang, Qinghao Hu, Jianxiao Chen, **Fei Liu**, Fei Long, Luchen Shen, Liyang Lin. Operation Executor.  [CN 114129228 A](#). 2021.
- [P6] Jialin Yang, Qinghao Hu, Jianxiao Chen, **Fei Liu**, Fei Long, Luchen Shen, Liyang Lin. Operation Executor.  [CN 114176660 A](#). 2021.
- [P7] Junjie Gao, **Fei Liu**, Shunzheng Meng, Sihao Zuo, Jialin Yang. A Kind of Flexible Joint Mechanism.  [CN 209713128 U](#). 2018. *Active*.
- [P8] Jialin Yang, Xilong Hou, Lijuan Yao, **Fei Liu**. Lifting Operation Instrument.  [CN 209574762 U](#). 2018. *Active*.

Research Experience

Advanced Robotics and Controls Lab, UCSD

Dec. 2019 – present

PostDoc,  [ARCLab](#)

San Diego, CA, USA

- Develop for the unified modeling, simulation, and control of deformable, rigid, articulated, fluid object using position-based dynamics (PBD), in particular for articulated manipulation (impedance control, trajectory optimization, rope shape control etc) and surgical applications (soft tissue, membrane, blood and tools).
- Differentiability for the PBD simulation using adjoint method based on chain-rule and Autodiff tools.
- Simulation framework using NVIDIA-Flex, PBD, and self-written constrained based solver.
- Real-to-sim transfer techniques using non-rigid perception, registration, and tracking.
- Closed-loop controller design, motion planning and validation using field robots, such as da Vinci Reseach Kit (DVRK), 7-dof Baxter Robotic Arm, 7-dof Franka Panda Arm, a catheter robot, a non-holonomic mobile robot, a hydraulic-driven underwater robotic arm, haptic device etc.
- **Continuum Robot Project:** Shape reconstruction using projection of geometrical primitives (cylinders, circles etc.), differentiable rendering and perform visual servoing control.

Biorobotics Institute, Scuola Superiore Sant'Anna

Apr. 2019 – Nov. 2019


Researcher,  [Assistive Robotics Lab](#)

Pisa, Italy

- Simultaneous localization and mapping (SLAM) of mobile robotic platform under ROS.
- Autonomous initialization through computer vision approaches using aruco markers (QR codes).
- Autonomous navigation of the mobile robot including path planning, obstacle avoidance.
- Shared control theory development and implementation of the mobile platform.
- Design of PHP/HTML-based web user interface.
- Experimental tests in Verona, Italy.

Center for Micro-BioRobotics IIT@SSSA

Mar. 2018 – Apr. 2019


PostDoc,  [Istituto Italiano di Tecnologia](#)

Pisa, Italy
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- Modeling and control KUKA LWR4+ robotic arm using ROS and Gazebo : motion control, trajectory planning, master-slave
- Modeling and control of flexible continuum surgical tool : static tension-deflection model, Euler-Lagrange dynamics, port-Hamiltonian based control.
- Analysis of several continuum structure prototypes : variation of design (notches, single-backbone, articulated).
- Develop teleoperation framework using haptic devices (Sigma.7).
- Preliminary study of simulation platform for flexible surgical tools using SOFA ([!\[\]\(83eb2aa26b610eb6a9dca7cf4702d681_img.jpg\) Simulation Open Framework Architecture](#)).

Control Engineer & Project Director

Oct. 2016 – Feb. 2018

 ROBO Medical Technology Co., Ltd

Shenzhen, China

- Develop teleoperation of a single-port abdominal robotics surgical system using haptic devices (i.e., PHANTOM Omni, Novint Falcon, Omega.3) and joysticks (i.e., Logitech G Extreme 3D, Microsoft Xbox).
- Modeling and control of a tendon-driven articulated end-effector : kinematics, motion control, master-slave.
- Model-based uncertainties identification and compensation : hysteresis, friction.
- Modeling and control of a 4 DOFs positioning arm (parallel mechanisms) : kinematics, motion control, master-slave.
- Calculation of the RCM point of positioning arm.
- Modeling and control (based on gait analysis) of a powered lower limb orthosis for rehabilitation.
- SLAM algorithm (build on ROS) of autonomous mobile robots for medical transportation in hospitals.

PHD Thesis : Dual-user Haptic Training System

Sep. 2012 – Sep. 2016

Advisors: Prof. Tanneguy Redarce, Prof. Arnaud Lelevé, Dr. Damien Eberard

INSA de Lyon, France

- Focused on modeling and control aspects with/without time delays.
- Developed real-time experiments both with Matlab/Simulink, ROS and Chai3D.
- Published three international conference papers, and one journal paper.

Group Leader : DJI RoboMasters Mobile Manipulation Challenge

Aug. 2014

Design of Autonomous Mobile Robot Using SLAM and Computer Vision Approach.

Shenzhen, China

 Dajiang Innovations Technology Co., Ltd (DJI)

- Developed SLAM framework for mobile robots (chariots) u on ROS.
- Implemented fast on-board object tracking and recognition algorithms.
- Developed multi-robot coordination and searching algorithms.

Master Thesis : Cooperative Haptic Hands-on MIS Trainer

Sep. 2012 – Aug. 2013

Master Internship at Ampère Laboratory

INSA de Lyon, France

- Designed teleoperation system using port-Hamiltonian approach.
- Implemented control algorithms with haptic devices (PHANTOM Omni).
- Developed real-time experiments using Matlab/Simulink.

Team Leader : International Aerial Robotics Competition (IARC)

Aug. 2012

A Low Cost Autonomous Quadrotor UAV-Icarus

Peking, China

- Mathematical modeling of a self-made low cost laser rangefinder based on geometric calculation for environment mapping.
- Autonomous control of the quadrotor using environment mapping and detection algorithm (wall and window detection using point cloud analysis).
- Awarded **Innovative Design**.

Undergraduate Internship <i>Image Meta-data Feature Extraction for Content-Context Based Image Retrieval</i> <ul style="list-style-type: none"> Implemented image processing and classification algorithms. 	Sep. 2011 – Jun. 2012 <i>NPU, Xi'an, China</i>
Team Leader : International Mathematical Contest in Modeling (MCM) <i>Optimal Design of U-shaped Snowboard Course</i> <ul style="list-style-type: none"> Awarded Meritorious Winner (First Prize Mention). 	Feb. 2012 <i>NPU, Xi'an, China</i>
Team Leader : Robocup 3D Simulation Group <i>Robocup Soccer Center of NPU, Simulation Robots of Robocup Soccer</i> <ul style="list-style-type: none"> Designed gait algorithm of NAO (Humanoid) robot. Developed control strategies for simulated soccer competition under linux platform. Awarded Third Prize in China Open 2011. 	Sep. 2010 – Jun. 2012 <i>NPU, Xi'an, China</i>
Project Leader : Student Project of Chinese Ministry of Education <i>Mining Methods for Gene Expression Profile Classification</i> <ul style="list-style-type: none"> Implemented statistical and computing algorithms related to data mining. 	Nov. 2011 – Jun. 2012 <i>NPU, Xi'an, China</i>
Project Leader : Student Project of Chinese Ministry of Education <i>Path Planning of Mobile Robot</i> <ul style="list-style-type: none"> Implemented path planning algorithms of mobile robot (A^*, genetic algorithm, fuzzy control etc. 	Nov. 2010 – Jun. 2011 <i>NPU, Xi'an, China</i>
“Freescale Cup” National Smart Car Design Competition <i>Design and Control of an Intelligent Car for Path Following</i> <ul style="list-style-type: none"> Awarded Third Prize in NPU Open 2011. 	Dec. 2010 – May. 2011 <i>NPU, Xi'an, China</i>
Research Assistant : Laboratory Project <i>Navigation of Unmanned Aerial Vehicle (UAV) Based on Digital Map</i> <ul style="list-style-type: none"> Supervisor: Prof. Suilao Li, College of Automation, NPU 	Sep. 2010 – Jun. 2011 <i>NPU, Xi'an, China</i>
Research Assistant : Laboratory Project <i>Design of Intelligent Vehicle and Autonomous Navigation</i> <ul style="list-style-type: none"> Supervisor: Prof. Suilao Li, College of Automation, NPU 	Sep. 2009 – Jun. 2010 <i>NPU, Xi'an, China</i>

Professional Activities

Journal/Conference Reviewer <ul style="list-style-type: none"> <i>IEEE Transactions on Robotics (T-RO)</i> <i>IEEE Transactions on Mechatronics (T-MECH)</i> <i>IEEE Robotics and Automation Letters (RAL)</i> <i>IEEE Transactions on Medical Robotics and Bionics</i> <i>Control Engineering Practice</i> <i>Robotica</i> <i>Journal of Mechanisms and Robotics (JMR)</i> <i>International Conference on Robotics and Automation (ICRA)</i> <i>American Control Conference (ACC)</i> <i>International Conference on Learning Representations (ICLR)</i> 	2016 – present
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- *IFAC Workshop on Lagrangian and Hamiltonian Methods for Nonlinear Control (LHMNC)*
- *IEEE RAS/EMBS Conference on Biomedical Robotics and Biomechatronics (BioRob)*

Poster Presentation

2015 – 2021

- *Emerging Frontiers in Research and Innovation (EFRI) All-Teams Workshop, Virtual, USA.*
- *37th Annual International Conference of the IEEE Engineering in Medicine and Biology Society (EMBS), Milano, Italy.*

Oral Presentation

2015 – 2021

- *2021 International Conference on Robotics and Automation, Virtual, Xi'an, China.*
- *7th Summer School on Surgical Robotics (SSSR 2015), Montpellier, France.*
- *37th EMBS Ignite Sessions, Milano, Italy.*
- *4th International Workshop on Medical and Service Robots (MESROB), Nantes, France.*

Volunteer

- *20th World Olympic Collectors Fair, Lausanne, Switzerland. May. 2014*
- *Heart++ : High School Student Course Assistance, Xi'an, Northwestern Polytechnical University. 2018-2012*


Membership

2015 – 2021

- **IEEE Membership** 2017 – present
- **IEEE Student Membership.** 2015 – 2016
- **EMBS Membership.** 2015 – 2016

Supervision Activities

PhD Students

 **Yu Huan** : *currently senior engineer at United-Imaging Healthcare Co., Ltd., Shanghai*
Mar. 2018 – Mar. 2019, Scuola Superiore Sant'Anna

- Topic : Design and control of flexible miniature surgical tools (continuum robot).

Master Students

Awies Mohammad Mulla : *currently first-year master student at UCSD*

Sep. 2022 – present, Department of Electrical and Computer Engineering (ECE), UCSD

- Topic : Tool-tissue interaction modeling of position-based dynamics with Incremental Potential Contact (IPC).

Xiao Liang : *currently second-year master student at UCSD*

Sep. 2021 – present, Department of Computer Science Engineering (CSE), UCSD

- Topic : Reconstruction of 4D lung motion using neural-ODE integration.

 **Junming Wu** : *currently second-year master student at UCSD*


Sep. 2021 – present, Department of ECE, UCSD

- Topic : Bi-manual close-loop control of dual-arm suturing using physical-based simulation.

Chong He : *currently second-year master student at UCSD*

Sep. 2021 – Aug. 2022, Department of Mechanical and Aerospace Engineering (MAE), UCSD

- Topic : Shape reconstruction of catheter robot using monocular images.

 **Yunhai Han** : *currently first-year PhD student at Georgia Institute of Technology*


Jan. 2021 – Jan. 2022, Department of MAE, UCSD

- Topic : Simulation framework using position-based dynamics using self-written constraints based solver.

Mingen Li : *currently first-year PhD student at University of Minnesota, Twin Cities*

Jan. 2021 – Jan. 2022, Department of ECE, UCSD

- Topic : Simulation and control of articulated rigid body robots using position-based dynamics.

 **Entong Su** : *currently second-year master student at UCSD*


Jan. 2021 – Jan. 2022, Department of ECE, UCSD

- Topic : Simulation of rope-like object using position-based dynamics for shape control.

 **Harleen Singh** : *currently medical device engineer 2 at Dexcom Inc.*

Jan. 2020 – Jul. 2021, Department of ECE, UCSD

- Topic : Modeling of the catheter continuum robot for position and orientation motor control.

 **Zihan Li** : *currently software algorithm engineer at OmniVision Technologies, Inc.*

Jan. 2020 – Nov. 2020, Department of ECE, UCSD

- Topic : Registration method for real-to-sim transfer applications of deformable tissue manipulation.

 **Jingbin Huang**

Mar. 2020 – Nov. 2020, Department of ECE, UCSD


- Topic : Modeling and control of surgical tool for suction based simulation of blood fluid.

 **Sean Liu** : *currently lead engineer at Hyperspec.ai*

Jun. 2020 – Sep. 2020, Department of ECE, UCSD

- Topic : Reconstruction of a catheter robot shape using projection of geometrical primitives.

Undergraduate Student

 **Neelay Joglekar** : *currently third-year undergraduate student at UCSD*

Jan. 2021 – present, Department of ECE, UCSD

- Topic : Dynamic model of rope-like objects using cosserat rod theory and surgical thread reconstruction.

 **Yutong Zhang** : *currently first-year master student at UCSD*


Jan. 2021 – present, Department of Computer Science, UCSD

- Topic : Simulation platform using libIGL/openGL rendering and visualization for various objects, i.e., rigid, articulated robots, deformable, fluid etc.

 **Zhiyi Yuan** : *currently software engineer at Qualcomm Inc.*

Jan. 2021 – May 2022, Department of ECE, UCSD


- Topic : Coding of the gradients computed for position-based dynamics constraints.

 **Nemanja Babic** : *currently senior engineer at Hypertherm Associates Inc.*

May. 2015 – Aug. 2015, Research Internship, University of Ottawa & INSA de Lyon

- Topic : Simulation of haptic systems using CHAI3D.

High School Student

 **Ayaan Haque** : *currently first year undergraduate student at UC Berkeley*

Jan. 2021 – Jul. 2021, Saratoga High School, California

- Topic : Simulated Data Generation Through Algorithmic Force Coefficient Estimation.

 **Sajiv Shah** : *currently a mechanical engineer at Whisper Aero*

Jan. 2021 – Jul. 2021, Saratoga High School, California

- Topic : Simulated Data Generation Through Algorithmic Force Coefficient Estimation.

Supported Grants

CAREER: Contextually Informed Autonomous Robotic Surgery

Mar. 2021 – Present, *National Science Foundation (NSF)*

Grant No. : 2045803/PI: Prof. Michael Yip

Role : Postdoc Researcher

- Topic : Modeling and simulation of soft tissue deformation and interactive robotic tool control.

EFRI C3 SoRo: Safe Medical Continuum Robots: Sensing, Control and Fabrication

Nov. 2019 – Present, *National Science Foundation (NSF)*

Grant No. : 1935329/PI: Prof. Michael Yip

Role : Postdoc Researcher

- Topic : Shape reconstruction of catheter robots using endoscopic images and visual-servoing control.

Special Foundation for Intelligent Robots: Creation and Kinematic Model of Modular Variable Stiffness Continuum Flexible Actuator

Mar. 2019 – Nov. 2019, *Ministry of Science and Technology (MOST) of China*

Grant No. : 2018YFB1307700/PI: Shenzhen Robo Medical Technology CO Ltd

Role : Project Leader

- Topic : Modeling and control of a continuum flexible ESD robot using curvature-based model.

Honors and Awards

Individual Awards

2012 **Innovative Design Award** at International Aerial Robotics Competition (IARC)

2012 **First Prize** at International Mathematical Contest in Modeling (MCM)

2011 **Third Prize** in Robocup China Open 2011

2008-2012 **Yearly Distinguished Student Scholarship** of Northwestern Polytechnical University

Paper Awards

2021 Nominated for **Best Paper** at IEEE International Conference on Robotics and Automation (ICRA)

Research Techniques and Relevant Skills

Computer Languages: Python, C++, C, MATLAB/Simulink, PHP

Software Skill: PyTorch, Linux, LaTeX, ROS, Gazebo, MoveIt, Chai3D, SOFA, OpenCV, Open3D, NLopt, OSQP etc..

Hardware Experiences: da Vinci Research Kit (DVRK), 7-DOF Baxter Robotic Arm, KUKA LWR 4+, NDI Electromagnetic Sensor/Aurora, Phantom Omni, Omega.3 & Sigma.7 (Force Dimension), Novint Falcon, MAXON Motors, EPOS Drivers, SICK Laser Range-finder, IMU sensors, etc..

Languages

Chinese: Native

English: Advanced

French: Intermediate B1

Italian: Beginner