

Mengyu FU

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EDUCATION

University of North Carolina at Chapel Hill, NC

Aug. 2017 - Mar. 2022

Ph.D. in Computer Science

Harbin Institute of Technology, Harbin, China

Sep. 2011 - Jul. 2015, Sep. 2015 - Jul. 2017

M.Eng. in Control Science and Engineering

GPA 95.49%, rank 1/182

B.Eng. in Automation, Honors School (top 5%)

GPA 94.43%, rank 2/192

EXPERIENCES

Software Engineer, Google

Mountain View, CA

Team: YouTube Shorts Discovery

June 2022 - present

Develop the recommendation system for short videos, focusing on video ranking and packing.

Graduate Research Assistant, Computational Robotics Research Group

Chapel Hill, NC

Advisor: Prof. Ron Alterovitz

2017 - 2022

Thesis: Efficient Motion and Inspection Planning for Medical Robots with Theoretical Guarantees

Designed and implemented robot **motion planning** and **inspection planning** algorithms with theoretical guarantees for surgical robots (**C++** and **templates**). These algorithms allow the robots to successfully navigate around complex environments or patient anatomy using multimodal sensor data. Experimented with both simulation and physical robot systems (**ROS**, medical-image segmentation, registration). Played major role in writing an NSF-funded proposal.

Journal and Conference Reviewer: TRO, RAL, IROS 2019-2022, ICRA 2019-2022, ISER 2018

Machine Learning Intern, Nuro Inc.

Mountain View, CA

Manager: Wei Liu, Qiuyu Peng

Summer 2021, Summer 2020, Summer 2019

Applied deep learning techniques (**C++**, **Python**, **TensorFlow**, **GCP**, **k8s**) to solve problems related to autonomous vehicles, focused on **behavior prediction** and **ego-vehicle planning**.

Graduate Research Assistant, Space Control and Inertial Technology Center

Harbin, China

Advisor: Prof. Changhong Wang and Prof. Zhenshen Qu

2015 - 2017

Master thesis: deep-learning-based video action recognition (**Caffe**).

Bachelor thesis (outstanding thesis, top 2%): semi-physical simulation system with vision & IMU data fusion (**LabVIEW**).

Undergrad Research Assistant, Research Institute of Intelligent Control and System

Harbin, China

Advisor: Prof. Huijun Gao

2014 - 2015

Studied data-driven classification and fault diagnosis based on Support Vector Machines (SVMs).

SKILLS

Languages & Operating systems

C++ (Advanced), Python, C, and Java. Linux and macOS.

Tools

TensorFlow, Google Cloud Platform (GCP), Kubernetes (k8s), MATLAB (& Simulink), CMake, Robot Operating System (ROS), Caffe, LabVIEW, Git, Vim, and \LaTeX .

Libraries

The Open Motion Planning Library (OMPL), OpenCV, Flexible Collision Library (FCL), and Insight Toolkit (ITK).

AWARDS

Best Paper Finalist, Robotics: Science and Systems (RSS)

2021

Best Student Paper Finalist, ASME Dynamic Systems and Control Conference (DSCC)

2020

First Class Scholarship, China Aerospace Science and Technology Corporation

2016

Outstanding Undergraduate Thesis (top 2%), Harbin Institute of Technology

2015

National Scholarship (top 1.5%), Ministry of Education of China

2012-2013, 2013-2014

PUBLICATIONS

- [18] A. Kuntz, M. Emerson, T. E. Ertop, I. Fried, **M. Fu**, J. Hoelscher, M. Rox, J. Akulian, E. A. Gillaspie, Y. Z. Lee, F. Maldonado, R. J. Webster, and R. Alterovitz. “Autonomous Medical Needle Steering In Vivo.” (**Under review**)
- [17] **M. Fu**, K. Solovey, O. Salzman, and R. Alterovitz. “Toward Certifiable and Optimal Motion Planning for Medical Steerable Needles.” accepted by *The International Journal of Robotics Research (IJRR)* (**Accepted**)
- [16] **M. Fu**, A. Kuntz, O. Salzman, and R. Alterovitz. “Asymptotically-optimal inspection planning via efficient near-optimal search on sampled roadmaps.” accepted by *The International Journal of Robotics Research (IJRR)* (**Accepted**)
- [15] J. Hoelscher, I. Fried, **M. Fu**, M. Patwardhan, M. Christman, J. Akulian, R. J. Webster, and R. Alterovitz. “A Metric for Finding Robust Start Positions for Medical Steerable Needle Automation.” in *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, pp. 9526-9533, Kyoto, Japan, October 2022.
- [14] **M. Fu**, K. Solovey, O. Salzman, and R. Alterovitz. “Resolution-Optimal Motion Planning for Steerable Needles.” in *IEEE/RSJ Int. Conf. on Robotics and Automation (ICRA)*, pp. 9652-9659, Philadelphia, US, May 2022.
- [13] **M. Fu**, O. Salzman, and R. Alterovitz. “Toward Certifiable Motion Planning for Medical Steerable Needles.” in *Robotics: Science and Systems (RSS)*, held virtually, July 2021. [**Best Paper Finalist**]
- [12] **M. Fu**, O. Salzman, and R. Alterovitz. “Computationally-Efficient Roadmap-based Inspection Planning via Incremental Lazy Search.” in *IEEE/RSJ Int. Conf. on Robotics and Automation (ICRA)*, pp. 7449-7456, Xian, CN, May 2021.
- [11] I. Fried, J. Hoelscher, **M. Fu**, M. Emerson, T. Efe Ertop, M. Rox, J. Granna, A. Kuntz, J. A. Akulian, R. J. Webster III, and R. Alterovitz. “Design Considerations for a Steerable Needle Robot to Maximize Reachable Lung Volume.” in *IEEE/RSJ Int. Conf. on Robotics and Automation (ICRA)*, pp. 1418-1425, Xian, CN, May 2021.
- [10] J. Hoelscher, **M. Fu**, I. Fried, M. Emerson, T. Efe Ertop, M. Rox, A. Kuntz, J. A. Akulian, R. J. Webster III, and R. Alterovitz. “Backward Planning for a Multi-Stage Steerable Needle Lung Robot.” in *IEEE Robotics and Automation Letters (RAL)*, vol. 6, no. 2, pp. 3987-3994, April 2021.
- [9] M. Rox, M. Emerson, T. Efe Ertop, I. Fried, **M. Fu**, J. Hoelscher, A. Kuntz, J. Granna, J. Mitchell, M. Lester, F. Maldonado, E. A. Gillaspie, J. Akulian, R. Alterovitz, and R. J. Webster III. “Decoupling Steerability from Diameter: Helical Dovetail Laser Patterning for Steerable Needles.” in *IEEE Access* 8 (2020): 181411-181419.
- [8] T. Efe Ertop, M. Emerson, M. Rox, J. Granna, F. Maldonado, E. Gillaspie, M. Lester, A. Kuntz, C. Rucker, **M. Fu**, J. Hoelscher, I. Fried, R. Alterovitz, and R. J. Webster III. “Steerable Needle Trajectory Following In The Lung: Torsional Deadband Compensation And Full Pose Estimation With 5DOF Feedback For Needles Passing Through Flexible Endoscopes.” in *ASME Dynamic Systems and Control Conference (DSCC)*, held virtually, October 2020. [**Best student paper finalist**]
- [7] A. Kuntz, **M. Fu**, et al. “Planning High-Quality Motions for Concentric Tube Robots in Point Clouds via Parallel Sampling and Optimization.” in *IEEE/RSJ Int. Conf. on Intelligent Robots and Systems (IROS)*, pp. 2205-2212, Macau, CN, November 2019.
- [6] **M. Fu**, A. Kuntz, O. Salzman, and R. Alterovitz. “Toward Asymptotically-Optimal Inspection Planning via Efficient Near-Optimal Graph Search.” in *Robotics: Science and Systems (RSS)*, Freiburg im Breisgau, DE, June 2019.
- [5] **M. Fu**, A. Kuntz, R. J. Webster III, and R. Alterovitz. “Safe Motion Planning for Steerable Needles using Cost Maps Automatically Extracted from Pulmonary Images.” in *IEEE/RSJ Int. Conf. on Intelligent Robots and Systems (IROS)*, pp. 4942-4949, Madrid, ES, October 2018.
- [4] Z. Qu, S. Yu, and **M. Fu**. “Motion Background Modeling Based on Context-Encoder.” in *International Conference on Artificial Intelligence and Pattern Recognition (AIPR)*, pp. 32-36, Lodz, PL, September 2016.
- [3] Z. Qu, X. Chu, **M. Fu**, X. Liu, W. Xie, and C. Wang. “Design of Real-Time Measurement System with Vision/IMU for Close-Range Semi-Physical Rendezvous and Docking Simulation.” in *IEEE Chinese Guidance, Navigation and Control Conference (CGNCC)*, pp. 2292-2298, Nanjing, CN, August 2016.
- [2] **M. Fu**, Y. Tian, and F. Wu. “Step-Wise Support Vector Machines for Classification of Overlapping Samples.” in *Neurocomputing*, Vol 155, pp. 159-166, May 2015.
- [1] Y. Tian, **M. Fu**, and F. Wu. “Steel Plates Fault Diagnosis on The Basis of Support Vector Machines.” in *Neurocomputing* Vol 151, pp. 296-303, March 2015.