

# Patrick Li-Yu Lo

134B, North Building  
Research Dr, Durham NC



<https://pattylo.github.io/>

## EDUCATION

**Duke University**  
PhD Student (MEMS)

*Present*

**The Hong Kong Polytechnic University**  
MPhil in Robotics & Control (Presidential Fellow)

*Mar 2025*  
GPA: 4.0/4.3

**The Hong Kong Polytechnic University**  
BEng (1st Hons) in Aeronautical and Aviation Engineering (APEC Entry Scholarship)  
Exchange: University of Queensland, Australia

*Jun 2021*  
GPA: 3.75/4.3

## RESEARCH EXPERIENCE (SLIDES)

**Adaptive Control for Underactuated Robots leveraging Koopman Operators and Reinforcement Learning for Dynamic Robustness**  
*Sep 2024 - Present*

*Research Assistant*

- Designed an adaptive framework to address data insufficiency in Koopman operator-based controllers.
- Developed a policy network for optimizing controller parameters.
- Demonstrating the framework's performance through simulations and physical experiments.

**Improving and Optimizing Adaptive Controllers via Disturbances Observers and Reinforcement Learning**  
*Aug 2023 - Aug 2024*

*MPhil Student*

- Proposed an adaptive framework for MPC, LQR, and EKF on mobile robots using disturbance observation.
- Improved, analyzed, and implemented General ESO (GESO) and Error-State ESO (ESES0) for lump disturbance estimation.
- Developed reinforcement learning (RL) for parameter optimization.
- Demonstrated performance on UUV MPC control, heterogeneous UAV-UGV relative state estimation, and multi-UAV sliding-mode control (SMC).

**Non-Robocentric Dynamic Landing for Quadrotor UAVs**

*Sep 2022 - Jul 2023*

*MPhil Student*

- Proposed a non-inertial autonomous dynamic landing framework without using airborne exteroceptive sensors.
- Developed an IEKF-based state estimator on SE(3).
- Designed kinematic and dynamic constrained trajectories using differential flatness and minimized jerk.
- Demonstrated system applicability via physical experiments using a self-designed UAV-UGV hardware system.

## WORK EXPERIENCE

**Hong Kong Center for Construction Robotics (HKCRC)**

*Jul 2021 - Jul 2022*

*Research Assistant*

- Developed a learning-based model via adversarial training and data augmentation for a CV-based construction logistics monitoring system.
- Developed PID controllers and EKF estimators for an automation system aiding prefabrication component installation, currently pending patent.

## PUBLICATIONS & PATENTS

- **L.-Y. Lo**, B. Li, C.-Y. Wen, and C.-W. Chang, "Experimental Non-Robocentric Dynamic Landing of Quadrotor UAVs with On-Ground Sensor Suite," *IEEE Transactions on Instrumentation and Measurement (TIM)*, vol. 73, 2024. *Links: [pdf](#), [code](#).*
- **L.-Y. Lo**, Y. Hu, B. Li, C.-Y. Wen, and Y. Yang, "An Adaptive Model Predictive Control for Unmanned Underwater Vehicles Subject to External Disturbances and Measurement Noise," in *2024 14th Asian Control Conference (ASCC)*. IEEE, 2024, pp. 01–07. *Links: [pdf](#), [code](#).*
- Y. Yang, K. Liu, **L.-Y. Lo**, T. Huang, Y. Fu, and C.-Y. Wen, "Fixed-Time Adaptive Consensus Control for

Multi-Quadrotor Subject to External Disturbances via Deep Reinforcement Learning,” submitted to *IEEE Transactions on Automation and Science Engineering (TASE)*, 2024.

- W. Yang, Z. Tan, Y. Xue, **L.-Y. Lo**, K. Liu, and C.-Y. Wen, “Hierarchical 3D Scene Graph Based Metric Semantic SLAM for Object Mapping and Counting,” submitted to *IEEE Transactions on Circuits and Systems II: Express Briefs*, 2024.
- **L.-Y. Lo**, B. Li, C.-Y. Wen, and C.-W. Chang, “Landing a Quadrotor on a Ground Vehicle Without Exteroceptive Airborne Sensors: A Non-Robocentric Framework and Implementation,” in *2023 IEEE 26th International Conference on Intelligent Transportation Systems (ITSC)*. IEEE, 2023, pp. 6080–6087. *Links: pdf*.
- C.-W. Chang, L.K. Chung, W.-C. Hung, and **L.-Y. Lo**, “An Integrated Auxiliary System for Construction Precast Components Installation,” Patent Pending, Application No.: 202310478194.5, *CN Patent*, [Filing Date: 2023-08-29].
- **L.-Y. Lo**, C. H. Yiu, Y. Tang, A.-S. Yang, B. Li, and C.-Y. Wen, “Dynamic Object Tracking on Autonomous UAV System for Surveillance Applications,” *Sensors*, vol. 21, no. 23, p. 7888, 2021. Editor’s Choice Article. *Links: pdf, code*.

---

## AWARDS & SCHOLARSHIP

- First Runner-up of UAV Challenge, 2023 & 2024 IEEE International Conference on Unmanned Aircraft Systems (ICUAS). *Links: web 2023, web 2024*.
- PolyU Presidential Postgraduate Fellowship Scheme (’22 - ’24).
- Dean’s List of PolyU Faculty of Engineering: ’17/18, ’18/19 & ’20/21.
- PolyU Undergraduate APEC Entry Scholarship (’17 - ’21).
- Wong Tit-shing Student Exchange Scholarship 2019/20.
- Dr. Y.K. Ching Memorial Scholarship.

---

## CORE SKILLS & EXPERIENCES

**Languages & Tools:** C++, Python, ROS, Matlab, Docker, PX4 Firmware, PyTorch, & OpenCV.

**Robotic Subjects:** Dynamic Analysis with Data, Optimal Control, Nonlinear Control Theory, Convex Optimization, Deep Learning, Reinforcement Learning, Optimization-based SLAM.

**Robotic Platforms:** AgileX Scout-Mini, Holybro Pixhawk 4 Mini, Holybro Kakute H7, BlueROV2, Unitree GO1.

**Links:** [Project Pages](#), [Learning Notes](#).

---

## OTHERS

- **Languages:** English (IELTS 7.5), Mandarin (Native), Cantonese (Proficient), Taiwanese (Proficient).
- **Services:** Reviewer for IEEE Transactions on Instrumentation and Measurement; IEEE Transactions on Mechatronics; IEEE Transactions on Vehicular Technology; IEEE Sensors Journal; 2023 IEEE International Conference on Intelligent Transportation Systems.
- **Volunteering:** Student Ambassador at HKPolyU (’19-’21); Teaching Assistant at HeartFire Education Service, China (Dec ’19), African Evangelistic Enterprise, Rwanda (Jun ’19), Royal University of Phnom Penh, Cambodia (May - Jun ’18).

---

## REFERENCES

Prof. Chih-Yung Wen	Dr. Boyang Li	Dr. Li-Ta Hsu	Dr. Ching-Wei Chang
(+852) 3400 2522	(+61) 02 4055 0828	(+852) 3400 8061	(+852) 6996 1656
cywen@polyu.edu.hk	boyang.li@newcastle.edu.au	lt.hsu@polyu.edu.hk	ccw@ust.hk