

# Yufeng Liu | Curriculum Vitae

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## Education

**Harbin Institute of Technology (Shenzhen)**  
*B.Eng. in Automation GPA:87/100 IELTS 6.5*

**Shenzhen, China**  
*Sept.2020–Jun.2024*

**Nanyang Technological University**  
*M.Sc. in Computer Control and Automation*

**Singapore**  
*Aug.2024–present*

## Experience

**Multi sensor SLAM in complex environments.**

**nROS-Lab, HITsz**  
*Oct.2021–Jun.2024*

- Participated in the implementation and experiment of an Edge-Based Monocular Thermal-Inertial Odometry [publication].
  - Developed a simulation system in Ignition Gazebo for SLAM in complex extreme environments.
  - Deployed the algorithm in the real world and conducted experiments in the real world and datasets.
  - Skilled in thermal image processing.
  - Familiar with the system framework of VIOs like VINS-Mono, ORB-SLAM3, etc.
- Proposed a SLAM framework that fuses thermal camera, LiDAR, and IMU.
  - Designed a novel multi-sensor SLAM framework specially designed for sensor-degraded scenes.
  - Skilled in multi-sensor calibration.
  - Skilled in approaches to perform multi-sensor time synchronization.
  - Familiar with common multi-sensor SLAM frameworks like LVI-SAM, R2Live, R3Live, FAST-LIVO, etc.
  - (This project is my Final Year Project & Dissertation, which won the HITsz Outstanding Final Year Project & Dissertation Award)
  - (Related journal publication is expected to be released in the near future.)
- Participated in the implementation of a SLAM system integrated planning and dynamic obstacle avoidance.
  - Applied deep-learning method for target detection to optimize the LiDAR odometry.
  - Designed shared memory method for pointcloud data acceleration.

**Teleoperated robot equipped with a VR remote-controlled gimbal system.**

**nROS-Lab, HITsz**  
*Oct.2022–Sept.2023*

- Designed a two-axis gimbal with sensors for mobile robots:
  - Designed the 3D model and implemented real-time embedded control.
  - Developed a framework for human-computer interaction, as well as a VR application.
  - Deployed Multi-sensor SLAM algorithm on the gimbal.

**Team leader of Sentry Robot Group in RoboMaster competition**

**Critical-HIT robot team, HITsz**  
*Oct.2020–Aug.2022*

- Led the Sentry Robot Group in HITsz Critical-HIT RoboMaster Team.
  - Designed a fully automatic inspection and combat-integrated robot.
  - Coordinated task allocation and fostered collaboration among team members as team leader.
  - Responsible for embedded.
  - Developed target aiming algorithm framework, including target detection tracking.

**Underwater grab robot control and navigation**

**Lujian Technology Ltd. Co., Shenzhen**  
*May.2022–Dec.2022*

- Participated in the design of an underwater robot
- Responsible for visual-inertial odometry and planning in underwater environments.
- Responsible for embedded motion control.
- Achieved a learning-based underwater target detection.

More detailed experiences can be explored at [Website](#).

## Skills

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Programming: C++, C, Python, MATLAB

Software & tools: ROS, OpenCV, Gazebo, PCL, GTSAM, Ceres, Git, PyTorch, LaTeX, Qt Creator, Unity

Hardware: STM32, SolidWorks

## Publications

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[1] Yu Wang, Haoyao Chen, **Yufeng Liu**, and Shiwu Zhang. Edge-based monocular thermal-inertial odometry in visually degraded environments. IEEE Robotics and Automation Letters(RA-L), 8(4):2078-2085, 2023. [\[link\]](#) [\[arxiv\]](#)

## Awards

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|---|------|
| o Outstanding Final Year Project & Dissertation Award - Top2% of HITsz                        | 2024 |
| o First Prize of 2022 RoboMaster University Championship                                      | 2022 |
| o Silver Prize of 13th Challenge Cup  | 2022 |
| o First Prize of 2021 RoboMaster University Championship                                      | 2021 |
| o Third Prize of ChinaUndergraduate Mathematical Contest in Modelling                         | 2021 |
| o First Place among all students of Competition of the HITsz Robot Design and Practice Course | 2020 |