

Richard (Han) Hu

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Experiences

PX Robotics

Jan. 2022 - Present

Senior Machine Learning Engineer, Motion Control Center

- **Innovation** Spearheaded reinforcement learning based biomimetic gait controllers projects by improving on SOTA algorithms. Exceeded SOTA methods on all metrics. Achieving 1.5x better disturbance rejection, doubling maximum velocity, and generalization to unseen rough terrains and tasks. Current have 2 patents pending.
- **Locomotion** Engineered a locomotion controller for quadruped robots by integrating reinforcement learning with model-based control to enhance disturbance rejection. Achieved state of the art disturbance rejection.
- **Process Optimization** Formulated an analytical approach to reinforcement learning training, slashing model iterations by up to 70%.
- **Infrastructure** Revamped the reinforcement learning pipeline using a modular design; led the development of MLOps tools, including cloud model sharing, test automation, and data collection and analysis, reducing manual tasks by 80%.
- **Strategy** Analyzed SOTA machine learning methods for quadruped control, large language models, manipulators, and embodied AI, provides insight on departmental product strategy.

Autonomous System and Biomechatronics Lab

Sep. 2018 - Aug. 2021

Developer, Master Thesis

- **Deep Learning** Led the development and **published** a novel sim-to-real transfer pipeline for rough terrain navigation in Pytorch.
- **Sim-to-Real** Researched, designed, and implemented a high fidelity Gazebo simulator and domain randomization.
- **Development** Developed a decentralized software and hardware robot architecture using ROS, C++, and Python.
- **Localization** Implemented LiDAR and visual SLAM on a mobile robot for real time pose estimation.
- **Control** Designed and optimized a cascade PID controller for global position and wheel control in rough terrain.
- **Analysis** Led real-world navigation, comparison, and ablation experiments to demonstrate that the pipeline achieved 87% real world success rate given a 90% simulation success rate; up to 72% increase against existing methods.
- **Hardware** Enhanced a robot with auxilliary computing units and sensors with components designed using SolidWorks.
- **Publication** Published in 1) IEEE Robotics and Automation Letters 2021 and 2) International Conference on Intelligent Robots and Systems 2021.

Huawei Noah's Ark Lab

May. 2020 - Jan 2021

Developer, Autonomous Driving Division

- **Path Planning** Developed, **published**, and **patented** a Delaunay Triangulation based spatial constraint generation algorithm for mapless autonomous vehicle navigation in a dynamic environment.
- **Development** Implemented a Python based path planning simulator and the algorithm's modules for fast development iterations.
- **Algorithms** Implemented Hybrid A* and Funnel algorithm for path planning in triangulation mesh.
- **Simulation** Engaged in simulator development using CARLA by automating map generation process from real-world datasets.
- **Publications** Published in 1) IROS 2021 Conference and 2) US Patent Application No. 17/515,522.

MIE443 Mechatronics Systems: Design & Integration

Jan. 2018 - Apr. 2020

Head Teaching Assistant

- **Lecture** Lectured 4th year engineering students on ROS based robot navigation and SLAM methods.
- **Mentorship** Guided students on ROS based autonomous robot algorithm development, vision sensor, and OpenCV.
- **Award** Recipient of UofT MIE 2019-20 Teaching Assistant Award.

Water and Energy Research Laboratory

Jan. 2018 - Sep. 2018

Developer, Pico-Scale Hydro Turbine Design

- **Mechanical** Designed and published a variable guide vane for pico-scale hydro turbine using SolidWorks.
- **Analysis** Evaluated the guide vane failure mode with fluid pressure test, mechanical stress test, and finite element analysis.
- **Development** Prototyped the turbine and an experiment pipeline using Arduino, SLA 3D printing and machining techniques.

Conavi Medical

May. 2016 - Aug. 2017

Mechanical Engineer Intern, Novasight Hybrid System

- **Analysis** Investigated potential design hazards and risks of catheter rotary assembly.
- **Manufacturing** Streamlined an efficient assembly and calibration work instruction for intravascular catheter.
- **Organization** Established an inventory system with full traceability for FDA 510k submission validation.
- **Management** Directed technical design reviews with senior leadership, accelerated the exit of the project phase.
- **Mechanical** Designed imaging and rotary assembly for a intravascular catheter using MATLAB and SolidWorks.

Multiphase Flow and Spray Systems Lab

Jun. 2015 - Sep. 2015

Researcher

- **Development** Developed Arduino based camera to fluid pipeline synchronization system to speed up data collection by 85%.
- **Analysis** Classified 13 novel air-fluid impingement shatter pattern using statistical analysis.

Projects

Parallel Proximal Policy Gradient in Pytorch

Nov. 2019

Personal Project

- **Development** Implemented parallel agent for faster experience collection and training for proximal policy gradient in Pytorch

Apprenticeship Learning with Inverse Reinforcement Learning Implementation

Mar. 2019

Developer, Course Project

- **Development** Implemented the Apprenticeship Learning algorithm using traditional Q-Learning algorithm in Python
- **Lecture** Lectured students on the algorithm using a version implemented in Google Colab

aUToronto - SAE AutoDrive Challenge (Winner 2018-19)

Sep. 2018 - Oct. 2019

Planning and Control Team Member, University of Toronto Team

- **Collaboration** Aim to develop a level 4 autonomous vehicle using ROS and C++ in a team of 30+ students
- **Localization** Implemented real-time kinematics GPS using NovAtel's SPAN for centimeter level localization
- **Mapping** Automated the semantic map layer's lane to centerline association process using Python, QGIS, and Open Street Map

Toward Smart Cities: Road Accident Prevention

Sep. 2018 - Dec. 2018

Developer, Course Project

- **Collaboration** Data-driven accident prediction using Scikit-learn in Python; within a team of 5 students
- **Data Engineering** Data collection, visualization, feature engineering, and negative sampling
- **Machine Learning** Trained and benchmarked 3 supervised learning models: Random Forest, SVM, and MLP Network

Autonomous Turtlebot

Jan. 2018 - Sep. 2018

Developer, Course Project

- **Path Planning** Developed robot coverage and exploration algorithm using ROS and C++
- **Computer Vision** Object detection and identification using OpenCV library
- **Control** Implemented person-following and emotional model for human-robot interaction

Autonomous Maze Navigation Rover Design

Sep. 2017 - Dec. 2017

Developer, Course Project

- **Development** Designed the software and hardware architecture for autonomous payload pick-up and delivery robot in a maze
- **Path Planning** Designed and implemented localization, collision avoidance, and path planning algorithm in MATLAB and Arduino

Publications

A Sim-to-Real Pipeline for Deep Reinforcement Learning Autonomous Navigation in Cluttered Rough Terrain

Hu. H, Kaicheng Zhang, Aaron Hao Tan, Michael Ruan, Christopher Agia, and Goldie Nejat

RAL and IROS2021

- Proposed a pipeline to transfer challenging rough terrain navigation policy from simulation to the real-world using high fidelity simulation, abstract observation space, and domain randomization.
- The pipeline achieved a 87% real world navigation success rate given a 90% simulation success rate.
- The pipeline has up to 72% increase in navigation success along with a faster travel time and shorter distance against existing methods.

Spatial Constraint Generation for Motion Planning in Dynamic Environments

Hu. H, Peyman Yadmellat

Patent and IROS2021

- Proposed to generate spatial constraint using triangulation mesh for long-term mapless path planning in a dynamic environment.
- Overcame the static triangulation mesh assumption and the object masking issue that existing methods have.
- Achieved up to 18% increase in navigation success rate and up to 28% increase in valid plans compared to existing methods.
- Patent pending .

Optimization and System Identification of a Variable Pico-Scale Hydro Turbine for Pressure Regulation

Yu. SM, Ko. Y, Hu. H, Seo. J, and Bilton. AM

ASME

- Engaged in the design and prototyping of the turbine and its experiment rig using SolidWorks, machining, and 3D printing.

Education

University of Toronto

Master of Applied Science, Mechanical Engineering

- **Specialization** Deep Reinforcement Learning, Machine Learning, Mobile Robotics; GPA (4.00/4.00)

Toronto, Canada

Sep. 2018 - Aug. 2021

University of Toronto

Bachelor of Applied Science, Mechanical Engineering

- **Specialization** Robotics and Mechatronics Minor; Dean's Honor List for all terms; GPA (3.81/4.00)

Toronto, Canada

Sep. 2013 - Apr. 2018

Honors & Awards

2019-20	MIE Teaching Assistant Award , University of Toronto	<i>Toronto, Ontario</i>
2013-18	Dean's Honor List , University of Toronto	<i>Toronto, Ontario</i>
2018	Best Undergraduate Poster Presentation , CFD Society of Canada Conference	<i>Winnipeg, Manitoba</i>
2015	University of Toronto Excellence Award , University of Toronto	<i>Toronto, Ontario</i>
2015	Shell Canada Limited Engineering Scholarship , University of Toronto	<i>Toronto, Ontario</i>
2015	Best Innovation Award and Best Prototype Award , U of T Engineering Competition Junior Design	<i>Toronto, Ontario</i>