

# ZHEXU LI

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## SUMMARY

After 6 years of rigorous training at UCSD, I have received extensive training and gained practical experience in various aspects of **data science**, including **statistical machine learning, deep learning, cloud computing, data mining**, and **data visualization**. I am thrilled to utilize my skills and expertise to drive innovation and revolutionize industries, paving the way for a brighter future.

## EDUCATION

**Master of Science: Machine Learning and Data Science**, Expected in 06/2023  
University of California - San Diego

**Bachelor of Science: Data Science**, 06/2021  
University of California - San Diego

## SKILLS

- **Python**
- **SQL**
- **Machine Learning:** Scikit-learn
- **Deep Learning:** PyTorch
- **Data Analysis:** Pandas, R, Matlab, Excel, GeoPandas, ArcGIS
- **Cloud Computing:** PySpark, Hadoop, AWS
- **Data Visualization:** JavaScript, CSS, HTML, Seaborn, Bokeh

## RESEARCH EXPERIENCE

**RESEARCH ASSISTANT** 08/2021 to 09/2022

**Existential Robotics Lab**, La Jolla, CA

Developed ROS Gazebo simulation environment for autonomous driving prototyping.

Experimented and intergraded SLAM packages onto several ground robots for autonomous racing. Mentored by Professor Nikolay Atanasov.

## ACADEMIC PROJECTS

- **Deep Learning:** Experimented with state-of-the-art deep learning models on various tasks ranging from wildlife classification, artist identification, to image segmentation and art generation. Directly modified model architectures to better fit the task given.
- **Data Mining and Cloud Computing:** Performed parallel data analysis and data mining on large real world datasets using Hadoop, Spark and Dask on AWS EC2 clusters.
- **Interactive Visualization:** Developed a Dash-based indoor airborne COVID - 19 infection risk estimation website under the supervision of Professor Rajesh Gupta. Developed a Flask-based website for real time analyzation and visualization of Airbnb rental trends in NYC.
- **Autonomous Driving:** Implemented Particle Filter SLAM and Visual Inertial SLAM using various sensor readings of autonomous navigation prototypes.