Bohao Zhang

PhD Candidate · Robotics

University of Michigan, 2505 Hayward St, Ann Arbor, MI 48109

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Education

University of Michigan — *Ann Arbor*
PhD Candidate in Robotics — *Aug 2020 - present*
- Advisor: Prof. Ram Vasudevan

University of Michigan — *Ann Arbor*
BS in Computer Engineering — *Aug 2018 - May 2020*
- Minor in Mathematics

Shanghai Jiaotong University — *Shanghai*
BS in Electrical & Computer Engineering — *Aug 2016 - Aug 2020*

Professional Experience

2019-2020 **Undergraduate Research Assistant**, RoahmLab, University of Michigan

Research Projects

Provably-Safe, Real-time Planning & Control For Bipedal Robots Using Reachability-Based Trajectory Design — *2021 - present*

Worked on Agility Robotics' Digit-v3 humanoid robot
- Offline whole-body trajectory generation using nonlinear optimization
- Apply whole-body robust controller to achieve ultimate tracking performance under model uncertainty
- Generate whole-body reachable sets for collision checking during online planning
- Leader of the project

Autonomous Robust Manipulation via Optimization with Uncertainty-aware Reachability — *2021 - 2023*

Worked on Kinova Gen3 robotic arm
- Apply whole-body robust controller to achieve ultimate tracking performance under model uncertainty
- Reachability-based planning to achieve guaranteed-safe performance
- Design and implement algorithms for generating reachable sets and online planning

Real-Time, Safe Motion Planning and Control for Manipulation of Unsecured Objects — *2022 - present*

Worked on Kinova Gen3 robotic arm
- Generate reachable sets of contact constraints to guarantee safety of manipulating unsecured objects
- Design and implement algorithms for generating reachable sets and online planning

Real-Time, Certified, Chance-Constrained Motion Planning using the Parallel Bernstein Algorithm — *2020 - 2021*

Worked on a two-wheeled Segway
- Reachability-based planning to enable risk-aware performance
- Apply parallel Bernstein algorithm to find the global optimum of the online optimization problem in real time
- Implement algorithms for online planning

Safe, Optimal, Real-time Trajectory Planning with a Parallel Constrained Bernstein Algorithm *2019 - 2020*

Worked on a two-wheeled Segway

- Reachability-based planning to achieve guaranteed-safe performance
- Apply parallel Bernstein algorithm to find the global optimum of the online optimization problem in real time
- Design and implement algorithms for online planning

Publications

Published

Shreyas Kousik*, **Bohao Zhang***, Pengcheng Zhao*, Ram Vasudevan. 2021. Safe, Optimal, Real-time Trajectory Planning with a Parallel Constrained Bernstein Algorithm. IEEE Transactions on Robotics, vol. 37, no. 3, pp. 815-830.

Patrick Holmes, Shreyas Kousik, **Bohao Zhang**, Daphna Raz, Corina Barbalata, Matthew Johnson-Roberson, Ram Vasudevan. 2020. Reachable Sets for Safe, Real-Time Manipulator Trajectory Design. Robotics: Science and Systems.

In Prep

Jonathan Michaux, Patrick Holmes, **Bohao Zhang**, Che Chen, Baiyue Wang, Shrey Sahgal, Tiancheng Zhang, Sidhartha Dey, Shreyas Kousik, Ram Vasudevan. 2023. Can't Touch This: Real-Time, Safe Motion Planning and Control for Manipulators Under Uncertainty.

Skills

Languages	**MATLAB, C++, CUDA, Python**,
Softwares	**fmincon, Eigen, IPOPT, MuJoCo, Pinocchio, PyBullet, PyTorch**,
Soft Skills	**Professional academic communication, Project leadership, Independent research ability**,

Awards & Fellowships

2018 & 2019 **Dean's list**, University of Michigan

2017 **Honorable Mention**, COMAP Mathematical Contest in Modeling

2016 **John Wu & Jane Sun Outstanding Scholarship**, Shanghai Jiaotong University

Outreach & Professional Development

Service and Outreach

2022 **Girls in Science and Engineering (WISE GISE) Summer Day Camp**, Mentor

Peer Review

Reviewed one publication for IEEE Transactions on Robotics

Reviewed one publication for IEEE Transactions on Machine Learning in Communications and Networking