

# Weijian Zhang

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## EDUCATION

### University of Birmingham

Birmingham, United Kingdom

*Ph.D. Candidate in Computer Science*

*Feb. 2023 – Present*

*Advisor: Prof. Masoumeh Mansouri*

*Thesis: Formation Control and Motion Planning for Multi-Robot System*

### University of Birmingham

Birmingham, United Kingdom

*M.Sc. in Robotics (Degree Class: Distinction)*

*Sep. 2021 – Sep. 2022*

*Advisor: Prof. Masoumeh Mansouri*

*Thesis: Multi-robot object delivery in formation based on convex optimization*

### Southwest Jiaotong University

Chengdu, China

*B.Eng. in Automation*

*Sep. 2017 – Jun. 2021*

## RESEARCH INTERESTS

My research interests lie at the intersection of **planning** and **control** in multi-robot systems. My current research interests focus on **multi-robot formation control**, **multi-robot motion planning**, and **multi-robot cooperative manipulation**.

## PUBLICATIONS

### [1] Multi-Robot Navigation in Obstacle-cluttered Environments with LOS connectivity

Weijian Zhang, Charlie Street and Masoumeh Mansouri

*In Progress*

### [2] Collaborative Human-Robot Object Transportation Using a Deformable Sheet

Weijian Zhang, Charlie Street and Masoumeh Mansouri

*IEEE International Conference on Robotics and Automation (ICRA)*, 2026.

*Under Review*

### [3] Robots Calling the Shots: Using Multiple Ground Robots for Autonomous Tracking in Cluttered Environments

Weijian Zhang, Charlie Street and Masoumeh Mansouri

*IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, 2025. [\[PDF\]](#) [\[VIDEO\]](#) [\[CODE\]](#)

### [4] Multi-Nonholonomic Robot Object Transportation with Obstacle Crossing Using a Deformable Sheet

Weijian Zhang, Charlie Street and Masoumeh Mansouri

*IEEE International Conference on Robotics and Automation (ICRA)*, 2025. [\[PDF\]](#) [\[VIDEO\]](#) [\[CODE\]](#)

**Selected for Best Conference Paper Award Finalist & Best Paper Award Finalist on Multi-Robot Systems**

### [5] A Decoupled Solution to Heterogeneous Multi-Formation Planning and Coordination for Object Transportation

Weijian Zhang, Charlie Street and Masoumeh Mansouri

*Robotics and Autonomous Systems (RAS)*, 2024. [\[PDF\]](#) [\[VIDEO\]](#) [\[CODE\]](#)

**Selected for Best Poster award at The 7th IEEE UK & Ireland RAS Conference**

### [6] Multi-Formation Planning and Coordination for Object Transportation

Weijian Zhang, Charlie Street and Masoumeh Mansouri

*IEEE European Conference on Mobile Robots (ECMR)*, 2023. [\[PDF\]](#) [\[VIDEO\]](#) [\[CODE\]](#)

## RESEARCH EXPERIENCE

### Using Multiple Ground Robots for Autonomous Tracking in Cluttered Environments

Oct. 2024 – Mar. 2025

*Research Student, University of Birmingham*

*Advisor: Prof. Masoumeh Mansouri and Dr. Charlie Street*

- Introduced a novel hierarchical multi-robot trajectory planning framework which maximizes camera coverage in cluttered environments while avoiding collisions and maintaining visibility of the human.
- Evaluated our approach in simulation, demonstrating how we outperform existing works by explicitly considering the kinodynamic constraints of differential-drive robots and the topology of the environment.

### Collaborative Object Transportation Using a Deformable Sheet

Aug. 2024 – Ste. 2025

*Research Student, University of Birmingham*

*Advisor: Prof. Masoumeh Mansouri and Dr. Charlie Street*

- Designed a multi-modal real-time formation trajectory planning framework where leadership switches between the human and robots to maximize safety and transportation efficiency.
- Developed a method for computing feasible regions that can be visualized to the human to guide them during obstacle crossing.
- Proposed a heuristic path exploration method which efficiently evaluates a set of homotopically distinct solution spaces for the formation.
- Proposed a two-stage iterative motion planning framework for finding locally time-optimal collision-free formation trajectories using a deformable sheet.
- Validated the efficacy of our framework in simulation and through real robot experiments.

**Heterogeneous Multi-Formation Planning and Coordination for Object Transportation**
Feb. 2023 – Jul. 2024

*Research Student, University of Birmingham*
*Advisor: Prof. Masoumeh Mansouri and Dr. Charlie Street*

- Designed a comprehensive H-MFPC framework which integrates formation generation, planning, and coordination techniques for heterogeneous formations.
- Proposed an efficient formation generation approach for heterogeneous multi-robot systems which synthesises collision-free and kinematically feasible trajectories in unstructured environments.
- Proposed a cost-optimal formation planning method that maintains rigidity for heterogeneous formations.
- Proposed a loosely-coupled multi-formation coordination algorithm for ensuring deadlock-free and collision-free navigation among formations.

### SELECTED AWARDS

<b>ICRA 2025 Best Paper Award Finalist on Multi-Robot Systems - IEEE</b>	Oct. 2025
<b>RAS 2024 Best Poster award - IEEE</b>	Jul. 2024
<b>Computer Science School Prize - University of Birmingham</b>	Dec 2022
<b>Comprehensive Scholarship - Southwest Jiaotong University</b>	Dec 2020
<b>Comprehensive Scholarship - Southwest Jiaotong University</b>	Dec 2019

### ACADEMIC SERVICE

**Reviewer:** ICRA (2024, 2025, 2026), IROS (2024, 2025), AAMAS (2025), MRS (2025), RITA (2025)

**Teaching Assistant:** LM Robot Vision (*University of Birmingham*, Autumn 2023), LH Computer Vision and Imaging (*University of Birmingham*, Autumn 2023), LC Artificial Intelligence 1 (*University of Birmingham*, Spring 2024/2025), LM Advanced Robotics (*University of Birmingham*, Autumn 2024), LH/LM Intelligent Robotics (*University of Birmingham*, Autumn 2024), LM Robot Motion Planning and Control (*University of Birmingham*, Spring 2025/2026)

### SKILLS

**Languages:** English (Fluent), Chinese (Native)

**Programming Tools:** Python, C++ , MATLAB,  $\text{\LaTeX}$

**Frameworks:** Git, ROS, Gazebo, Pybullet, Linux

**Platforms:** TurtleBot3/4, MiR, HUNTER SE