

# Weijian Zhang

📍 Birmingham, United Kingdom | 📩 wxz163@student.bham.ac.uk | 🐧 GitHub | 🌐 <https://simonzhang1999.github.io>

## EDUCATION

### University of Birmingham

*Ph.D. Candidate in Computer Science*

*Advisor: Prof. Masoumeh Mansouri*

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

Birmingham, United Kingdom

Feb. 2023 – Present

### University of Birmingham

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

*Advisor: Prof. Masoumeh Mansouri*

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

Birmingham, United Kingdom

Sep. 2021 – Sep. 2022

### Southwest Jiaotong University

*B.Eng. in Automation*

Chengdu, China

Sep. 2017 – Jue. 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**

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**ICRA 2025 Best Conference Paper Award Finalist - IEEE**

May 2025

**ICRA 2025 Best Paper Award Finalist on Multi-Robot Systems - IEEE**

May 2025

**RAS 2024 Best Poster award - IEEE**

Jul. 2024

**Computer Science School Prize - University of Birmingham**

Dec. 2022

**Comprehensive Scholarship - Southwest Jiaotong University**

Dec. 2020

**Comprehensive Scholarship - Southwest Jiaotong University**

Dec. 2019

### **ACADEMIC SERVICE**

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**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**

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

**Programming Tools:** Python, C++, MATLAB, L<sup>A</sup>T<sub>E</sub>X

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

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