

Ruoxiang Li | Curriculum Vitae

Kaifu District, Changsha, Hunan, China – 410073

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🌐 Homepage

RESEARCH INTEREST

Visual SLAM, Event-based SLAM, Robotics, Computer Vision

EDUCATION

National University of Defense Technology (Non-military student)

Master of Engineering in Computer Science and Technology

Advisor: Prof. Dr. Dianxi Shi

Changsha, China

Sept. 2017 - June 2020

Northeastern University

Bachelor of Engineering in Internet of Things

GPA: 3.5835 / 5 (Top 15%)

Shenyang, China

Sept. 2013 - June 2017

PUBLICATIONS

- **Ruoxiang, Li** and Dianxi, Shi and Yongjun, Zhang and Kaiyue, Li and Ruihao, Li, "FA-Harris: A Fast and Asynchronous Corner Detector for Event Cameras," IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), 2019.
- Kaiyue, Li and Dianxi, Shi and Yongjun, Zhang and **Ruoxiang, Li** and Ruihao, Li, "Feature Tracking Based on Line Segments with the Dynamic and Active-pixel Vision Sensor (DAVIS)," In submission.
- Zhuoyue, Yang and Dianxi, Shi and Yongjun, Zhang and Shaowu, Yang and Fu, Li and **Ruoxiang, Li**, "Multi-UAV Collaborative Monocular SLAM Focusing on Data Sharing," International Conference on Neural Information Processing. Springer, Cham, 2018.

COMPETITION EXPERIENCE

ABU Robocon (Third Award, Best Design Award)

June 2015

- **Team Task:** Independently design two robots cooperating to play badminton doubles.
- **Duties included:** Coordinate conversion, data acquisition and processing procedures based on Kinect for Windows v2 using C language, test the effect of illumination on Kinect depth camera.
- **Development Tools:** Halcon, Microsoft Visual Studio

Robot Competition for Undergraduates in Liaoning Province (First Award)

Oct. 2014

- **Team Task:** Independently design two robots cooperating to collect golf balls in the designated area and transport the collected balls to the starting position.
- **Duties included:** Robot control program design, control the robot to collect golf balls by fixed route based on LPC1700 series Cortex-M3 micro-controller and μC /OSII system (using C language).
- **Skills & devices:** CAN communication, Gyroscope, Encoder

PROJECT EXPERIENCE

Intelligent Unmanned Cluster System

2017 - 2018

- Aim to construct operational support platform for intelligent unmanned cluster system.
- Participate in the research of incremental global view extension technology related to visual SLAM.
- Responsible for multi-UAV collaborative mapping based on Monocular SLAM.

COURSES

Master

2017 - Present

- Machine Learning (A)
- Matrix Analysis and Calculation (B)
- Principle of Artificial Intelligence (B)
- Computational Complexity (B)
- Computational Geometry (B)
- Parallel Computing (B)

Bachelor

2014 - 2017

- Object-Oriented Programming (C++) (97)
- Design and Analysis of Algorithms (95)
- Probability Theory and Mathematical Statistics (90)
- Data Structure (89)
- Discrete Mathematics (89)
- Linear Algebra (86)

HONORS AND AWARDS

National University of Defense Technology

2017 - Present

- Postgraduate Admission Scholarship (Nov. 2018)
- Outstanding Postgraduate (June 2019)

Northeastern University

2014 - 2017

- Second-class Scholarship (Apr. 2014)
- Second-class Scholarship (Oct. 2014)
- Outstanding Student Leader (Oct. 2014)
- Third-class Scholarship (Nov. 2015)
- Outstanding Student Leader (Nov. 2015)
- First-class Scholarship (Oct. 2016)
- Zhongtian Iron and Steel Scholarship (Second-Class) (Oct. 2016)
- Second-class Scholarship (Oct. 2017)
- Outstanding Graduate of Liaoning Province (Mar. 2017)

REFERENCES

○ Prof. Dr. Dianxi Shi

dxshi@nudt.edu.cn

Professor, State Key Laboratory of Parallel and Distributed Processing

National University of Defense Technology, Changsha-410073, China.

Artificial Intelligence Research Center (AIRC), National Innovation Institute of Defense Technology (NIIDT), Beijing-100166, China.

Tianjin Artificial Intelligence Innovation Center (TAIIC), Tianjin-300457, China.

○ Dr. Ruihao Li

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Dr. Ruihao Li received his Ph.D. from University of Essex, Colchester, UK.

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