

Wenyu Yang 杨雯语

Information

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Advanced Manufacturing Technology Laboratory.

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Education

- **M.Eng. Harbin Institute of Technology** **09/2019-Present**
Advisor: Dr. Chengxi Lei Dept. of Mechatronics
Research Topic: Plastic Deforming, Robotic, Mechanic
- **B.Eng. Ocean University of China** **09/2015-06/2019**
Mechanical Design Manufacture & Automation
GPA:3.21/4 Rank:8/63

IELTS: Total 6.5; L7 R7.5 W6 S6

Publications

- **Role of mandrel in variable curvatures local-induction-heating bending process of B1500HS thin-walled rectangular tube**, Tingjun Cai, Chengxi Lei, **Wenyu Yang**, Hongya Fu, Zhongwen Xing. *International Journal of Advanced Manufacturing Technology (IJAMT)* (under review)

Honors and Awards

- First scholar(*twice*) **2017/2018**
- Second Prize in 14th Mechatronics Innovation Competition. Shandong **2018**
- Second Prize in 7th National Marine Vehicle Design and Manufacture Competition. Wuhan. **2018**
- Second Prize in 6th "Internet +" innovation and entrepreneurship contest. Heilongjiang **2020**

Skills

- **Programming Skills:** C/C++, Matlab, Python
- **Robot Frameworks:** ROS, Gazebo
- **Tools:** Linux, Visual Studio, Pycharm, Keil, Solidworks, Ansys, Abaqus

Research Interest

- Plastic forming; Robotics; Control; Sensor Fusion; Machine learning.

Project Experience

- **2016.10-2017.06 UAV with manipulator based on binocular camera**
 - Goal:** To build a UVA that is able to catch underwater objects automatically
 - Method:** Visual-servo control, object detection, H-D kinematics model
 - Innovative:** The mass of the manipulator is mainly located at its foundation, thus the movement of the end will not change the rotational inertia of the AUV
 - Difficulties:** Transmission mechanism, hand-eye vision calibration
 - Results:** Belt drive & wire drive manipulator is built, and is able to automatically catch objects guided by stereo camera.

- **2017.10-2018.06 Deformed Underwater Robot**
 - Goal:** To build a UVA that is able dive/go forward quickly in different states
 - Method:** Deformation structure, Buoyancy changing
 - Innovative:** The center of mass and center of buoyancy changing according to different modes (drive & dive)
 - Results:** 2 different modes for the UAV to dive or go forward more efficient is developed

- **2019.3-2020.06 Induction heating bending of High-strength steel tube**
 - Goal:** To explore the mechanism of high strength steel tube hot bending forming
 - Method:** Theoretical calculation, Numerical simulation, Experiment verification
 - Innovative:** New technology to forming high strength steel tubes in free curvatures
 - Difficulties:** Forming quality and forming accuracy
 - Results:** New process is developed in high strength steel tube induction heating bending

- **2019.10- Dexterous hand (on-going)**
 - Goal:** To build dexterous hand (*fingers*) driven by palm muscle movement
 - Method:** Force sensing resistor, pattern recognition
 - Innovative:** Sensory control of dexterous hand
 - Results:** Up coming.....