

# Sanghyun Kim

---

|                        |   |
|------------------------|---|
| CURRENT<br>AFFILIATION | <p><b>Ph.D. Candidate</b> (expected in 2020.2) at the Department of Transdisciplinary Studies,<br/>Graduate School of Convergence Science and Technology,<br/>Seoul National University</p> <p><b>Visiting Researcher</b> (until 2019.6) at the Gepetto Team,<br/>Laboratory for Analysis and Architecture of Systems (LAAS),<br/>Centre National de la Recherche Scientifique (CNRS)</p>   |
| CONTACT<br>INFORMATION | <p><i>Address:</i> 23 Avenue Edouard, 31400, Toulouse, France<br/><i>E-mail:</i> ggory15@snu.ac.kr<br/><i>Phone:</i> 82-10-5366-4998 (Korea), 33-07-68-79-58-27 (France)<br/><i>WWW:</i> <a href="http://ggory15.github.io">http://ggory15.github.io</a> (for my projects), <a href="http://github.com/ggory15">http://github.com/ggory15</a> (for source codes)</p>  |
| EDUCATION              | <p><b>Seoul National University</b>, Seoul, Korea <b>2012.3 - Presence</b><br/>Ph.D. Candidate of Dept of Transdisciplinary Studies</p> <ul style="list-style-type: none"><li>• Lab: Dynamic Robotic System Lab (DYROS Lab, <a href="https://dyros.snu.ac.kr">https://dyros.snu.ac.kr</a>)</li><li>• Advisor: Professor Jaeheung Park (park73@snu.ac.kr)</li></ul> <p><b>Seoul National University</b>, Seoul, Korea <b>2005.3 - 2012.2</b><br/>B.A., Mechanical Engineering, March, 2012</p>   |
| VISITING<br>EXPERIENCE | <p><b>Centre National de la Recherche Scientifique (CNRS)</b>, France <b>2018.8 - Presence</b><br/>Visiting Researcher</p> <ul style="list-style-type: none"><li>• Lab: Gepetto Team (<a href="http://projects.laas.fr/gepetto">http://projects.laas.fr/gepetto</a>)</li><li>• Advisor: Dr. Nicolas Mansard (nmansard@laas.fr)</li><li>• Funding: Korean government grant</li></ul> <p><b>Gwangju Institute of Science and Technology (GIST)</b>, Korea <b>2010.6 - 2010.9</b><br/>Student Internship</p> <ul style="list-style-type: none"><li>• Lab: Haptic Team (<a href="http://dyconlab.gist.ac.kr">http://dyconlab.gist.ac.kr</a>)</li><li>• Advisor: Professor Jeha Ryu (ryu@gist.ac.kr)</li></ul>   |
| RESEARCH<br>INTERESTS  | <p><b>Hierarchical whole-body control</b> of bipedal robot and mobile-based humanoid<br/><b>Task and contact transition algorithm</b> for hierarchical controller<br/><b>Torque-based task space control</b><br/><b>Whole-body planning</b> for high redundant robot<br/><b>Dexterous robot hand control</b><br/><b>Manipulation of redundant robotic system</b></p>  |
| RESEARCH<br>EXPERIENCE | <p><b>During visiting researcher in Gepetto Team, LAAS-CNRS, France</b></p> <p><b>Whole-body Planning for Humanoid</b> <b>2018 - Presence</b></p> <ul style="list-style-type: none"><li>• (Ongoing Work) Generating contact sequence, CoM trajectory, feet trajectories, and whole-body trajectory for legged robots.<ul style="list-style-type: none"><li>✓ Video: <a href="https://youtu.be/JpwigzMQg6E">https://youtu.be/JpwigzMQg6E</a></li></ul></li><li>• Implementation of CoM trajectory generator based on <i>Time Optimization</i>.</li><li>• Implementation of feet trajectories using the concept of hyper-plane.</li><li>• Implementation of Quadratic Programming (QP)-based whole-body planner in C++ and Python:<ul style="list-style-type: none"><li>✓ Video: <a href="https://youtu.be/nHiLV89cMG8">https://youtu.be/nHiLV89cMG8</a></li><li>✓ Codes: <a href="https://github.com/ggory15/tsid_python_binding">https://github.com/ggory15/tsid_python_binding</a></li></ul></li></ul> |

### ***Model Predictive Control for Humanoid***

**2018 - Presence**

- (Ongoing Work) Developing whole-body controller using Differential Dynamic Programming (DDP).
- (Ongoing Work) Implementation of DDP-based controller with the collision avoidance constraint.
  - ✓ (Preliminary) Video : <https://youtu.be/rq3dXdt8t0E>

### **During Ph.D. student**

#### ***Whole-body Control of Torque-controlled Humanoids***

**2014 - Presence**

- Design and development of torque-controlled humanoid, DYROS-Red [C3].
  - ✓ EtherCAT and RTX programming for real-time control
  - ✓ High-level controller: Whole-body controller
  - ✓ Low-level controller: Elmo motion controller
  - ✓ Video : <https://youtu.be/01E-rKixNfE>
- Implementation of whole-body controllers for torque-controlled humanoids.
  - ✓ Using operational-space controller [C3]
  - ✓ Using hierarchical QP-based controller [J3]
  - ✓ Using DDP-based controller
- (Ongoing Work) Development contact force generator with multi-constraints for dynamic balance.

#### ***Multiple Task Execution Algorithm***

**2017 - Presence**

- Dynamic task transition algorithm to generate complex behavior.
- Continuous transitions between arbitrary tasks using the activation parameter [J3].
  - ✓ Insertion and removal both equality and inequality tasks without discontinuity of the control input.
  - ✓ Development of avoidance tasks including joint-limit, singularity, and obstacle.
  - ✓ Video : <https://youtu.be/-lfnLhmSk3M>
  - ✓ Codes: <https://ggory15.github.io/tasktransition-project>
- (Ongoing Work) Applying the task transition method to operate mobile-based humanoid
  - ✓ Development controller for archiving complex tasks [O2]
  - ✓ Self-collision avoidance algorithm using the concept of attractive force [O1]
  - ✓ Video : <https://youtu.be/K8RnMAA0rg4>
  - ✓ Video : <https://youtu.be/FyiSZ1lomSs>
- (Ongoing Work) Multi-contact transition for humanoids using Gravito-Inertial Wrench Cone (GIWC)

#### ***Control of Position-controlled Humanoids***

**2014 - 2018**

- Design and development of position-controlled humanoid, DYROS-Jet [J1].
  - ✓ RS-232 communication with 200 Hz
  - ✓ High-level controller: Jacobian-based controller
  - ✓ Low-level controller: Robotis controller
  - ✓ Video : <https://youtu.be/9UwJQREUjtc>
- Implementation of inverse kinematics controllers for position-controlled humanoids
  - ✓ using Jacobian-based inverse kinematics controller [J1, C4, W2]
  - ✓ using Forward And Backward Reaching Inverse Kinematics (FABRIK) [C8]
  - ✓ using Recursive Neural Network (RNN) [C7]
- Disturbance observer to enhance balancing performance [C6]
  - ✓ Feed-forward joint disturbance observer for compliant motion
  - ✓ Video: <https://youtu.be/LHGxx0M9ijs>

#### ***Singularity Avoidance Algorithms***

**2016 - 2017**

- Comparative analysis of six representative singularity avoidance algorithms:  
Damped Pseudo Inverse, Error Damped Pseudo Inverse, Jacobian Transpose, Selectively Damped Inverse, Filtered Inverse, and Task Transition Method

***Development of Humanoid System for DRC Finals 2015*** **2014 - 2016**

- Student leader of Team SNU
  - ✓ Managing the whole framework of robot
  - ✓ Developing the upper-body and lower-body position controller
- No falling down during the competitions and 12th in DRC Finals 2015 [J1, C4, B1, W2]
  - ✓ Video: <https://youtu.be/aWpyfKkbzf0>

***Artificial Intelligence Robot CPR System*** **2014 - 2016**

- Robot manipulator to perform CPR in emergency situations [P1, P3, C5]
- Automatic System based biological data from a patient
- Simulation on mannequin and animal test
  - ✓ Video: <https://youtu.be/D9saZERvzf8>

***Robot Hand Tele-operation Control*** **2012 - 2014**

- Robot hand synergy mapping using multi-factor model [P2, C2, W1]
- Extracting synergy by considering individual characteristic as well as grasping motion
  - ✓ Video: <https://youtu.be/QzGgV9KHaZI>
- Grasping Force Estimation using sEMG signals [J2]

***Tele-operation Control of Ultrasonic Examination System*** **2012 - 2013**

- Tele-operated robotic arm for remote ultra-sound exam
- Automated orientation control for ultrasound
- Contact force feedback using haptic device
  - ✓ Video: [https://youtu.be/\\_OSkL5e70fl](https://youtu.be/_OSkL5e70fl)

**During internship in GIST, Korea**

***Friction and Gravity Compensator for Surgery Simulator*** **2010.6 - 2010.9**

- Research and development on the Laparoscopic simulator
- Haptic Feedback using friction and gravity compensator [C1]

**TECHNICAL SKILLS** **Hardware Experience**

***Human-sized Humanoids***

- Torque controlled robot, *DYROS-Red*
- Position controlled robot, *DYROS-Jet*
- Torque controlled robot, *TALOS (PAL Robotics Co.)*
- Position controlled robot, *HRP-2*

***Mobile-based Humanoids***

- Four-wheeled mobile base, *Husky*, with 7-DoF arm, *Franka Panda*

***Manipulator***

- 7-DoF arm, *Franka Panda*
- 6-DoF arm, *Roman-6D*
- 6-DoF arm, *Denso Arm*

**Software Experience**

***Programming Skills***

- Intermediate C++, Python, and Matlab programming for robotics (Windows, Ubuntu 16.04 LTS)
- V-Rep, MuJoCo, Gazebo, and Pinocchio for the robotic simulation

***Libraries***

- Math - Eigen, LAPACK, MKL
- Optimization - qpOASES, Eiquadprog, IPOPT, IPOPT
- Robot Kinematics and Dynamics: Pinocchio, RBDL
- Others: Boost (in particular, boost-python), FCL

HONORS AND  
AWARDS

**Korean government grant** for Visiting Scholar of LAAS-CNRS, 2018.  
**Best paper award** in Journal of Korea Robotics Society (JKROS), 2018.  
**Cum laude** from Dept. of Mechanical Engineering at Seoul National University, 2012.

PATENTS

[P3] **Sanghyun Kim** *et al.* Automatic cardiopulmonary resuscitation device and control method therefor, US Patent, No. 20190029919A1, CN Patent, No. 108697572A, EU Patent, No. 3409258A1, 2019

[P2] **Sanghyun Kim**, Jaeheung Park, Mignon Kim, Jimin Lee, Joungheum Kwon, Bumjae You. APPARATUS FOR ESTIMATING GRASPING POSTURE AND GRASPING FORCE. Korea Patent, No.10-2016-0075150, 2016.

[P1] **Sanghyun Kim** *et al.* APPARATUS FOR AUTOMATIC CARDIOVASCULAR PULMONARY RESCITATION. Korea Patent, No.10-2016-0011876, 2016.

INTERNATIONAL  
JOURNAL ARTICLES

[J3] **S. Kim**, K. Jang, S. Park, Y. Lee, S. Y. Lee, and J. Park, Continuous Task Transition Approach for Robot Controller based on Hierarchical Quadratic Programming, IEEE Robotics and Automation Letters (with ICRA 2019 presentation), Vol. 4, No. 2, pp. 1603-1610, 2019

[J2] **S. Kim**, M. Kim, J. Kim, S. Kim, and J. Park. Grasping Force Prediction by EMG Signals and Arm Posture: Tensor Decomposition Approach, International Journal of Bionic Engineering, accepted, 2019

[J1] **S. Kim**, M. Kim, J. Lee, S. Hwang, J. Chae, B. Park, H. Cho, J. Sim, J. Jung, H. Lee, S. Shin, M. Kim, W. Choi, Y. Lee, S. Park, J. Oh, Y. Lee, S. Lee, M. Lee, S. Yi, K. Chang, N. Kwak, and J. Park. Team SNU's Control Strategies to Enhancing Robots Capability: Lessons from the DARPA Robotics Challenge Finals 2015. Journal of Field Robotics, Vol. 34, No. 2, pp. 359-380, 2017

INTERNATIONAL  
CONFERENCE  
ARTICLES

[C8] **S. Kim**, J. Kim, and J. Park. Real-time Inverse Kinematics Technique for Controlling Humanoid Avatar with Redundant Arm, Ubiquitous Robot 2018, Hawaii, USA, 2018.

[C7] M. Kim, J. Kim, **S. Kim**, J. Sim, and J. Park. Disturbance Observer based Linear Feedback Controller for Compliant Motion of Humanoid Robot, International Conference on Robotics and Automation, Australia, 2018.

[C6] M. Kim, **S. Kim**, and J. Park. Human Motion Imitation for Humanoid by Recurrent Neural Network. The 13th International Conference on Ubiquitous Robots and Ambient Intelligence, Xian, China, 19-22 Aug, 2017.

[C5] J. Jung, J. Kim, **S. Kim**, W. Kwon, S. Na, K. Kim, J. Lee, G. Suh, and J. Park. Application of Robot Manipulator for Cardiopulmonary Resuscitation, International Symposium on Experimental Robotics, Tokyo, Japan, 2016.

[C4] **S. Kim**, M. Kim, J. Lee, S. Hwang, J. Chae, B. Park, H. Cho, J. Sim, J. Jung, H. Lee, S. Shin, M. Kim, N. Kwak, Y. Lee, S. Lee, M. Lee, S. Yi, K. K.C. Chang, and J. Park. Approach of Team SNU to the DARPA Robotics Challenge Finals. 2015 IEEE-RAS International Conference on Humanoid Robots, Seoul, Korea, 3-5 Nov 2015.

[C3] M. Schwartz, S. Hwang, Y. Lee, J. Won, **S. Kim**, and J. Park. Aesthetic Design and Development of Humanoid Legged Robot. The 2014 IEEE-RAS International Conference on Humanoid Robots, Madrid, Spain, 18-20 Nov 2014.

[C2] **S. Kim**, M. Kim, J. Lee, and J. Park. Robot Hand Synergy Mapping Using Multi-factor

Model and EMG signal. International Symposium on Experimental Robotics, Marrakech/Essaouira, Morocco, 15-18 June 2014.

[C1] **S. Kim**, C. Lee, and J. Ryu. Data-driven Haptic Rendering of Friction between Surgical Device and Trocar for Laparoscopic Surgery Simulator, The 6th Asian Conference on Computer Aided Surgery (ACCAS), Busan, Korea, 2010.

DOMESTIC  
JOURNAL ARTICLES

[DJ6] K. Jang, **S. Kim**, S. Park, and J. Park. Unified Framework for Overcoming Motion Constraints of Robots Using Task Transition Algorithm, Journal of Korea Robotics Society, Vol. 13, No. 2, 2018.

[DJ5] J. Kim, **S. Kim**, and J. Park. The Trends of HRI: Focusing on Task Oriented Robot User Interface, Robot and Human, Vol. 14, No. 4, 2017.

[DJ4] **S. Kim** and J. Park. Singularity Avoidance Algorithms for Controlling Robot Manipulator: A Comparative Study, Journal of Korea Robotics Society, Vol. 12, No. 1, 2017. **Best Paper Award**

[DJ3] S. Shin, M. Kim, J. Ahn, **S. Kim**, and J. Park. Development of Tele-operation Interface and Stable Navigation Strategy for Humanoid Robot Driving, Journal of Institute of Control, Robotics and Systems, Vol. 22, No. 11, 2016.

[DJ2] **S. Kim**, B. Park, and J. Park. DRC Finals 2015 Analysis of Participants, Robot and Human, Vol. 12, No. 4, 2015.

[DJ1] **S. Kim**, C. Lee, J. Kim, and J. Ryu. Approximate Friction and Gravity Compensation in Haptic Laparoscopic Surgery Simulator, Transactions of the KSME, Vol. 35, No. 8, 2010.

DOMESTIC  
CONFERENCE  
ARTICLES

[DC8] S. Y. Lee, S. Park, K. Jang, **S. Kim**, S. Kim, and J. Park. A Comparative Study of Tracking Control with Closed Loop Inverse Kinematics Algorithm, The 14th Korea Robotics Society Annual Conference (KROC), Korea, 2019.

[DC7] J. Jang, **S. Kim**, S. Park, S. Y. Lee, and J. Park. Self-collision Avoidance Algorithm for Robot Manipulator using Continuous Task Transition Algorithm, The 14th Korea Robotics Society Annual Conference (KROC), Korea, 2019.

[DC6] K. Jang, **S. Kim**, S. Park, and J. Park. Joint Limit Avoidance of Non-holonomic Mobile Manipulator using Weighting Matrix in Generalized Pseudo-Inverse, Conference on Korean Society for Precision Engineering, Korea, 2017.

[DC5] M. Kim, R. Destenay, **S. Kim**, J. Kwon, K. Yeom, J. Park, and B. You. Avatar Motion Generation by Null-Space Mapping Based on Minimum Number of Markers. 2015 Conference on Information and Control Systems, Sokcho, Korea, 2015.

[DC4] **S. Kim**, M. Kim, and J. Park. Extracting Postural Synergies Using Grasping Taxonomy, The 9th Korea Robotics Society Annual Conference (KROC), Korea, 2014.

[DC3] J. Lee, M. Kim, **S. Kim**, and J. Park. Estimation of Hand Posture and Grasping Force Using Surface EMG, The 9th Korea Robotics Society Annual Conference (KROC), Korea, 2014.

[DC2] **S. Kim**, C. Lee, J. Kim, and J. Ryu. Friction and Gravity Compensation in Haptic Laparoscopic Surgery Simulator, Conference on Korean Society of Mechanical Engineers (KSME), Korea, 2010.

[DC1] **S. Kim**, C. Lee, J. Kim, and J. Ryu. Trocar Friction modelling for Friction and gravity

Compensation, Conference on Korean Society of Mechanical Engineers (KSME), Korea, 2010.

- BOOK CHAPTER [B1] **S. Kim**, M. Kim, J. Lee, S. Hwang, J. Chae, B. Park, H. Cho, J. Sim, J. Jung, H. Lee, S. Shin, M. Kim, W. Choi, Y. Lee, S. Park, J. Oh, Y. Lee, S. Lee, M. Lee, S. Yi, K. Chang, N. Kwak, and J. Park. Team SNU's Control Strategies to Enhancing Robots Capability: Lessons from the DARPA Robotics Challenge Finals 2015, The DARPA Robotics Challenge Finals: Humanoid Robots to the Rescue, Springer, pp. 347-379, 2018.
- WORKSHOPS [W2] **S. Kim** and J. Park. Control Strategies of Team SNU for DRC Finals, and Future Directions for Robots in Human Environment. Invited speaker at Workshop on What did we do for the DARPA Robotics Challenge?, 2015 IEEE-RAS International Conference on Humanoid Robots, Seoul, Korea, 3-5 Nov 2015.
- [W1] **S. Kim**, J. Lee, M. Kim, and J. Park. Teleoperated Robot Hand Control using Tensor Decomposition. Full-day Tutorial on Robotics-based Methods for the Identification, Recognition, and Synthesis of Human Motions, IEEE/RSJ International Conference on Intelligent Robots and Systems, Tokyo, Japan, 3 Nov 2013.
- ONGOING PAPERS [O2] **S. Kim**, K. Jang, S. Park, Y. Lee, S. Y. Lee, and J. Park, Whole-body Control of Non-holonomic Mobile Manipulator Based on Hierarchical Quadratic Programming and Continuous Task Transition. IEEE International Conference on Advanced Robotics and Mechatronics (ARM), under review, 2019.
- [O1] K. Jang, **S. Kim**, S. Park, S. Kim, and J. Park, Real-Time Self-Collision Avoidance based on Attractive Force and Torque for Differentially Driven Mobile Manipulators, IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), under review, 2019.