

# QUANG-HA PHAM

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## RESEARCH INTERESTS

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SLAM, Localization, State Estimation and Control.

## EDUCATION

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|---------------|--|---------------------|
| <b>M.Eng.</b> | University of Technology, VNU-HCM  | Mar 2021 – present  |
|               | • <b>Major:</b> Control Engineering & Automation ( <i>Research Program</i> )   |                     |
| <b>B.Eng.</b> | University of Technology, VNU-HCM  | Sep 2016 – Nov 2020 |
|               | • <b>Major:</b> Control Engineering & Automation ( <i>Honors Program</i> )   |                     |
|               | • <b>GPA:</b> 8.42/10.0  |                     |
|               | • <b>Thesis:</b> Constructing Map and Collision-Free Path for Autonomous Vehicles ( <i>defended with 9.58/10.0</i> ) |                     |

## RESEARCH EXPERIENCE

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| <b>Graduate Research Assistant</b>   | Oct 2020 – present  |
| Vietnam Automation & Mechatronics Laboratory   |                     |
| <ul style="list-style-type: none"><li>• Develop an efficient camera-lidar fusion mechanism for SLAM in natural environments (<i>ongoing</i>).</li><li>• Build a ROS-based autopilot software suite, namely VIAM-USV-VC, for VIAM-USV2000 surface vessel:<ul style="list-style-type: none"><li>○ Implement previously simulated WAM-V's algorithms.</li><li>○ Realize data interchange with STM32F407 microcontroller through CAN bus, with VIAM-USV-GC ground control station through MAVLink protocol.</li><li>○ Deploy in Jetson Nano embedded computer.</li></ul></li><li>• Simulate some autonomous capabilities for surface vessel on Gazebo:<ul style="list-style-type: none"><li>○ Refine 3D model of WAM-V surface vessel by equip it with additional sensors and actuators.</li><li>○ Implement R-modelled sliding-mode heading controller, straight-or-bspline LOS path following, SBG obstacle avoidance.</li></ul></li></ul> |                     |
| <b>Research Assistant</b>  | Jul 2018 – Oct 2020 |
| Vietnam Automation & Mechatronics Laboratory   |                     |
| <ul style="list-style-type: none"><li>• Develop an online, graph-based LiDAR SLAM system:<ul style="list-style-type: none"><li>○ Implement PLICP fast scan-matcher for dense pose graph construction.</li><li>○ Perform sliding-windowed optimization on graph's nodes by g2o.</li><li>○ Utilize ROS's ecosystem to facilitate sensor reading, data interchange, data logging and algorithmic visualization.</li><li>○ Test the system's performance prior to real-world deployment by simulating on Gazebo.</li></ul></li></ul>   |                     |

- Carry out experiments with Hokuyo UTM-30LX 2D LiDAR in both structured and natural environments.
- Build a customized version of QGC ground control station, namely VIAM-USV-GC, for VIAM-USV2000 surface vessel.
- Build a Qt-based GUI to remotely command and monitor Delivery AGV:
  - Implement Dijkstra's algorithm for global path planning.
  - Realize data interchange with the vehicle's autopilot through MAVLink protocol, with Android-based ordering app through MQTT protocol.
- Build a ROS-based autopilot software suite for Delivery AGV:
  - Implement straight LOS path following, PID heading control.
  - Realize data interchange with STM32F407 microcontroller through UART bus, with monitor GUI through MAVLink protocol.
  - Deploy in Raspberry Pi 4 embedded computer.

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## PUBLICATIONS

**2021**

**P. Q. Ha**, T. N. Huy, N. T. Toan and T. T. Phuc, "Online Robust Sliding-Windowed LiDAR SLAM in Natural Environments," accepted at *2021 International Symposium on Electrical and Electronics Engineering (ISEE)*, Ho Chi Minh City, 2021.

**2020**

T. N. Huy, V. M. Hung, N. T. Cuong, P. M. Tam and **P. Q. Ha**, "Implementation and Enhancement of Set-Based Guidance by Velocity Obstacle along with LiDAR for Unmanned Surface Vehicles," in *2020 5th International Conference on Green Technology and Sustainable Development (GTSD)*, Ho Chi Minh City, 2020.

**P. Q. Ha** and P. M. Tam, "Constructing Map and Collision-Free Path for Autonomous Vehicles," *Bachelor Thesis*, University of Technology, Vietnam National University Ho Chi Minh City, 2020.

**P. Q. Ha**, T. N. Huy and T. T. Phuong, "Design and Control of Automated Guided Vehicle," *Applied Mechanics and Materials*, vol. 902, pp. 33-42, 2020.

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## PRESENTATIONS AND INVITED LECTURES

**Paper Presentation**, "Online Robust Sliding-Windowed LiDAR SLAM in Natural Environments," *International Symposium on Electrical and Electronics Engineering (ISEE)*, 15/4/2021.

**Paper Presentation**, "Implementation and Enhancement of Set-Based Guidance by Velocity Obstacle along with LiDAR for Unmanned Surface Vehicles," *International Conference on Green Technology and Sustainable Development (GTSD)*, 28/11/2020.

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## PROJECTS

<b>Design and Control a Delivery AGV</b>	Sep 2019 – Sep 2020
2019 Scientific Research for Student, University of Technology, VNU-HCM	

- **Role:** I was responsible for building the software infrastructure on embedded computer, implementing guidance and control laws, designing monitor GUI on laptop.
- **Description:** We aim to make local delivery faster and cheaper without human intervention by designing an automated guided vehicle. Our team managed to design the electrical components of Delivery AGV, build ordering app for buyers and monitor GUI for shop-owners, automate the vehicle's journey.
- **Result:** Our project earned an acceptance certificate at the end of the program.

## HONORS AND AWARDS

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### **Certificate of Merit**

Jan 2021

For outstanding research achievements in 2019 – 2020 academic year, signed by Principal of University of Technology, VNU-HCM.

### **City Excellent Student**

April 2016

Second prize of the Excellent Student in English, organized by the Department of Education Training, Ho Chi Minh City, Vietnam.

## SKILLS

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**Maths:** Linear Algebra, Probability, Differential Equation, Vector Calculus, Calculus of Variations, Fourier Analysis, Numerical Analysis, Complex Analysis, Differential Geometry.

**Language:** C++/C, Matlab, Python, QML.

**Framework:** ROS2, ROS, Gazebo, Matlab/Simulink, Qt, g2o, MAVSDK.