

# Jiadong Lu

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## EDUCATION

**Zhejiang University** | Advisor: [Chao Xu](#), [YanJun Cao](#) 2024 – Present  
*Master in Control Science and Engineering*

**Shandong University** 2020 – 2024  
*Bachelor in Control Science and Engineering*

- GPA: 4.0/4.0 (**Rank: 2/28**)
- Data Structure (99), Fundamentals of Mechanical Engineering (99), Artificial Intelligence Technology Practice (99), Introduction to Artificial Intelligence (99), Machine Learning (99), University Physics (95), Image Processing and Computer Vision (95), Probability Theory (92), Automatic Control Theory (92).
- Thesis: Research on Reconfigurable Tracked Robot System (**Outstanding Undergraduate Thesis**)

## PUBLICATIONS († for equal contribution)

- [1] **Jiadong Lu**†, Zhehan Li†, Tao Han, Chao Xu, Fei Gao, and Yanjun Cao, "Continuous-Time Relative-Inertial-Odometry with Enhanced Clamped Non-Uniform B-spline," IEEE Transactions on Automation Science and Engineering (**In preparation**)
- [2] Chice Xuan†, **Jiadong Lu**†, Zhihao Tian, Jiacheng Li, Mengke Zhang, Hanbin Xie, Jianxiong Qiu, Chao Xu, and Yanjun Cao, "Novel Design of Reconfigurable Tracked Robot with Geometry-Changing Tracks," IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), 2024. (**Oral Presentation**)
- [3] Zhehan Li, Zheng Wang, **Jiadong Lu**, Zhiren Xun, Chao Xu, Fei Gao, and Yanjun Cao, "Hierarchical Cooperative Relative Localization via Closed-Form Solutions and Relative Kinematics," IEEE Transactions on Robotics. (**Submitted**)
- [4] Si Wang, Zhehan Li, **Jiadong Lu**, Rong Xiong, Yanjun Cao, Yue Wang, "Mr. Virgil: Learning Multi-robot Visual-range Relative Localization," IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), 2025. (**Oral Presentation**)

## PROJECT EXPERIENCE

**Air-Ground Cooperation without Global Information: RoFly and CubeTrack** Zhejiang, China  
**Cooperation with CREPES and CoNi-MPC**  
*IROS 2025 EXPO* | Team Leader 2025

- Present a live demo showcasing the autonomous collaboration between RoFly, an amphibious quadrotor, and CubeTrack [3], a reconfigurable tracked vehicle. The system is enabled by CREPES [1, 4, 5] for relative localization and by non-inertial MPC [2] for control in the non-inertial frame.
- Primary responsibility for the relative localization, and the control modules.

## AWARDS

**Presidential Scholarship Finalist** of Shandong University (1 %) 2023  
**The First Prize** of Nation College Student Intelligent Car Competition (5 %) 2022  
**The Second Prize** of Nation College Student Intelligent Car Competition (10 %) 2021  
**Advanced Individual in Innovation** of Shandong University (5 %) 2023  
**The First Prize Scholarship** of Shandong University (5 %) 2022 & 2023

## SKILLS

**Programming:** C++ (5+ years), C (5+ years), Python (5+ years), ROS (3+ years), MATLAB (4+ years).  
**Language:** English - Full professional proficiency | Chinese - Native.  
**Software & Hardware Development:** Linux, ROS, Gazebo, Git, Docker, SolidWorks, Fusion.