NIU Xuezhi

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Uppsala, Sweden

EDUCATION

- **Uppsala University**
  Ph.D. Student in Embedded Systems

  2024–present
  Uppsala, Sweden

- **KTH Royal Institute of Technology**
  M.Sc. Mechatronics

  2021–2023
  Stockholm, Sweden

- **City University of Hong Kong**
  B.Eng. Mechanical Engineering

  2017–2021
  Hong Kong SAR, China

- **National University of Singapore**
  Academic Exchange

  2020
  Singapore

RESEARCH INTERESTS

- Cyber-Physical Systems
- Control & Dynamics
- Reinforcement Learning

JOURNAL PUBLICATIONS

- Tan,K., **Niu, X.**, Q. Ji, L. Feng, and M. Törngren, "Optimal gait design for a soft quadruped robot via multi-fidelity Bayesian optimization," *Applied Soft Computing*, vol. 169, p. 112568, 2025.

CONFERENCE PUBLICATIONS

- **Niu, X.**, Tan, K., & Feng, L.. Optimal Gait Control for a Tendon-driven Soft Quadruped Robot by Model-based Reinforcement Learning. In *2025 International Conference on Robotics and Automation (ICRA)*. IEEE

OTHER PUBLICATIONS

- Maser Thesis: Xuezhi, N. (2023). Optimal Gait Control of Soft Quadruped Robot by Model-based Reinforcement Learning. Thesis, 2023. Available: DiVA, id: diva2:1810127.

- HK project: C. Egenäs, F. Ekman, C. Ma, T. Naser, **X. Niu**, A. Sernelin, S. Stenow, and B. Ström, "Electronically Vacuum Regulated Shut-off Valve for Milking System," Report (Refereed), 2023. [Online]. Available: DiVA, id: diva2:1738909.

PROFESSIONAL SERVICE

- Reviewer for IEEE-RAS International Conference on Humanoid Robots (Humanoids), IEEE International Conference on Industrial Cyber-Physical Systems (ICPS)

- Teaching assistant for master level courses at KTH (MF2007) and Uppsala (1DT106, 1DT108, 1DT054, 1RT495, 1DT104)

AWARDS & ACHIEVEMENTS

- Talent Development Scholarship, Hong Kong SAR, China — *2020.6*
- Second Prize in National Finals of the Challenge Cup Competition, Beijing, China — *2019.11*
- Silver Prize in National Finals of Internet + Competition, Hangzhou, China — *2019.10*
- Second Prize in HK University Student Innovation and Entrepreneurship Competition — *2019.4*