

# Wei-Hsuan Cheng

📍 Taipei, Taiwan    ✉ johnnathancheng0125@gmail.com / ✉ r11631045@ntu.edu.tw    in Wei-Hsuan Cheng  
🔗 wei-hsuan-cheng

## Education

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### National Taiwan University (NTU)

(Expected) Spring 2025

Master in Biomechatronics Engineering

- Overall GPA: 4.12/4.3
- Scholarships: 2023 Master Student Scholarship (First Place) from Dept. Biomechatronics Engineering, NTU
- Coursework:** Robotics, Optimal Control, Stochastic Control, Robust Control, System Identification, Linear Systems
- Master Thesis:** Application of Vision- and Force-Based Supervisory Teleoperation for Robotic Dexterous Manipulation Tasks in Industrial Surveillance

### National Tsing Hua University (NTHU)

June 2022

Bachelor in Interdisciplinary Programme of Nuclear Science (IPNS)

- Specialising in Energy Engineering and Power Mechanical Engineering.

## Skills

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**Programming:** C++, Python, MATLAB, JavaScript, LaTeX

**Robotics Research Interests:** Motion Planning and Control, Kalman Filtering, Computer Vision, Vision- and Force-based Control, Application of Conformal Geometric Algebra (CGA) in Robotics

**Software/Hardware/Tools:** ROS 1 & 2, MoveIt2!, PCL, PyQt5, Git, Docker, SolidWorks, Fusion 360, Nvidia Jetson, STM32 MCU

## Research Experience

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### Delta-NTU Joint Research & Development Centre [🔗](#)

Taipei, Taiwan

Project leader in the collaboration research project of NTU and the CTO Office in Delta Electronics, Inc.

Dec 2023 – Present

### Supervisory Teleoperation of Manipulator for Surveillance

- Develop a supervisory tele-manipulation system for industrial surveillance, with hierarchical-autonomy-level structure (teleop-supervised-autonomous). A human-robot interface (HRI) is designed for the operator to teleoperate remote robot via wireless communication and perform dexterous manipulation tasks in industrial surveillance scenario (e.g. buttons, switches, and valves operations).
- Apply both vision- and force-based control strategies for robotic arm dexterous manipulation tasks (preparing for Master thesis and submitting to **RA-L** journal).

### Robots and Medical Mechatronics Lab (RMML) [🔗](#)

Taipei, Taiwan

Master student researcher, advised by Prof. Ping-Lang Yen

Sept 2022 – Present

### Project Experiences and Contributions

- Agricultural Robot:
  - Improve EKF-SLAM for agricultural tracked mobile robot by involving IMU bias estimation and on-line state covariance update.
  - Apply vision-based control scheme and object 6D pose estimation for robotic tomato harvesting.
- Surgical Robot:
  - Improve attitude and angular velocity estimation, and the visual servo control scheme for surgical robot end-effector using multi-sensor fusion and a quaternion-based EKF.

## Selected Projects

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### Attitude and Angular Velocity Estimation of Surgical Robot Using Sensor Fusion with Optical Tracker, IMU, and Quaternion-based Extended Kalman Filter

 [kf.cpp](#), May 2023

- A multi-sensor fusion framework is used for estimating the attitude and angular velocity of surgical robot end-effector, for better robustness (against occlusions) and tracking precision in minimally invasive surgeries.
- An quaternion-based EKF algorithm is derived based on a constant angular velocity model.
- The EKF algorithm is simulated in MATLAB and implemented in ROS 2 C++.

### Kendo Robot- Combining Robotics Technologies with Martial Art

 [kendo\\_robot](#), Dec 2023

- A supervisory teleoperation kendo robot system. The robotic arm holding kendo sword tracks the opponent's pose and wait for the operator's command to attack on different body positions.
- Detect and track the 3D human body by DL-based real-time human pose estimation algorithm and RGB-D alignment. An interactive GUI is built using JavaScript for real-time visualisation and robotic motion planning.
- Robotic arm IK solver and sword motion planner are designed based on a new mathematical framework, conformal geometric algebra (CGA).
- Developed using ROS 1 Python, and a web-based interactive GUI using JavaScript. ROS-JavaScript communication through web socket.

### CGA IK- Closed-Form Inverse Kinematics Solver based on CGA

 [cga\\_ik](#), Nov 2023

- Aim to promote a new mathematical framework **conformal geometric algebra (CGA)** for robotics applications.
- Implement a closed-form IK solver for 6-DoF collaborative robots based on CGA.
- Simulated and visualised in a web-based interactive GUI using JavaScript. Implemented in ROS 2 Python and tested on a real robot.

### Furuta Pendulum Balancing Control and Disturbance Rejection via State-Observer Feedback and Internal Model Design

Dec 2022

- Stabilise the Furuta pendulum system by the design of state-observer feedback controller. An internal model is utilised to reject the sinusoidal process noise in the input signal of maxon motor.
- Course project of EE5128 Linear Systems @ NTU EE. System dynamics and control algorithm are simulated in Simulink, Simscape, and MATLAB.

## Teaching Assistants (TAs)

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### Engineering Mathematics (I)

Autumn 2022

### Introduction to Foreign Literature on Bio-Systems Engineering

Autumn 2022

## Awards

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**Robotics Competition Winner (Kendo Robot)** as a team leader in the course project of CSIE5074 Robotics, offered by Prof. Li-Chen Fu @ NTU EE.

Dec 2023