



Shuangquan Zou

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Education

2014.09-2018.06	Shenyang Jianzhu University	Automation	Bachelor
GPA: 91.71/100 Ranking: 1/132 for consecutive seven semesters Obtained the only recommended postgraduate quota for the entire major Recommended postgraduate offer: <input type="checkbox"/> Tongji University <input type="checkbox"/> Tianjin University <input type="checkbox"/> Northeastern University <input checked="" type="checkbox"/> Harbin Institute of Technology			
2018.09-2020.06	Harbin Institute of Technology (HIT)	Control Engineering	Master
GPA: 87.98/100 Ranking: 3/40 Obtained the recommended doctorate quota			
2020.09-present	HIT	Control Science and Engineering	Ph.D candidate
2023.02-2024.08	National University of Singapore	Mechanical Engineering	Exchange Ph.D

Awards

Ph.D:

Engineering Fund (2020-2024)
CAI 613 Institute Scholarship (2022)

China Scholarship Council Funding (18 months)

Master:

National Scholarship (2019)
School Merit Student (2020)

Outstanding Graduates Awards (2020)
The First Prize Scholarship (2020)

Bachelor:

National Scholarship (2016)
Provincial Government Scholarship (2015)
Mayor Scholarship (2017)
The First Prize Scholarship*7 (2014-2018)
Academic Excellence Scholarship*7 (2014-2018)
Excellent Graduation Thesis (2018)

China Telecom Scholarship (2018)
Provincial Outstanding Graduates Awards (2018)
Presidential Scholarship*2 (2016, 2017)
School Outstanding Graduates Awards (2018)
School Merit Student (2015)
Volunteer Advanced Individual (2015)

Publications

- Zou S**, Lv Y*, Qi J, et al. A deep neural network approach for accurate 3D shape estimation of soft manipulator with vision correction [J]//SENSORS AND ACTUATORS A-PHYSICAL, 2022:113692. (SCI)
- Zou S**, Lv Y*, Guan Q, et al. A real-time 3D centerline estimation framework for multi-section soft manipulator based on stereo vision [J]//Control Engineering and Applied Informatics, 2022, 24(2):46-56. (SCI)
- 邹双全**, 吕跃勇*, 管清华, 刘立武, 马广富. 基于 SOM 算法的软体机械臂三维形状实时感知[J]//哈尔滨工业大学学报. (EI, Accepted)
Zou S, Lv Y*, Guan Q, et al. Real-time 3D shape recognition for soft manipulator based on SOM algorithm [J]//Journal of Harbin Institute of Technology. (EI, Accepted)
- Lv Y*, **Zou S**, Meng F, et al. A shape detection system and method for soft manipulator [P] CN109955234b, 2021-06-15. (China Invention Patent)
- Zou S**, Lv Y*, Man Y, et al. Design and implement of shape detection for the soft manipulator[C]//2020 39th Chinese Control Conference (CCC). IEEE, 2020: 3972-3977. (EI)
- Zou S**, Lv Y*, Zhao L, et al. A novel shape detection method for continuum soft manipulator based on cable encoders[C]//2019 Chinese Control Conference (CCC). IEEE, 2019: 4709-4714. (EI)
- Zou S**, Yan H, Zhang L. Reliable Static Output Feedback Guaranteed Cost Control for Uncertain Systems with Time-Delay[C]//Chinese Intelligent Automation Conference. Springer, Singapore, 2017: 407-413. (EI)

Research Experiences

1. Project: Design and manufacture of the prototype

Student Leader

Supervisor: Prof. Guangfu Ma (Group Leader)

09.2018-2019.06

- Investigated the materials and components required for the prototype of the soft manipulator, and the following materials were finally determined through referenced paper and numerous performance testing experiments.
- Built the entire experimental platform, including the pneumatic platform and the electronic control platform, and the selection and debugging of each equipment is the basis for the following research work.
- Learned the SOLIDWORKS to draw the draft of the baseplate, rigid frame and other components for the prototype, and printed them out with 3D printing technology, so that I can repair and adjust the components by myself in the future

2. Project: Constant curvature 3D shape estimation based on joint information

Student Leader

Supervisor: Prof. Guangfu Ma (Group Leader)

09.2019-06.2020

- Proposed a novel method to detect the 3D shape of soft continuum manipulator based on constant curvature model
- Established a distributed sensor network and programmed STM32 to read the sensor data and transmit it to the workstation through wireless Bluetooth module. (Keil)
- Set the serial communication in the simulation environment, and developed the piecewise constant curvature kinematics model. The 3D shape of the soft manipulator is solved through the received joint data. (MATLAB)
- Extended the kinematic model to the multi-section soft manipulator, and performed the shape detection experiment.

3. Project: Real-time 3D shape reconstruction using machine vision

Student Leader

Supervisor: Prof. Guangfu Ma & Prof. Jinsong Leng

09.2020-06.2021

- Proposed a high-precision 3D shape estimation for soft manipulator using vision
- Built a program frame for the ZED camera to read real-time image data in Pycharm, and programmed the machine vision algorithm for preprocessing (including HSV conversion, binarization, filtering and morphological processing) and completed the contour extraction. (OpenCV, Python)
- Used SOM algorithm to cluster the 2D centerline of the extracted contour data. Compared with other machine learning algorithms (such as K++ means algorithm, competitive learning algorithm) and thinning algorithm, the experiments showed that SOM algorithm is more suitable for this research work.
- Proposed a numerical method to reconstruct the centerline, and the accuracy and verified real-time performance of the whole framework

4. Project: A deep neural network approach for accurate 3D shape estimation with vision correction

Student Leader

Supervisor: Prof. Guangfu Ma

09.2021-01.2022

- Proposed a DNN approach to accurately estimate the 3D shape of the soft manipulator in real time, which integrates traditional sensing, machine vision, and deep learning.
- Conducted experiments to analyze that the constant curvature kinematics method can only roughly estimate the shape of the soft manipulator, while the visual detection method is too sensitive to the environment and self-occlusion.
- Created a dataset through extensive experiments and trained a deep neural network to construct a nonlinear relationship between joint information and visual center points. (Pytorch)
- Conducted the error evaluation for the trained DNN on the test set, and performed a real-time bending deformation experiment to suggest the DNN approach can accurately measure 3D shape for soft manipulator via length information in real time.

5. Project: Design and closed-loop experimental verification of a single-variable control algorithm

Student Leader

Supervisor: Prof. Guangfu Ma (Group Leader)

03.2022-present

- Proposed a data-driven control algorithm to control the bending angle of the soft manipulator through the design of a single variable controller.
- Used the vision sensor to obtain the end position in real time, and adopted the inverse kinematics model to solve the current bending angle, which forms an error with the expected bending angle, and further drives the controller to change the air pressure value.
- Designed PID and model free adaptive controllers (MFAC), which do not depend on the accurate system model. Its effectiveness is verified by closed-loop experimental control to the desired angle.

Honor

1. **Grand Prize**
Siemens Cup China Intelligent Manufacturing Challenge Preliminary
Shanghai, China
06.2017
2. **Second Prize**
Siemens Cup China Intelligent Manufacturing Challenge Final
Shanghai, China
08.2017
3. **Honorable Mention**
Mathematical Contest In Modeling (MCM)
Shenyang, China
02,2017
4. **First Prize**
The Chinese Mathematics Competitions (CMC)
Shenyang, China
12,2016
5. **Third Prize**
Contemporary Undergraduate Mathematical Contest in Modeling
Shenyang, China
11,2015
6. **Gold Prize**
China College Students' 'Internet+'Innovation and Entrepreneurship Competition
Shenyang, China
09, 2016

Personal Experiences

1. Student representative speech for undergraduate graduation ceremony
Shenyang, China
07.2018
2. Weekly volunteer for the orphanage
Harbin, China
04.2015-2017.07
3. Oral presentation for the 38th China Control Conference
Guangzhou, China
07.27.2019-07.30.2019
4. Oral presentation for the 39th China Control Conference online
Shenyang, China
07.27.2020-07.29.2020
5. Oral presentation for the 7th "Soft Robot Theory and Technology" seminar
Weihai, China
10.29.2021-10.31.2021
6. 2023 6th IEEE International Conference on Soft robotics
Singapore
04.03.2023-04.07.2023
7. 2023 19th IEEE International Conference on Automation Science and Engineering
Auckland, New Zealand
08.26.2023-08.30.2023