Zhaoze Wang

Master Student

Geburtsdatum: 14. Juli 1997
Geburtsort: Liaoning

Kontakt

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Westermkötter Straße 3
59557 Lippstadt,
Deutschland

Führerschein

- B

Fähigkeiten

- Python
- PyTorch
- ROS
- Git
- Docker
- MATLAB
- C++

Sprachen

Chinesisch - Muttersprache
Deutsch - Sehr gute Kenntnisse
Englisch - Sehr gute Kenntnisse

Berufserfahrung

RESEARCH INTERN
Juli 2024 - heute

FORVIA HELLA - Lippstadt, Germany

- Improvement of FMCW Radar Simulation with Generative AI
- Development of 3D Ray Tracing and Radar Signal Processing with CUDA

MASTER THESIS STUDENT
November 2023 - Mai 2024

Bosch Center for Artificial Intelligence - Stuttgart

Title: Self-supervised Dense Visual Descriptor Learning for Scene Understanding in Mobile Robots
- Grade: 1.3 / 1.0
- Development of Instance- and Category-level 3D Object Detection
- Results Evaluation on the ScanNet Dataset

RESEARCH INTERN
Mai 2023 - Oktober 2023

Bosch Center for Artificial Intelligence - Stuttgart

- Improvement of existing Implementations such as Geometric Correspondence
- Training Dense Object Nets for Key-Point Tracking and 6-DoF Pose Estimation.

STUDENT RESEARCH ASSISTANT
Oktober 2022 - April 2023

FAU-Institute of Microwaves and Photonics - Erlangen

- Cross-modal & Multi-task Learning with GNSS and Automotive Radar
- Road Area Segmentation and Path Planning
- Published by IEEE Robotics and Automation Letters (RA-L)

Bildungsweg

MASTER
2023

Friedrich-Alexander Universität Erlangen-Nürnberg, Mechatronics and Robotics - Erlangen

Master of Science : Mechatronics and Robotics
Field of Research : Computer Vision, Multi-Modal Learning, SLAM
Final Note of Degree : 1.8

BACHELOR
2020

Harbin Engineering University, Mechanical Engineering - Harbin, China

Bachelor of Science Mechanical Engineering
Note of Degree : 2.4

Publication

- Title: Cross-modal Supervision based Road Segmentation and Trajectory Prediction with Automotive Radar
- Accepted by IEEE Robotics and Automation Letters (RA-L) on July 22nd, 2024.

Practical Experience

Mobile Robots & SLAM
- State Estimation based on Sensor Fusion e.g. Kalman Filter and Particle Filter
- Fast-SLAM Algorithm Implementation on Webot Simulator
- Demo: https://github.com/Wangzhaoze/UTN_Mobile_Robotics

Human-Robot-Interaction
- Forward / Inverse Kinematics, Adaptive Control, Impedance control
- Experiment on Franka Emika Panda for target grasping