

# Haoying (Jack) Zhou

Robotics Engineer (Systems, Software, Simulation, Control) | Research/Applied Scientist | Robotics PhD Candidate  
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## SUMMARY

Final-year PhD candidate (**Expected to graduate in May 2026**) in Robotics Engineering, specializing in surgical robotics (**dVRK, the da Vinci Research Kit**), with a strong background in long-horizon R&D: from **robot infrastructure development, robot system identification and system integration to simulation, multi-modal data collection & analysis and AI-driven perception & automation**. Practical robotic problem solver for both hardware and software. Open to relocation inside the U.S.. Target for **Full-Time positions starting May/June 2026**. Require F1-OPT/H-1B or equivalent visa sponsorship.

## TECHNICAL SKILLS

**Programming Languages:** Python, MATLAB, C/C++, Bash/Shell

**Simulation & Visualization:** AMBF (Bullet Physics), Blender, Gazebo/RViz, 3D Slicer, V-REP, NVIDIA Isaac Sim, Simulink, Ansys FEA

**Robotics:** ROS/ROS2, model-based robotics (kinematics/dynamics/control), system identification, teleoperation, calibration

**Platform & Infrastructure:** dVRK Classic/Si (5+ YoE), Linux, Git, Image pipeline (v4l2, udev), PyQt, CMake/catkin/colcon, Docker

**Machine Learning & AI:** PyTorch, OpenCV, Computer Vision, Deep Learning, Imitation Learning

**Design & Manufacturing:** Rapid Prototyping, SolidWorks, 3D Printing, Machine Shop, AutoCAD

## EDUCATION

### Worcester Polytechnic Institute

*Ph.D. in Robotics Engineering, GPA: 3.95/4.0*

• Additional Training: Laboratory Animal Surgery, IRB, Radiation and MRI safety certified

Worcester, MA

Sep 2020 – May 2026 (Expected)

### Boston University

*M.S. in Mechanical Engineering, GPA: 3.78/4.0*

Boston, MA

Sep 2018 – May 2020

### University of California, Berkeley

*Senior-year Visiting Undergraduate Student in Mechanical Engineering, GPA 3.95/4.0*

Berkeley, CA

Aug 2017 – May 2018

### Beijing Institute of Technology

*B.S. in Mechanical Engineering*

Beijing, China

Sep 2014 – May 2018

## PROFESSIONAL EXPERIENCE

### Visiting Graduate Scholar

*Johns Hopkins University*

June 2023 – Present

Baltimore, MD

- Develop infrastructures to be shared with the dVRK community
- Develop high-fidelity simulation environments for NSF AccelNet Surgical Robotics Challenges in AMBF simulator and NVIDIA Omniverse Isaac Sim, utilized by 50+ international participants.
- Conduct advanced AI research utilizing the physical dVRK and simulation environments for surgical robotics applications
- Led International Conference Workshop live demonstrations in 2024 ISMR

### Image-Guided Therapy Robotics Intern

*Philips Research North America*

May 2022 – Aug 2022

Cambridge, MA

- Developed robot motion simulator using DICOM and PyQt5, improving refreshing frequency by 30 times
- Integrated the Xbox game controller as an alternative control input, enabling teleoperation testing

## SELECTED RESEARCH PROJECTS

### Multi-Modal Data Collection and Preprocessing Framework

Sep 2024 – Present

*Johns Hopkins University*

- Lead and manage 8-person cross-functional team building time-synchronized multi-modal data collection and preprocessing pipeline, delivering IRB-compliant data collection and analysis (1000+ ex-vivo trajectories to NVIDIA Open-H-Embodiment effort)

- Lead and mentor development of multi-threaded C++ synchronized recorders, integrating stereo endoscopy, side-view video, custom sensors and robotic kinematics across 20+ ROS topics within millisecond-level time synchronization
- Design and implement a custom capacitive contact sensor using Arduino to acquire the ground truth of tool-tissue contact
- Integrate a modern chip-on-tip endoscope with dVRK-Si, enabling seamless teleoperation and high-quality image data acquisition
- Develop PyQt5 annotation tool, kinematic reprojection pipeline using hand-eye calibration and AI-driven preprocessing framework (FoundationStereo, RAFT, SAM2), generating high-level features for AI applications
- Employ invisible UV-fluorescent paints for key-point ground truth annotation

### **Surgical Robot Dynamic Model Identification and Control**

Nov 2022 – Present

*Johns Hopkins University*

- Develop a novel hybrid force estimation method for the dVRK Patient Side Manipulator (PSM) under trocar interaction combining the model-based approach and the learning-based approaches, reducing the estimation errors by 30%
- Implement gravity compensation based on dynamic model identification of dVRK-Si Patient Side Manipulator (PSM) using convex optimization approaches in Python, reducing the static control errors by 73%
- Design and implement PID control, feedforward compensation, and model-based control using Lagrangian dynamics with SymPy symbolic computation and CVXPY & pyOpt convex optimization on the physical dVRK-Si PSM

### **Digital Twin for Suturing Scenes**

Feb 2022 – Present

*Johns Hopkins University*

- Develop high-fidelity environments with realistic dynamic feedback for suturing execution on an open-source 3D simulation platform (AMBF), utilized for NSF AccelNet Surgical Robotics Challenges and policy training data collection & benchmarking
- Scan the real-world suturing training phantoms using MRI and import the segmented 3D models into the simulation environment
- Build photorealistic dVRK surgical instrument simulation models from CADs, sharing the models with the dVRK community
- Construct high-fidelity digital twin for suturing scenes in NVIDIA Omniverse Isaac Sim

### **AI-driven Perception and Automation Application in Digital Twin**

Sep 2021 – Jun 2025

*Johns Hopkins University*

- Implement imitation learning algorithms for suturing automation in simulation, achieving 95% success rate for task completion, task generality on the order of 91.5% and 20% less task execution time
- Develop a novel pipeline for synchronized data collection and conduct user study for human demonstration acquisition on the digital twin (simulation) using the physical dVRK Master Tool Manipulator (MTM) as the teleoperation interface
- Develop a novel deep learning approach for real-time markerless suturing needle 6D pose estimation in simulation, achieving average errors of 1.4 mm and 2.9 degrees

### **Surgical Robot Infrastructure Development**

Mar 2021 – Present

*Research Technician*

*Worcester Polytechnic Institute*

- Brought a full da Vinci Surgical System from non-functional state to operational using the dVRK controllers, performing calibration & validation procedures, configuring dVRK controllers and enabling full teleoperation capability
- Diagnosed and resolved critical system failures (encoder malfunction, brake defects) through systematic investigation (failure mode analysis); determined root cause, proposed design improvements, and provided feasible solutions
- Owned a novel approach for surgical instrument lubrication and instrument internal cable tension recovery
- Developed a replacement solution for the dVRK viewer console monitors and re-enabled the height adjustment linear actuator
- Developed the video pipeline for endoscope image stacks using Video for Linux v2 drivers, sharing with the dVRK community

### **Surgical Robotics System Integration**

Jan 2022 – Jun 2025

*Worcester Polytechnic Institute*

- Integrated custom sensors (sEMG electrodes, haptic devices) or customized end-effectors (photo-acoustic probe) with servo control algorithm and teleoperation systems for dVRK PSM
- Developed the synchronized autonomous scanning system using ROS communication for photo-acoustic probe image overlay
- Enabled teleoperation for dVRK PSMs with multiple common haptic devices, such as Phantom Omni and Razer Hydra controller, which were subsequently utilized in a dVRK-based AR measurement system

### **Point Cloud Completion**

May 2023 – Feb 2024

*Worcester Polytechnic Institute*

- Proposed a novel chamfer distance loss function for point cloud completion task
- Achieved new state-of-the-art results on some benchmark dataset

### **Lower-Limb Exoskeleton Walking Strategy Learning**

Sep 2020 – Mar 2021

*Worcester Polytechnic Institute*

- Developed an automated walking strategy for lower-limb exoskeleton in simulation using imitation learning approach
- Implemented Iterative Linear Quadratic Regulator to find the optimal weight matrix for control

### **Reaching-to-Grasping Task Automation with Robot Learning**

Oct 2018 – May 2020

*Boston University*

- Developed an automation algorithm for reaching-to-grasping task in V-REP simulation using imitation learning approach
- Leveraged joystick for the Baxter Robot end-effector control and human demonstration data collection

## SELECTED COURSE PROJECTS

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<b>Visual Inertial Odometry with Multi-Scale Constraint Kalman Filter</b>	Worcester Polytechnic Institute
<b>FaceSwap and Neural Radiance Fields (NeRF) Implementation</b>	Worcester Polytechnic Institute
<b>Adaptive Robustness Control Design for UAV with ROS Gazebo</b>	Worcester Polytechnic Institute
<b>Laboratory Animal Surgery</b>	Worcester Polytechnic Institute
<b>Autonomous Racing Car Dynamic and Control Design</b>	University of California, Berkeley
<b>Real-Time Bubble Recognition</b>	University of California, Berkeley
<b>Object Tracking Mechatronics System Design and Manufacturing</b>	University of California, Berkeley

## PUBLICATIONS

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1. **Zhou, H.**\*, Liu, C. \*, Wu, Y., ..., & Kazanzides, P. (2026, under review). "SurgSync: Time-Synchronized Multi-modal Data Collection Framework and Dataset for Surgical Robotics." In *IEEE Intl. Conf. on Robotics and Automation (ICRA)*.
2. **Zhou, H.**, Yang, H., Deguet, A., ..., & Kazanzides, P. (2025). "Gravity Compensation of the dVRK-Si Patient Side Manipulator based on Dynamic Model Identification." In *Hamlyn Symp. on Medical Robotics (Oral)*.
3. Yang, H., **Zhou, H.**, Fischer, G. S., & Wu, J. Y. (2024). "A Hybrid Model and Learning-Based Force Estimation Framework for Surgical Robots." In *IEEE/RSJ Intl. Conf. on Intelligent Robots and Systems (IROS)*.
4. **Zhou, H.**, Jiang, Y., Gao, S., ..., & Fischer, G. S. (2024). "Suturing Tasks Automation Based on Skills Learned From Demonstrations: A Simulation Study." In *Intl. Symp. on Medical Robotics (ISMR)*, IEEE.
5. Wu, J., **Zhou, H.**, Kazanzides, P., Munawar, A., & Liu, A. (2024). "SurgicAI: A Hierarchical Platform for Fine-Grained Surgical Policy Learning and Benchmarking." In *Conf. on Neural Information Processing Systems (NeurIPS) Datasets and Benchmarks Track*.
6. Lin, F. \*, Liu, H. \*, **Zhou, H.** \*, Hou, S. \*, Yamada, K. D., ... & Zhang, Z. (2024). "Loss Distillation via Gradient Matching for Point Cloud Completion with Weighted Chamfer Distance." In *IEEE/RSJ Intl. Conf. on Intelligent Robots and Systems (IROS)*.
7. Kim, T. W., **Zhou, H.**, Barragan, J. A., ..., & Munawar, A. (2026). "Robot-Assisted Suturing in Surgical Simulation: A Comparative Analysis between NVIDIA's Simulator and an Open Platform." In *Journal of Medical Robotics Research*
8. Kim, T. W., **Zhou, H.**, Barragan, J. A., ..., & Munawar, A. (2025). "Surgical Robotics Environment in NVIDIA Isaac Sim for Robot-Assisted Suturing." In *Intl. Symp. on Medical Robotics (ISMR)*, IEEE.
9. Allison, C. J., **Zhou, H.**, Munawar, A., Kazanzides, P., & Barragan, J. A. (2024). "FIRE-3DV: Framework-Independent Rendering Engine for 3D Graphics Using Vulkan." In *IEEE Intl. Conf. on Robotic Computing (IRC)*.
10. Barragan, J. A., Zhang, J., **Zhou, H.**, Munawar, A., & Kazanzides, P. (2024). "Realistic Data Generation for 6D Pose Estimation of Surgical Instruments." In *IEEE Intl. Conf. on Robotics and Automation (ICRA)*.
11. Jiang, Y., **Zhou, H.**, & Fischer, G. S. (2023). "Development and Evaluation of a Markerless 6 DOF Pose Tracking Method for a Suture Needle from a Robotic Endoscope." *Journal of Medical Robotics Research*.
12. Jiang, Y., **Zhou, H.**, & Fischer, G. S. (2023). "Markerless suture needle tracking from a robotic endoscope based on deep learning." In *Intl. Symp. on Medical Robotics (ISMR)*, IEEE.
13. Wu, Z., Schmidt, A., Moore, R., **Zhou, H.**, ..., & Salcudean, S. E. (2025). "SurgPose: a Dataset for Articulated Robotic Surgical Tool Pose Estimation and Tracking." In *IEEE Intl. Conf. on Robotics and Automation (ICRA)*.
14. Yang, K., Meier, T. B., **Zhou, H.**, Fischer, G. S., & Nycz, C. J. (2022). "A sEMG Proportional Control for the Gripper of Patient Side Manipulator in da Vinci Surgical System." In *Intl. Conf. of the IEEE Engineering in Medicine & Biology Society (EMBC)*
15. Gao, S., Wang, Y., Ma, X., **Zhou, H.**, Jiang, Y., Yang, K., ... & Zhang, H. K. (2023). "Intraoperative laparoscopic photoacoustic image guidance system in the da Vinci surgical system." *Biomedical optics express*.
16. Gao, S., Wang, Y., **Zhou, H.**, Yang, K., Jiang, Y., Lu, L., ... & Zhang, H. K. (2023). "Laparoscopic photoacoustic imaging system integrated with the da Vinci surgical system." In *Medical Imaging: Image-Guided Procedures, Robotic Interventions, and Modeling*, SPIE.
17. Wang, S. \*, Wang, J.F. \*, Koh, Y. \*, **Zhou, H.**, ..., & Kazanzides, P. (2025). "An Augmented Reality Measurement Tool for the da Vinci Research Kit." In *Intl. Symp. on Medical Robotics (ISMR)*, IEEE.
18. Goldfarb, N., **Zhou, H.**, Bales, C., & Fischer, G. S. (2021). "Control of a lower limb exoskeleton using Learning from Demonstration and an iterative Linear Quadratic Regulator Controller: A simulation study." In *Intl. Conf. of the IEEE Engineering in Medicine & Biology Society (EMBC)*.

## **AWARD & CERTIFICATIONS**

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- Dr. Glenn Yee Graduate Student Tuition Award - Worcester Polytechnic Institute, Fall 2024, Spring 2025 and Spring 2026
- Dr. Glenn Yee Graduate Student Travel Award - Worcester Polytechnic Institute, Spring 2024
- CITI Program Training - Social & Behavioral Research- Johns Hopkins University
- CITI Program Training - Human Subjects in Biomedical Research - Worcester Polytechnic Institute
- Radiation Safety Training - Johns Hopkins University, Worcester Polytechnic Institute
- MRI Safety Training - Worcester Polytechnic Institute