ICAROB 2026

PROCEEDINGS OF THE 2026 INTERNATIONAL CONFERENCE ON ARTIFICIAL LIFE AND ROBOTICS

January 29 to February 1, 2026
B-Con Plaza, Beppu, Oita, JAPAN
31st AROB International Meeting Series

Editor-in-Chief
Takao Ito
Editors: Yingmin Jia, Ju-Jang Lee, Masanori Sugisaka
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Proceedings of The 2026 International Conference on

ARTIFICIAL LIFE AND ROBOTICS

(ICAROB2026)

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History

The International Conference on Artificial Life and Robotics (ICAROB) resulted from the AROB-symposium (International Symposium on Artificial Life and Robotics) whose first edition was held in 1996 and the eighteenth and last edition in 2013. The AROB symposium was annually organized by Oita University and ALife Robotics Corporation Ltd., under the sponsorship of the Science and Technology Policy Bureau, the Ministry of Education, Science, Sports, and Culture (Monbusho), presently, the Ministry of Education, Culture, Sports, Science, and Technology (Monkasho), Japanese Government, Japan Society for the Promotion of Science (JSPS), the Commemorative Organization for the Japan World Exposition ('70), Air Force Office of Scientific Research, Asian Office of Aerospace Research and Development (AFOSR/AOARD), USA. We would like to express our sincere thanks to not only Monkasho (annually fund support from 1996 to 2013) but also JSPS, the Commemorative Organization for the Japan World Exposition ('70), and various other Japanese companies for their repeated support. The old symposium (this symposium has been held every year at B-Con Plaza, Beppu, Oita, Japan except in Oita, Japan (AROB 5th ’00) and in Tokyo, Japan (AROB 6th ’01).) was organized by the International Organizing Committee of AROB and was co-operated by the Santa Fe Institute (USA), RSJ, IEEJ, ICASE (Now ICROS) (Korea), CAAI (P. R. China), ISCIE, IEICE, IEEE (Japan Council), JARA, and SICE. The old AROB-symposium expanded much by absorbing much new knowledge and technologies into it. This history and character of the former AROB symposiums are passed on the current ICAROB conference and to these journals, Journal of Robotics, Networking and Artificial Life (JRNAL)(vol1-8) & Journal of Robotics, Networking and Artificial Life (JRNAL)(vol9-) & Journal of Advances in Artificial Life Robotics (JAALR). From now on, the Society of Artificial Life and Robotics is in charge of management of both the conference and the journals. The future of the ICAROB is brilliant from a point of view of yielding new technologies to human society in the future modern society. We also expect to establish an international research institute on Artificial Life and Robotics in the future with the help of Japanese Government and ICAROB. This conference invites you all.

Aims and Scope

The objective of this conference is the development of new technologies for artificial life and robotics which have been recently born in the world and are expected to be applied in various fields. This conference presents original technical papers and authoritative state-of-the-art reviews on the development of new technologies concerning robotics, networking technology, artificial life and, especially computer-based simulation and hardware for the future modern society. This conference covers a broad multidisciplinary field, including areas such as:

Artificial intelligence & Complexity
Artificial living
Artificial mind research
Artificial nervous systems for robots
Artificial sciences
Bipedal robot
Brain science and computing
Chaos
Cognitive science
Computational Molecular biology
Computer graphics
Data mining
Disasters robotics
DNA computing
Empirical research on network and MOT
Environmental navigation and localization
Evolutionary computations
Facial expression analysis, music recommendation and augmented reality
Foundation of computation and its application
Fuzzy control
Genetic algorithms
Human-welfare robotics
Image processing
Insect-like aero vehicles
Intelligence in biological systems
Intelligent control
Management of technology
Medical surgical robot
Micro-machines
Multi-agent systems
Nano-biology
Nanorobotics
Networking
Neural circuits
Neurocomputer
Neuromorphic Systems
Neuroscience
Pattern recognition

Quantum computing
Reinforcement learning system & Genetic programing
Robotics
Software development support method
System cybernetics
Unmanned underwater vehicles
Unmanned Aerial Systems Technologies
Unmanned Aerial Systems design, controls and navigation
Unmanned Aero vehicles
Virtual reality
Visualization
Hardware-oriented submissions are particularly welcome. This conference will discuss new results in the field of artificial life and robotics.

Copyrights

Accepted papers will be published in the proceedings of the 2026 International Conference on Artificial Life and Robotics (ICAROB2026) by the Society of Artificial Life and Robotics. All copyrights of the published papers belong to the Society of Artificial Life and Robotics. Some of high-quality papers in the proceeding will be requested to re-submit their papers for the consideration of publication in Journal of Robotics, Networking and Artificial Life (JRNAL)(vol1-8) & Journal of Robotics, Networking and Artificial Life (JRNAL)(vol9-) & Journal of Advances in Artificial Life Robotics(JAALR) under agreement of both Editor-in-Chief Dr. Takao Ito and 3 reviewers. All correspondence related to the conference should be addressed to ICAROB Office.

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Messages

Masanori Sugisaka
Honorary General Chair
(President, ALife Robotics Corp., Ltd, Japan)

Masanori Sugisaka

Masanori Sugisaka

Honorary General Chair of ICAROB

It is my great honor to invite you all to The 2026 International Conference on Artificial Life and Robotics (ICAROB 2026) to be held at B-Con Plaza, Beppu, Oita, Japan, 2026. This Conference is changed as the old symposium from the first (1996) to the Eighteenth (2013) annually which were organized by Oita University and ALife Robotics Corporation Ltd. under the sponsorship of the Science and Technology Policy Bureau, the Ministry of Education, Science, Sports, and Culture (Monbusho), presently, the Ministry of Education, Culture, Sports, Science, and Technology (Monkasho), Japanese Government, Japan Society for the Promotion of Science (JSPS), The Commemorative Organization for the Japan World Exposition (’70), Air Force Office of Scientific Research, Asian Office of Aerospace Research and Development (AFOSR/AOARD), USA. I would like to express my sincere thanks to not only Monkasho (annually fund support from 1996 to 2013) but also JSPS, the Commemorative Organization for the Japan World Exposition (’70), Japanese companies for their repeated support.
The old symposium was organized by International Organizing Committee of AROB and was co-operated by the Santa Fe Institute (USA), RSJ, IEEJ, ICASE (Now ICROS) (Korea), CAAI (P. R. China), ISCIE, IEICE, IEEE (Japan Council), JARA, and SICE. The old AROB symposium was growing up by absorbing many new knowledge and technologies into it. This history and character was inherited also from ICAROB2014(The 2014 International Conference on Artificial Life and Robotics, included a series of ICAROB proceedings indexed by SCOPUS and CPCI-Web of Science now. This year we have The 2026 International Conference on Artificial Life and Robotics (ICAROB2026). The future of The ICAROB is brilliant from a point of view of yielding new technologies to human society in 21st century. I have founded Robot Artificial Life Society in 2017/12/07 together with Professor at Hiroshima University Takao Ito and Professor at University of Miyazaki Makoto Sakamoto. I hope that fruitful discussions and exchange of ideas between researchers during Conference (ICAROB2026) will yield new merged technologies for happiness of human beings and, hence, will facilitate the establishment of an international joint research institute on Artificial Life and Robotics in future.

Takao Ito
General Chair
(Professor Hiroshima University, Japan)

Takao Ito

General Chair of ICAROB

It is my great honor and pleasure to invite you all to the 2026 International Conference on Artificial Life and Robotics (ICAROB 2026).

The ICAROB has a long history. First launched in 1996 as ISAROB, this former organization of ICAROB, was developed under the strong leadership and yeoman efforts of the former President—the internationally famous Professor Masanori Sugisaka, who is widely acknowledged as the father of our AROB conference. Our conference has brought together many research scholars, faculty members, and graduate students from all over the world, and published numerous manuscripts in high-quality proceedings as well as highly reputed journals every year.

Over the years, dramatic improvements have been made in the field of artificial life and its applications. The ICAROB has provided a foundation for unifying the exchange of scientific information on the studies of man-made systems that exhibit the behavioral characteristics of natural living systems, including software, hardware, and wetware. Our conference shapes the development of artificial life, extending our empirical research beyond the territory circumscribed by life-as-we-know-it and into the domain of life-as-it-could–be. It will provide us with a good place to present our new research results, innovative ideas, and valuable information about artificial intelligence, complex systems theories, robotics, and management of technology.

The conference site is B-con plaza, one of the most famous international convention centers in Oita prefecture, Japan. You will find many fantastic scenic spots and splendid historical places in Oita prefecture. Please enjoy your stay!

I eagerly look forward to personally meeting you during the ICAROB 2026 and to sharing a most pleasant, interesting, and fruitful conference with you. Do come and make this conference a fruitful, productive as well as enjoyable event!

Yingmin Jia
Co-General Chair
(Professor, Beihang University, P.R. China)

Yingmin Jia

Co-General Chair of ICAROB

It is my great pleasure to invite you to The 2026 International Conference on Artificial Life and Robotics (ICAROB2026), will be held at B-Con Plaza, Oita, JAPAN, from January 29 to February 1, 2026， and your understanding and support will be the strongest driving force for us to organize the meeting well.

ICAROB develops from the AROB, which was created in 1996 by Prof. Masanori Sugisaka and will celebrate her 31st Anniversary in 2026. So far, many important results have been presented at past meetings and have a profound impact on artificial life and robotics. Doubtless, it is really one of the most representative international conferences in the field of artificial intelligence and attracts wide interests among scientists, researchers, and engineers around the world, and effectively promotes the unprecedented popularity of artificial intelligence. Especially, we congratulate Prof. Ito Takao on his taking over from Prof. Sugisaka as the new General Chair of ICAROB and look forward to the conference getting better and better.

For a successful meeting, many people have contributed their great efforts to ICAROB. Here, I would like to express my special thanks to all authors and speakers, and the organizing team for their excellent works. Looking forward to seeing you at ICAROB2026.

Ju-Jang Lee
Co-General Chair
(Honorary professor, KAIST)

Ju-Jang Lee

Co-General Chair of ICAROB

The First International Conference on Artificial Life and Robotics (ICAROB) was held in Oita City, Oita, Japan from Jan. 11th to 13th, 2014. This year's Conference will be held amidst the high expectation of the increasingly important role of the new interdisciplinary paradigm of science and engineering represented by the field of artificial life and robotics that continuously attracts wide interests among scientist, researchers, and engineers around the globe.
Distinguished researchers and technologists from around the world are looking forward to attending and meeting at ICAROB. ICAROB is becoming the annual excellent forum that represents a unique opportunity for the academic and industrial communities to meet and assess the latest developments in this fast-growing artificial life and robotics field. ICAROB enables them to address new challenges, share solutions, discuss research directions for the future, exchange views and ideas, view the results of applied research, present and discuss the latest development of new technologies and relevant applications.
In addition, ICAROB offers the opportunity of hearing the opinions of well-known leading experts in the field through the keynote sessions, provides the bases for regional and international collaborative research, and enables to foresee the future evolution of new scientific paradigms and theories contributed by the field of artificial life and robotics and associated research area. The twenty-first century will become the century of artificial life and intelligent machines in support of humankind and ICAROB is contributing through wide technical topics of interest that support this direction.
It is a great honor for me as a Co-General Chair of the 13th ICAROB 2026 to welcome everyone to this important event. Also, I would like to extend my special thanks to all authors and speakers for contributing to their research works, the participants, and the organizing team of the 13th ICAROB.
I'm looking forward to meeting you at the 13th ICAROB at B-Con Plaza in Beppu city and wishing you all the best.

GENERAL SESSION TOPICS

GS1 Machine Learning I (4)	GS2 Machine Learning II (6)
GS3 Autonomous Driving (5)	GS4 Image Processing (8)
GS5 Robotics & AI (3)	GS6 Applications I (6)
GS7 Applications II (5)	GS8 Aircraft (3)
Poster (1)	

ORGANIZED SESSION TOPICS

OS1 Industrial Artificial Intelligence Robotics (11)	OS2 Safety Intelligent Life Trend and Challenge (4)
OS3 Trust and Innovation in AI-Driven Intelligent Living (4)	OS4 Applied Machine Learning and Intelligent Systems (10)
OS5 Advances in Field Robotics and Their Applications (16)	OS6 Advanced Techniques for UAVs and Structural Heritage (7)
OS7 AI System and Space Design Toward Co-Existence of Humans and Robots (9)	OS8 Software Development Support Method (3)
OS9 Biological and Intelligent Information System (7)	OS10 Robotics and Intelligent Systems (9)
OS11 Intelligent Control (8)	OS12 Mathematical Informatics (10)
OS13 Intelligent Control (5)	OS14 Natural Computing (3)
OS15 Human Machine Interface I (4)	OS16 Narrative, Sensibility, and Cognition: Post-narratological Discussion for Humans and Robots (12)
OS17 Human Machine Interface II (3)	OS18 Human Machine Interface III (4)
OS19 Research Towards the Renewable Energy and the Sustainable Development Goals (SDG's) (10)	OS20 Pattern Recognition and Control (5)

Timetable

TIMETABLE (1/29)

Local Time in Japan

1/29(Thu.) 17:30-19:30	Welcome Reception (Welcome Party, KAMENOI HOTEL BEPPU)
2/1(Sun.) 12:40-13:10	Farewell Party (Meeting Room 32)

TIMETABLE (1/30)

1/30(Fri.)	**Meeting Room 31**	**Meeting Room 32**	**Meeting Room 33**	**Meeting Room 3** **Remote Session** ZOOM ID: 816 5609 0602	**Meeting Room 4** **Remote Session** ZOOM ID: 833 5206 2529
8:40-	Registration (3rd Floor)				
9:00-11:00	OS1 Industrial Artificial Intelligence Robotics -1 (8) Chair: Eiji Hayashi	OS11 Intelligent Control (8) Chair: Ching Ju Chen	Poster (1) Chair: Takao Ito		
11:00-11:20	Coffee Break				
11:20-11:50	Chair: Marion Oswald (Meeting Room 31) Opening Ceremony				
11:50-13:00	Lunch				
13:00-14:00	Chair: Eiji Hayashi (Meeting Room 31) Plenary Speech PS1 Young-Im Cho (Gachon University, Republic of Korea)				
14:00-14:20	Coffee Break				
14:20-15:20	Chair: Prof. Ju-Jang Lee (Meeting Room 31) Plenary Speech PS3 Saori Iwanaga (Japan Coast Guard Academy)				
15:20-15:30	Coffee Break				
15:30-16:30	OS1 Industrial Artificial Intelligence Robotics -2(3) Chair: Eiji Hayashi	OS10 Robotics and Intelligent Systems -1(4) Chair: Kuo-Hsien Hsia	OS2 Safety Intelligent Life Trend and Challenge (4) Chair: I-Hsien Liu	GS4 Image Processing -1(4) Chair: Yui Tanjo On-site	OS20 Pattern Recognition and Control (5) Chair: Fengzhi Dai
16:30-16:40	Coffee Break				
16:40-17:55		OS10 Robotics and Intelligent Systems -2(5) Chair: Kuo-Hsien Hsia	OS3 Trust and Innovation in AI-Driven Intelligent Living (4) Chair: I-Hsien Liu	GS4 Image Processing -2(4) Chair: Yui Tanjo On-site	ZOOM ID: 837 7627 1944 OS19 Research Towards the Renewable Energy and the Sustainable Development Goals (SDG's)-1 (5) Chair: Ammar A.M. Al Talib

TIME TEBLE (1/31)

1/31(Sat.)	Meeting Room 31	Meeting Room 32	Meeting Room 33	Meeting Room 3 Remote Session ZOOM ID: 816 5609 0602	Meeting Room 4 Remote Session ZOOM ID: 833 5206 2529	Meeting Room 5 Remote Session ZOOM ID: 837 7627 1944
8:40	Registration (3rd Floor)					
9:00-10:45	OS5 Advances in Field Robotics and Their Applications -1(6) Chair: Shinsuke Yasukawa	GS2 Machine Learning II (6) Chair: Ju-Jang Lee	GS3 Autonomous Driving & Aircraft (5) Chair: Saori Iwanaga	OS6 Advanced Techniques for UAVs and Structural Heritage (7) Chair: Hazry Desa	OS15 Human Machine Interface I (4) Chair Norrima Mokhtar	
10:45-11:00	Coffee Break					
11:00-12:00	OS5 Advances in Field Robotics and Their Applications -2(4) Chair: Shinsuke Yasukawa		OS14 Natural Computing (3) Chair: Marion Oswald	GS1 Machine Learning I (4) Chair: Dengchuan Cai on-site	OS17 Human Machine Interface II (3) Chair: Norrima Mokhtar	
12:00-13:00	Lunch					
13:00-14:00	Chair: Kazuo Ishii (Meeting Room 31) Plenary Speech PS2 Ren C. Luo (National Taiwan University, Taiwan)					
14:00-14:20	Coffee Break					
14:20-15:50	OS5 Advances in Field Robotics and Their Applications -3(6) Chair: Shinsuke Yasukawa	OS16 Narrative, Sensibility, and Cognition: Post-narratological Discussion for Humans and Robots -1(6) Chair: Jumpei Ono	GS6 Applications II (6) Chair: Chung-Wen Hung	OS12 Mathematical Informatics -1(6) Chair: Amane Takei on-site	OS18 Human Machine Interface III (4) Chair: Norrima Mokhtar	OS4 Applied Machine Learning and Intelligent Systems -1(5) Chair: Kasthuri Subaramaniam
15:50-16:00	Coffee Break					
16:00-17:30		OS16 Narrative, Sensibility, and Cognition: Post-narratological Discussion for Humans and Robots -2(6) Chair: Jumpei Ono	GS7 Applications I (5) Chair: Hiroaki Wagatsuma	OS12 Mathematical Informatics -2(4) Chair: Amane Takei on-site	OS19 Research Towards the Renewable Energy and the Sustainable Development Goals (SDG's)-2 (5) Chair: Ammar A.M. Al Talib	OS4 Applied Machine Learning and Intelligent Systems -2 (5) Chair: Kasthuri Subaramaniam
18:30-20:30	Banquet (KAMENOI HOTEL BEPPU)					

TIME TEBLE (2/1)

2/1(Sun.)	Meeting Room 32	Meeting Room 33	Meeting Room 3 Remote Session ZOOM ID: 816 5609 0602	Meeting Room 4 Remote Session ZOOM ID: 833 5206 2529
8:40-	Registration (3rd Floor)			
9:00-10:30	OS7 AI System and Space Design Toward Co-Existence of Humans and Robots-1 (6) Chair: Yuichiro Tanaka	GS5 Robotics & AI (3) Chair: Akira Nakamura		
10:30-10:50	Coffee Break			
10:50-12:35	OS7 AI System and Space Design Toward Co-Existence of Humans and Robots-2 (3) Chair: Yuichiro Tanaka	OS8 Software Development Support Method (3) Chair: Tetsuro Katayama		OS9 Biological and Intelligent Information System (7) Chair: Masayuki Fujiwara on-site
12:40-13:10	Farewell Party (Meeting Room 32)			

The 2026 International Conference on ARTIFICIAL LIFE AND ROBOTICS (ICAROB2026)

Opening Ceremony

January 29 (Thursday)

17:30-19:30 Welcome Reception (Welcome Party, KAMENOI HOTEL BEPPU)

January 30 (Friday)

Meeting Room 31

11:20-11:50 Opening Ceremony

Chair: Marion Oswald (Vienna University of Technology, Austria)

Welcome Addresses

1. General Chairman of ICAROB	Takao Ito (Hiroshima University, Japan)
2. Co-General Chairman of ICAROB	Ju-Jang Lee (KAIST, Korea)
3. International Organizing Committee	Chan Gook Park (Seoul National University, Korea)
4. International Organizing Committee	Kuo-Hsien Hsia (National Yunlin University of Science and Technology, Taiwan)
5. Vice General Chair of ICAROB	Norrima Mokhtar (University of Malaya, Malaysia)

January 31 (Saturday)

Banquet:

18:30-20:30

Chair: Takao Ito (Hiroshima University, Japan)

Welcome Addresses

Ju-Jang Lee (KAIST, Korea)

Technical Paper Index

January 30 (Friday)

8:40-Registration

Meeting Room 31

11:20-11:50 Opening Ceremony
Chair: Marion Oswald (Vienna University of Technology, Austria)

13:00-14:00
Plenary Speech PS1
Chair: Eiji Hayashi (Kyushu Institute of Technology, Japan)

PS1 *Multimodal AI Framework for Urban Environmental Intelligence Integrating Hazard and Risk Prediction*
Young-Im Cho (Gachon University, Korea)

14:20-15:20
Plenary Speech PS3
Chair: Ju-Jang Lee (KAIST, Korea)

PS3 *Multi-Agent Simulation of Influenza Epidemics and Evaluation of Infection Control Measures*
Saori Iwanaga (Japan Coast Guard Academy, Japan)

Meeting Room 31
9:00-11:00 OS1 Industrial Artificial Intelligence Robotics-1 (8)
Chair: Eiji Hayashi (Kyushu Institute of Technology, Japan)

OS1-1 *Design and Development of a ROS2–Android Based Remote Control System for an Autonomous Beach Cleaning Robot*
Weizheng Pan, Chi Jie Tan, Eiji Hayashi (Kyushu Institute of Technology, Japan)

OS1-2 *Improved Multi-Object Tracking System Using 3D–2D Image Data Fusion for Beach Cleaning Robot*
Rut Yatigul, Tan Chi Jie, M.A Munjer, Wisanu Jitviriya, Teppakorn Sittiwanchai, Watcharin Tangsuksant, Eiji Hayashi
(Kyushu Institute of Technology, Japan, King Mongkut's University of Technology Thailand)

OS1-3 *LLM-Supervised Genetic Programming for Multi-Robot Behavior Tree Evolution*
Chi Jie Tan, M.A Munjer, Weizheng Pan, Eiji Hayashi, Way Soong Lim
(Kyushu Institute of Technology, Japan, Multimedia University, Malaysia)

OS1-4 *Tree Mapping in Forests with LiDAR–RGB Fusion*
M.A Munjer, Tan Chi Jie, Boufaroua Vincent, Eiji Hayashi (Kyushu Institute of Technology, Japan)

OS1-5 *System development of autonomous mobile field robots*
- Feature Matching Method for Expanding Human Tracking Functions -
Satoshi Yamaguchi, Eiji Hayashi (Kyushu Institute of Technology, Japan)

OS1-6 *Support System for Editing Performance Information for an Automatic Piano*
-Construction of a System to Extract Elements from Score and Real Performance-
Ryuta Matsuda, Eiji Hayashi (Kyushu Institute of Technology, Japan)

OS1-7 *Enhancing Squeeze-and-Excitation Networks with Mixed Pooling for Image Classification*
Rut Yatigul, Teppakorn Sittiwanchai, Aran Blattler, Eiji Hayashi, Wisanu Jitviriya
(King Mongkut's University of Technology Thailand, Kyushu Institute of Technology, Japan)

OS1-8 *Merging of Geometric and 3D Semantic Costmaps for Navigation in Complex Outdoor Environments*
Boufaroua Vincent, Chi Jie Tan, Eiji Hayashi (Kyushu Institute of Technology, Japan)

15:30-16:15 OS1 Industrial Artificial Intelligence Robotics-2 (3)
Chair: Eiji Hayashi (Kyushu Institute of Technology, Japan)

OS1-9 *The research on food segmentation technology in the ready-to-eat food industry*
Yamato Fukuiri, Gamolped Prem, Eiji Hayashi (Kyushu Institute of Technology, Japan)

OS1-10 *Deep Reinforcement Learning with NVBlox TSDF Mapping for Grasp Optimization Using a Custom Force-Sensing Three-Finger Gripper*
Yon Pang Ja Sin, Bytyqi Vjosa, Gamolped Prem, Eiji Hayashi (Kyushu Institute of Technology, Japan)

OS1-11 *Robust round object occlusion identification and localization using an algebraic nine-field method for local exploitation*
Anna Biedermann, Eiji Hayashi (Kyushu Institute of Technology, Japan)

Meeting Room 32

9:00-11:00 OS11 Intelligent Control (8)

Chair: Ching Ju Chen (National Yunlin University of Science and Technology, Taiwan)

Co-Chair: Chun-Chieh Wang (National Yunlin University of Science and Technology, Taiwan)

OS11-1 *Development of a Flight-Path Planning and AprilTag-based Landing System for Drone Logistics*
Yu-Ming Li, Jia-Ming Xu, Jia-Wen He, and Chau-Chung Song
(National Formosa University, Taiwan)

OS11-2 *Development of an Indoor VIO-Based Navigation System for Unmanned Vehicles*
Chih-Hao Chen, Lin, Jian Jhih, Li-Hao Chen and Chau-Chung Song
(National Formosa University, Taiwan)

OS11-3 *YOLOv11 Wormhole Detection System based on ESRT and EGA Enhancements*
Jun-Lin WU, Chung-Wen HUNG*
(Nation Yunlin University of Science and Technology, Taiwan)

OS11-4 *Modulation Control Strategies for Ultrasonic Transducers*
Chi-Wei Li, Chung-Wen HUNG*, Chun-Chieh Wang
(Nation Yunlin University of Science and Technology, Taiwan)

OS11-5 *Temperature-Controlled Multi-Segment Constant Current Charging Technique Based on PSO Algorithm*
Chun-Liang Liu, Guan Jhu Chen, Ching Ju Chen*, Ting-An Chang, Jin-Chen Zhuo
(National Yunlin University of Science and Technology, Taiwan)

OS11-6 *AIoT-Driven Smart Ecological Restoration of Sasakia Charonda Habitat*
Ching-Ju Chen*, Zhao-Sheng Chen, Chun-Liang Liu, Candera Wijaya
(National Yunlin University of Science and Technology, Taiwan)

OS11-7 *Swallowing Training Monitor*
Nai-Hui Chien, Po-Ting Wang (Chang Gung University of Science and Technology, Taiwan)

OS11-8 *Assisted Pelvic Floor Muscle Training Device*
Nai-Hui Chien, Tsai-Er Ho, Po-Ting Wang (Chang Gung University of Science and Technology, Taiwan)

15:30-16:30 OS10 Robotics and Intelligent Systems-1 (4)

Chair: Kuo-Hsien Hsia (National Yunlin University of Science and Technology, Taiwan)

Co-Chair: Jr-Hung Guo (National Yunlin University of Science and Technology, Taiwan)

OS10-1 *Design and Implementation of a Four-Wheel Steering Mechanism for Educational Demonstration*
Kuo-Hsien Hsia, Chun-Chi Lai, Yi-Ting Liu
(National Yunlin University of Science and Technology, Taiwan)

OS10-2 *Comparative Analysis of Speech Recognition Training Using Real and Synthetic Data*
Chung-Yu Li, Kuo-Hsien Hsia (National Yunlin University of Science and Technology, Taiwan)

OS10-3 *Development of a Flexible ROS-based Robot Architecture*
Jr-Hung Guo, Kuo-Hsien Hsia (National Yunlin University of Science and Technology, Taiwan)

OS10-4 *Implementation of Water-Washing Blackboard Cleaning Mobile Robot*
Jia-Ming Hsiao, Shao-I Hsiao, Yu-En Tien (National Yunlin University of Science and Technology, Taiwan)

16:40-17:55 OS10 Robotics and Intelligent Systems-2 (5)
Chair: Kuo-Hsien Hsia (National Yunlin University of Science and Technology, Taiwan)
Co-Chair: Jr-Hung Guo (National Yunlin University of Science and Technology, Taiwan)

OS10-5 *Image Recognition of UAV Photographed Ground Targets*
Kuo-Da Chou, Huang-Li Wang (National Formosa University, Taiwan)

OS10-6 *A Fault Prediction Method for Electron Beam Welding Equipment*
Kuo-Da Chou, Huang-Li Wang (National Formosa University, Taiwan)

OS10-7 Concept Design of Foot Massager
Yuting Hsiao, Dengchuan Cai, Chung-Wen Hung, Chen-Wei Tu, Zi-Jie Xu
(Nation Yunlin University of Science and Technology, Taiwan)

OS10-8 *Preliminary Design and Simulation Verification of an Autonomous Book Returning System Based on Navigation and Visual Recognition*
Chun-Chieh Wang*, Chung-Wen Hung, Chun-Lung Hsiao, Kuo-Hsien Hsia, Chian-Cheng Ho
(National Yunlin University of Science and Technology, Taiwan)

OS10-9 *Development of a SOTIF-Based Safety Evaluation Platform for Lane Keeping Assist (LKA) Systems*
Chien-An Chen, Yan-Hua Chen, Yi-Feng Tsou
(National Kaohsiung University of Science and Technology, Taiwan)

Meeting Room 33
9:00-9:15 Poster (1)
Chair: Takao Ito (Hiroshima university, Japan)

POS-1 *EEG-Based Prediction of Concentration Rank During Zentangle Practice Using Frequency-Specific Features and Machine Learning*
Ting-Chien Chuang, Muhammad Usman, Yao-Tien Chen
(Ming Chi University of Technology, Taiwan)
Chun-Ling Lin*(National Taipei University of Technology, Taiwan)

15:30-16:30 OS2 Safety Intelligent Life Trend and Challenge (4)
Chair: I-Hsien Liu (National Cheng Kung University, Taiwan)
Co-Chair: Chu-Fen Li (National Formosa University, Taiwan)

OS2-1 *A Dynamic Bayesian Game Model for Emergency Vehicle Evasive Decision-Making at Unsignalized Intersections*
Zhi-Yuan Su, Wei-Xiang Li, Jung-Shain Li, I-Hsien Liu, Kuan-Ting Lee
(National Cheng Kung University, Taiwan)

OS2-2 *Challenges of Self-Driving Cars at Unsignalized Intersections*
Kuan-Ting Lee, I-Hsien Liu, Wei-Xiang Li (National Cheng Kung University, Taiwan)
Chu-Fen Li (National Formosa University, Taiwan)

OS2-3 *Endogenous Anti-Jamming Strategies for UAV Swarms: Dynamic Topology Reconstruction and Risk-Aware Communication*
Ching-Fang Yang (Cheng Shiu University, Taiwan)
Kuan-Ting Lee (National Cheng Kung University, Taiwan)

OS2-4 *Lyapunov-Driven Adaptive Queue Management for P4-Programmable SDN: Stability-Guaranteed Low-Latency Control against Bufferbloat*
Wei-Xiang Lin[1], Ming-Syuan Wu1, Ya-Chen Li[1]*, Wen-Shyang Hwang[1], Cheng-Han Lin[2], Yu-Chi Lin[1]
[1](National Kaohsiung University of Science and Technology, Taiwan), [2](Fooyin University, Taiwan)

16:40-17:40 OS3 Trust and Innovation in AI-Driven Intelligent Living (4)
Chair: I-Hsien Liu (National Cheng Kung University, Taiwan)
Co-Chair: Jung-Shian Li (National Cheng Kung University, Taiwan)

OS3-1 *Exploring the key factors of innovation in AI health management services using FAHP*
Li-Min Chuang, Zong-Sheng Li (Chang Jung Christian University, Taiwan)

OS3-2 *Critical Success Factors of Taiwan's Multi-Level Marketing Industry in the AI-Driven Digital Era*
Li-Min Chuang, Hsieh Tsung Hsien (Chang Jung Christian University, Taiwan)

OS3-3 *Exploring the Relationship Between Moral Development and Internet-Triggered Academic Dishonesty Behavior among Cadets in Taiwan*
Shu-Hua Huang (Air Force Institute of Technology, Taiwan)
I-Hsien Liu (National Cheng Kung University, Taiwan)

OS3-4 *A Novel Digital Twin Framework for Industrial Control System: Cybersecurity Testbed Trends and Challenges*

Han-Yang Yu, Jung-Shain Li, I-Hsien Liu (National Cheng Kung University, Taiwan)

Meeting Room 3

15:30-16:30 GS4 Image Processing -1(4)

Chair: Yui Tanjo (Kyushu Institute of Technology, Japan)

GS4-1 *Evaluation of Virtual Monoenergetic X-ray Image Conversion Using U-Net*
Taiga Tanimoto[1], Naohiro Iwata[1], Yohei Kamikawa[1], Shogo Baba[2], Yukito Yoshida[1]

GS4-2 *Generation of Stripe-Patchwork Images by Selecting from Horizontal and Vertical Averages*
Jia-Lin Zhang, Toru Hiraoka (University of Nagasaki, Japan)

GS4-3 *Edge-Based Image Processing for Urban Change Detection after Earthquakes*
Adessarman Muhammad Sahlan[1], Bart Dewancker[1], Mohammad Albaroudi[2], Raji Alahmad[2], Fahd Moumni[2,3], Karim Hasibuan[2] ([1]The University of Kitakyushu, Japan) ([2]Kyushu Institute of Technology, Japan) ([3]MicroOrbiter Inc, Japan)

GS4-4 *Diffusion-Based Data Augmentation Mitigates Class Imbalance in Circulating Tumor Cell Fluorescence*
Kouki Tsuji[1], Kazue Yoneda[2 3], Tohru Kamiya[1]
([1]Kyusyu Institute of Technology, [2]Hyogo Medical University, [3]University of Occupational and Environmental Health, Japan)

16:40-17:40 GS4 Image Processing -2(4)

Chair: Yui Tanjo (Kyushu Institute of Technology, Japan)

GS4-5 *Estimating Driver Drowsiness Using Millimeter-Wave Radar*
Yoshikazu Hirayama, Kazuya Matsuo (Kyushu Institute of Technology, Japan)

GS4-6 *Engagement Estimation in E-Learning Using Facial and Upper-Body Videos*
Shun Takeshita, Noriko Takemura (Kyushu Institute of Technology, Japan)

GS4-7 *Development of a Direction Indicating Navigation Method for a Visually Impaired Person*
KenyuTakahashi, Yui Tanjo (Kyushu Institute of Technology, Japan)

GS4-8 Two-Stage YOLOv4-Tiny for Vascular Stenosis Detection Using AVF Shunt Sound Data
Lucky Nindya Palupi, Hiroki Tamura (University of Miyazaki, Japan)

Meeting Room 4

15:30-16:45 OS20 Pattern Recognition and Control (5) Online Presentation

Chair: Fengzhi Dai ((Tianjin University of Science and Technology, China)

Co-Chair: Yunzhong Song (Henan Polytechnic University, China)

OS20-1 *Efficient Approximation of RBF Networks through Attention-Kernel LSH*
Qianxiao Pan[1], Fengzhi Dai[1], Yunzhong Song[2]
([1] Tianjin University of Science and Technology, [2] Henan Polytechnic University, China)

OS20-2 *Performance Investigation of the Newton-Raphson Algorithm for Inverse Kinematics of a 7-DOF Robotic Manipulator*
Hao He, Miao Zhang (Tianjin University of Science and Technology, China)

OS20-3 *An Improved PSO Algorithm for Solving Robotic Six-DOF Manipulator IK*
Kai Sun, Miao Zhang (Tianjin University of Science and Technology, China)

OS20-4 *Improved SCGCR Algorithm for 7-DOF Redundant IK*
Zhaorui Hao, Miao Zhang (Tianjin University of Science and Technology, China)

OS20-5 *A New Cleaning Robot for Organisms Attached to Ocean-going Ships*
Haozhe Li, Xinlin Wang, Xinyu Chen, Jiaxu Cheng, Shengzhou Chen, Xingyu Zhao, Youyang Ye, Yang Tang, Ruirui Zhang, Wei Xiao, Fengzhi Dai (Tianjin University of Science and Technology, China)

16:40-17:55 OS19 Research Towards the Renewable Energy and the Sustainable Development Goals (SDG's) -1(5) Online Presentation

Chair: Ammar A.M. Al Talib (UCSI University, Malaysia)

Co-Chair: Takao Ito (Hiroshima University, Japan)

OS19-1 *Prediction of Occupant's Head Movement during Slalom Driving via Ensemble Learning Model*
Wong Wei Herng[1], Sarah 'Atifah Saruchi[2], Ammar A.M. Al-Talib[3], Sharifah Munawwarah[4], Mohd Hatta Mohamed Ariff[5], Nurhaffizah Hassan[6], Nor Aziyatul Izni[7], Alvi Khan Chowdury[8] ([1,3]UCSI University, Malaysia, [2]UMPSA, Malaysia, [4]University of Tsukuba, Japan, [5]UTM, Malaysia, [6,7]UiTM, Malaysia, [8]Monash University, Malaysia)

OS19-2 *Smart Elderly Health Monitoring Device Via Internet-of-Things (IoT)*
Eii Tze Xian[1], Sarah, Atifah Saruchi[2], Wan Zailah Wan Said[3], Ammar A.M. Al-Talib[4], Nor Aziyatul Izni[5], Nurhaffizah Hassan[6], Alvi Khan Chowdury[7], Sheikh Muhammad Hafiz Fahami[8] ([1,3,4]UCSI University, Malaysia, [2,8]UMPSA, Malaysia,[5,6]UiTM, Malaysia, [7]Monash University, Malaysia)

OS19-3 *Smart Petting System Via Internet of Things (IoT)*
Siah Jing Yi[1], Sarah, Atifah Saruchi[2], Wan Zailah Wan Said[3], Ammar A.M. Al-Talib[4], Nurhaffizah Hassan[5], Nor Aziyatul Izni[6], Sunmiya Fujita[7]
([1,3,4]UCSI University, Malaysia, [2,7]UMPSA, Malaysia,[5,6]UiTM, Malaysia)

OS19-4 *Seawater Desalination and Purifier Machine*
Alvin Loke Ting Foong[1], Ammar A.M. Al-Talib[1], Rodney Tan Hean Gay[1], Sarah 'Atifah Saruchi[2] ([1]UCSI University, Malaysia), ([2]UMPSA, Malaysia)

OS19-5 *A Compact Stratified Integrated Solar Water Heating System*

Farouk Hesham Farouk Elkholy[1], Ammar A.M. Al-Talib[1], Rodney Tan Hean Gay[1], Sarah 'Atifah Saruchi[2] ([1]UCSI University, Malaysia), ([2]UMPSA, Malaysia)

January 31 (Saturday)

Meeting Room 31
13:00-14:00
Plenary Speech PS2
Chair: Kazuo Ishii (Kyusyu Institute of Technology, Japan)

PS2 *AI Enabled Intelligent Robotics: Evolving Applications and Opportunities*
Ren C. Luo (National Taiwan University, Taiwan)

Meeting Room 31
9:00-10:30 OS5 Advances in Field Robotics and Their Applications -1(6)
Chair: Shinsuke Yasukawa (Kyusyu Institute of Technology, Japan)
Co-Chair: Kazuo Ishii (Kyushu Institute of Technology, Japan)

OS5-1 *Semi-Automated Urban Tree Pruning Using a Rule-Based 2D Vision Approach*
Mohammad Albaroudi, Abdullah Alraee, Raji Alahmad, Hussam Alraie, Kazuo Ishii
(Kyushu Institute of Technology, Japan)

OS5-2 *Automatic Scenario Generation for Agricultural robots Using Natural Language Instructions*
Takuya Fujinaga (Osaka Metropolitan University, Japan)

OS5-3 *Development of a Tele-Operation Control System for a Tomato-Harvesting Robot Using VR Interfaces*
Takuma Ushiroji, Takuya Fujinaga (Osaka Metropolitan University, Japan)

OS5-4 *Evaluation of an Optimal Approach Direction for a Tomato-Harvesting Robot Using a Digital Twin*
Kouya Taitou, Takuya Fujinaga (Osaka Metropolitan University, Japan)

OS5-5 *Tension Measurement Sensor for a Surface Vehicle Equipped with an Underwater Vehicle*
Naoto Shirahama, Takuya Fujinaga (Osaka Metropolitan University, Japan)

OS5-6 *Proposal of New Kinematics for Mobile Robots adapted Three-Rollers*
[1]Kenji Kimura, [2]Kazuki Nakayama, [3]Katsuaki Suzuki, [4]Kazuo Ishii,
([1]National Institute of Technology, Matsue College, Japan, [2] Toyohashi University of Technology, Japan,[3]Kumamoto Industrial Research Institute, Japan, [4]Kyushu Institute of Technology, Japan)

11:00-12:00 OS5 Advances in Field Robotics and Their Applications -2(4)
Chair: Shinsuke Yasukawa (Kyusyu Institute of Technology, Japan)
Co-Chair: Kazuo Ishii (Kyushu Institute of Technology, Japan)

OS5-7 *A Study on the Number of Passive Rollers and Trajectory of Omni-Roller in Mobile Robot*
[1]Kenji Kimura, [2]Katsuaki Suzuki, [3]Kazuo Ishii,
([1]National Institute of Technology, Matsue College, Japan, [2]Kumamoto Industrial Research Institute, Japan, [3]Kyushu Institute of Technology, Japan)

OS5-8 *Development of a Self-Locking Cam Mechanism for Spring Compression*
[1]Katsuaki Suzuki, [2]Yuya Nishida, [3]Kenji Kimura, [2]Kazuo Ishii
([1]Kumamoto Industrial Research Institute, Japan, [2]Kyushu Institute of Technology, Japan, [3]National Institute of Technology, Matsue College, Japan)

OS5-9 Voxel-Grid Based Deep Learning for Robust People Counting and Tracking with Event-Based Vision Sensors
Raji Alahmad, Zitong Zhou, Mohammad Albaroudi, Abdullah Alraee, Hussam Alraie, Shinsuke Yasukawa (Kyushu Institute of Technology, Japan)

OS5-10 *An Underwater Operation Method for a Diver Using Underwater Radio Frequency Communication and a Smartphone*
Daigo Katayama***, Raji Alahmad*, Kazuhiro Eguchi*, Toshiyuki Wakisaka***, Tohlu Matsushima*, Yuki Fukumoto*, Kazuo Ishii* (*Kyushu Institute of Technology, **Kobe City College of Technology, ***Panasonic Holdings Co., Ltd., Japan)

14:20-15:50 OS5 Advances in Field Robotics and Their Applications -3(6)
Chair: Shinsuke Yasukawa (Kyusyu Institute of Technology, Japan)
Co-Chair: Kazuo Ishii (Kyushu Institute of Technology, Japan)

OS5-11 *Computer Vision-Based Monitoring of Feeding Consistency in Aquaculture*
Abdullah Alraee, Mohammad Albaroudi, Hussam Alraie, Raji Alahmad, Irmiya R Inniyaka, Kazuo Ishii (Kyushu Institute of Technology, Japan)

OS5-12 *The processing of acoustic sonar data for the underwater robot self-localization*
Ryo Miyakawa, Kazuo Ishii, Yuya Nishida (Kyushu Institute of Technology, Japan)

OS5-13 *Remote Operation of an Underwater Vehicle equipped with a Radio communication Device*
Yuya Nishida, Ryo Miyakawa, Kazuo Ishii, Tohlu Matsushima, Daisuke Nakayama, Kazuhiro Eguchi, Yuki Fukumoto (Kyushu Institute of Technology, Japan)

OS5-14 *Multimodal RF-Enabled iPhone-Based Diver-in-the-Loop strategy for Underwater communication and UUV control*
Irmiya R. Inniyaka, Kazuhiro Eguchi, Toshiyuki Wakisaka, Yuya Nishida, Kazuo Ishii
(Kyushu Institute of Technology, Japan)

OS5-15 *Comparative Performance Analysis of YOLOv5 and YOLOv8 for Tomato Detection in Agricultural Robotics.*
Eslem Kıvrak, Orhun Erke Simav, Arda Şahin (Middle East Technical University, Türkiye),
Abdullah Alraee, Mohammad Albaroudi, Raji Alahmad (Kyushu Institute of Technology, Japan),
Hussam Alraie, Tayfun Nesimoğlu (Middle East Technical University, Türkiye)

OS5-16 *OS5-16 Resolving Object Overlap in Agricultural Imagery Using a Modified Watershed Transform*
Oğuzhan Çalışkan, Naime Ayça Sezginer, Elifnaz Bilgili, Mustafa Eray Erdoğan,
(Middle East Technical University, Türkiye),
Abdullah Alraee, Mohammad Albaroudi, Raji Alahmad (Kyushu Institute of Technology, Japan),
Hussam Alraie, Tayfun Nesimoğlu (Middle East Technical University, Türkiye)

Meeting Room 32
9:00-10:30 GS2 Machine Learning II (6)
Chair: Ju-Jang Lee (KAIST, Korea)

GS2-1 *Formation of Place and Episodic Memory in a Recurrent Neural Network*
Shin Tamura, Yutaka Yamaguti (Fukuoka Institute of Technology, Japan)

GS2-2 *A Systematic Comparison of Machine Learning Models for State of Charge Estimation in CubeSat Lithium-ion Battery System*
Babu Vishwanath Hemath Kumar*, Kitamura Kentaro, Necmi Cihan Orger, Kei Sano
(Kyushu Institute of Technology, Japan)

GS2-3 *AuscuFuse: A Robust Parallel Dual-Branch Network for Respiratory Sound Classification*
Ryusei Oshima, Tohru Kamiya (Kyushu Institute of Technology, Japan)

GS2-4 *A Method of Objects Remembrance Support Based on Object-Holding Action and Its Recognition*
Taisei Shiraki, Seiji Ishikawa, Yui Tanjo (Kyushu Institute of Technology, Japan)

GS2-5 *Development of Outdoor Autonomous Driving Robots- Improvement of the Performance with Autonomous Driving*
Kako Koyama, Yui Tanjo (Kyushu Institute of Technology)

GS2-6 *Development of a Method of Automated Food Presentation*
Ryosei Todo, Yui Tanjo (Kyushu Institute of Technology, Japan)

14:20-15:50 OS16 Narrative, Sensibility, and Cognition: Post-narratological Discussion for Humans and Robots-1 (6)
Chair: Jumpei Ono (Aomori University, Japan)
Co-Chair: Hiroki Fxyma (Kobe University, Japan)
Co-Chair: Yukiko Furuya (Chiba University, Japan)
Co-Chair: Takashi Ogata (Yamato University, Japan)

OS16-1 *An Analysis of Post Content and Like Ratings - Differences by Product Category and Media –*
Yoji Kawamura (Kindai University, Japan)

OS16-2 *Disinformation Narrative Distribution and Generation Using Generative AI*
Jumpei Ono (Aomori University, Japan), Takashi Ogata (Yamato University, Japan)

OS16-3 *Graph-Based Next-Event Prediction Methods Considering the Interrelationships among Game Players' Memories: Focusing on a Card Game*
Koki Nishiyama (Yamato University, Japan), Hiroki fxyma (Kobe University, Japan)
Takashi Ogata (Yamato University, Japan)

OS16-4 *Category-Theoretic View of Social Repair: Minimal Supplementation in Human Dialogue*
Yukiko Furuya, Akinori Abe (Chiba University, Japan)

OS16-5 *Toward a Multi-layered Computational Model of Structure and Meaning in Onna Koroshi Abura no Jigoku for AI-based Narrative Generation*
Sakura Kawai, Takashi Ogata (Yamato University, Japan)

OS16-6 *Toward Computational Narrative Discourse Analysis with Large Language Models: A Case Study on a Japanese Short Novel*
Riku Takahashi, Ayahiko Niimi (Future University Hakodate, Japan)

16:00-17:30 OS16 Narrative, Sensibility, and Cognition: Post-narratological Discussion for Humans and Robots-2 (6)
Chair: Jumpei Ono (Aomori University, Japan)
Co-Chair: Hiroki Fxyma (Kobe University, Japan)
Co-Chair: Yukiko Furuya (Chiba University, Japan)
Co-Chair: Takashi Ogata (Yamato University, Japan)

OS16-7 *Blending a Visual Novel and Narrative Discourse Theories Using Generative AI*
Yuka Okayama (Yamato University, Japan), Jumpei Ono (Aomori University, Japan)
Takashi Ogata (Yamato University, Japan)

OS16-8 *Acquiring Creative Narrative Generation Techniques from the Behaviors and Cognition of Individuals with Autism Spectrum Disorder*
Misao Ichio (Yamato University, Japan), Jumpei Ono (Aomori University, Japan),
Shin'ichiro Aoki (Iwate Prefectural University, Japan), Takashi Ogata (Yamato University, Japan)

OS16-9 *Developing a Shape Dataset for Multimodal Evaluation of Taste and Flavor*
Hiroki Fxyma (Kobe University, Japan)

OS16-10 *Toward AI-based Narrative Generation Techniques Based on the Narrative Structures of Japanese Folktales*
Jumpei Ono (Aomori University, Japan), Takashi Ogata (Yamato University, Japan)

OS16-11 *Design and Development of a Narrative World for a Multi-agent-based Narrative Generation Role-Playing Game*
Hikaru Sugizawa (Yamato University, Japan), Ono Jumpei (Aomori University, Japan)
Takashi Ogata (Yamato University, Japan)

OS16-12 *The Aesthetic Mindscape: Visualizing Human and AI Narratives in Abstract Art*
Jun Nakamura (Chuo University, Japan), Sanetane Nagayoshi (Shizuoka University, Japan)

Meeting Room 33
9:00-10:15 GS3 Autonomous Driving & Aircraft (5)
Chair: Saori Iwanaga (Japan Coast Guard Academy, Japan)

GS3-1 *Map-Based Navigation and Localization in the Autoware Simulator Using Integrated Open-Street-Map and Point-Cloud-Data*
Obada Al Aama[1], Tomoki Taniguchi[1], Davaanyam Jargal[1], Hodaka Inoue[1], Junya Oishi[2], Wataru Mizushina[2], Hakaru Tamukoh[1], Hiroaki Wagatsuma[1]
([1]Kyushu Institute of Technology, Japan, [2]Aisan Technology Co., Ltd., Japan)

GS3-2 *A Python-Based Framework for Preprocessing and Vehicle Flow Analysis of ETC2.0 Probe Data for Efficient Data Handling*
Rena Kato[1], Souma Noguchi[1], Ahmad Altaweel[1], Haruki Sato[1], Guanyu Su[1], and Hiroaki Wagatsuma[1] ([1]Kyushu Institute of Technology, Japan)

GS3-3 *Development of a Bird-Inspired Flapping-Wing Robot Capable of Bounding Flight*
Kanato Matsui, Hiroshi Ohtake (Kyushu Institute of Technology, Japan)

GS3-4 *A Study on Image Processing and Tracking Control of a Small Flapping Flight Robot with a Camera*
Shuto Wakugawa, Hiroshi Ohtake (Kyushu Institute of Technology, Japan)

GS3-5 *Separation of Stray Magnetic Fields in 3U CubeSats Using Multiple Magnetometers and Blind Source Separation method*
Enkhmend Ochirsukh, Kitamura Kentaro, Necmi Cihan Orger
(Kyushu Institute of Technology, Japan)

11:00-11:45 OS14 Natural Computing (3)
Chair: Marion Oswald (Vienna University of Technology, Austria)
Co-Chair: Yasuhiro Suzuki (Nagoya University, Japan)

OS14-1 *Dominance Regions: Geometric Framework for Multi-Component Dynamical Systems*
Yasuhiro Suzuki (Nagoya University, Japan)

OS14-2 *Algorithmic Observation and the Reconstruction of Scientific Rationality*
Yasuhiro Suzuki (Nagoya University, Japan)

OS14-3 *Vibro-Acoustic Spatial Modulation for Enhancing Environmental Experience in Interior Spaces*
Yasuhiro Suzuki (Nagoya University, Japan)

14:20-15:50 GS6 Applications I (6)
Chair: Chung-Wen HUNG (Nation Yunlin University of Science and Technology, Taiwan)

GS6-1 *A Method of Recognizing Health Condition Based on Walking Patterns*
Kanato Tajika, Seiji Ishikawa, Yui Tanjo (Kyushu Institute of Technology, Japan)

GS6-2 *Spatio-Frequency Consistency Learning for Self-Supervised Visual Representations*
Zhongxi Zhang, Cunwei Lu (Fukuoka Institute of Technology, Japan)

GS6-3 *Experimental Comparison of Leather Rotational Torque in Vertical and Horizontal Hide-Tanning Techniques for Traditional Leather Processing in Mongolia*
Renchinvanjil Yadam and Dondogjamts Batbaatar
(Mongolian University of Science and Technology, Mongolia)

GS6-4 *Method for determining the optimal pressure measurement site for heart rate monitoring using a flexible sheet-type tactile sensor*
Kyota Suzuki, Kazuya Matsuo (Kyushu Institute of Technology, Japan)

GS6-5 *Sleep Posture and Heartbeat Estimation Using a Flexible Tactile Sensor Sheet*
Hibiki Shimono, Kazuya Matsuo (Kyushu Institute of Technology, Japan)

GS6-6 *Heart Rate Measurement Using a Flexible Sheet-Type Tactile Sensor*
Kamui Nagano Kazuya Matsuo (Kyushu Institute of Technology, Japan)

16:00-17:15 GS7 Applications II (5)
Chair: Hiroaki Wagatsuma (Kyushu Institute of Technology, Japan)

GS7-1 *Dynamics of Inter-Brain Phase Synchronization During the Emergence of Coordinated Behavior*
Rena Kato[1], Akio Wakata[1], Kosei Shibata[1], Shabbir Mahmood[1], Diunuge Buddhika Wijesinghe[1], Yide Yang[1], Masayuki Fujiwara[2], Laurent Bougrain[3], Kiyohisa Natsume[1], and Hiroaki Wagatsuma[1]
([1]Kyushu Institute of Technology, Japan, [2]Komatsu University, Japan, [3]University of Lorraine, France)

GS7-2 *Extending LabStreamingLayer for Synchronized Monitoring of Expert Bus Drivers: GPS, Camera, Motion, and Eye-Tracking Integration for Risk-Point Analysis*
Shabbir Mahmood, Tomoki Taniguchi, Hodaka Inoue, Rena Kato, Kosei Shibata, Obada Al Aama, Davaanyam Jargal, Diunuge Buddhika Wijesinghe, Hakaru Tamukoh and Hiroaki Wagatsuma (Kyushu Institute of Technology, Japan)

GS7-3 *Dynamics of Landing and Push-Off in Running for Implications on Prosthetic Limb Design*
Choisuren Purevdorj[1], Abhinav Sharma[2], Kosei Shibata[1], Tomoki Taniguchi[1], Shintaro Kasai[1], Rena Kato[1], Yiqian Ge[1] and Hiroaki Wagatsuma[1]
([1]Kyushu Institute of Technology, Japan; [2]Indian Institute of Technology Kanpur, India)

GS7-4 *3D Point Cloud-based Change Detection from Image Pairs Based on Cross-Attention Networks*
Kazuma Morinaga, Yui Tanjo (Kyushu Institute of Technology, Japan)

GS7-5 *Analysis of Generalization Pertinency in Autoencoder-Based Anomaly Detection for Industrial Motor Sounds Using SVM*
Jamil Md Shafayet, Praveen Nuwantha Gunaratne, Hiroki Tamura
(University of Miyazaki, Japan)

Meeting Room 3

9:00-10:45 OS6 Advanced Techniques for UAVs and Structural Heritage (7)

Chair: Hazry Desa (Universiti Malaysia Perlis (UniMAP), Malaysia)
Co-Chair: M. Azizi Azizan (Universiti Malaysia Perlis (UniMAP), Malaysia)

OS6-1 *Variants of Robust Sliding Mode Control for Quadrotor UAVs under Parametric Uncertainties*
Hazry Desa[1], Azmat Saeed[2], M. Azizi Azizan[1], S. B. Yaakob[1], Abadal-Salam T. Hussain[3], Taha Almulaisi[4], M. Hassan Tanveer[5]
([1]UniMAP, Malaysia; [2]NUST, Pakistan; [3]Al-Kitab University, Iraq; [4]Northern Technical University, Iraq; [5]Kennesaw State University, USA)

OS6-2 *Unmanned Aerial Vehicle Fleet Management and Control System*
Thines Vasanthan[1], Hazry Desa[1], Azmat Saeed[2], M. Azizi Azizan[1], S. B. Yaakob[1], Abadal-Salam T. Hussain[3], Taha Almulaisi[4], M. Hassan Tanveer[5]
([1]UniMAP, Malaysia; [2]NUST, Pakistan; [3]Al-Kitab University, Iraq; [4]Northern Technical University, Iraq; [5]Kennesaw State University, USA)

OS6-3 *AI-Driven Structural Optimization of a Fixed Wing UAV Composite Airframe*
Afnan Nazmy[1], Hazry Desa[1], M. Azizi Azizan[1], S. B. Yaakob[1], Abadal-Salam T. Hussain[3], Taha Abdulsalam Almulaisi[4], M. Hassan Tanveer[5]
([1]UniMAP, Malaysia; [2]NUST, Pakistan; [3]Al-Kitab University, Iraq; [4]Northern Technical University, Iraq; [5]Kennesaw State University, USA)

OS6-4 *Smart Digital Twin System for Monitoring and Predicting the Deterioration of Religious Heritage Structure*
Ainur Fariha Mahhassan, M. Azizi Azizan, Hazry Desa (UniMAP, Malaysia)

OS6-5 *Smart Technologies for Sustainable Conservation of Malaysia's National Heritage Buildings: A Triple-Bottom-Line Perspective*
Muhammad Nazrul Naim Md Zain, M. Azizi Azizan, Hazry Desa (UniMAP, Malaysia)

OS6-6 Smart Engineering Diagnostics for Heritage Structure Health Assessment Using Integrated NDT and AI Analysis
Muhammad Adib Syahmi Muhammad, M. Azizi Azizan, Hazry Desa (UniMAP, Malaysia)

OS6-7 *Intervention Measures and Culturally Formed Engineering in Heritage Buildings*
Mimi Natasha Jamal, M. Azizi Azizan, Hazry Desa (UniMAP, Malaysia)

11:00-12:00 GS1 Machine Learning I (4)

Chair: Dengchuan Cai (National Yunlin University of Science and Technology, Taiwan)

GS1-1 *Development of functional differentiation in recurrent neural networks by mutual information regulation*
Yuki Tomoda, Yutaka Yamaguti (Fukuoka Institute of Technology, Japan)

GS1-2 *A Deep Learning-Based Shopping Support Method for a Visually Impaired Person*
Takaya Yamaguchi, Seiji Ishikawa, Yui Tanjo (Kyushu Institute of Technology, Japan)

GS1-3 *Spatial-Temporal Analysis of Earthquakes for Urban Resilience Using Machine Learning*
Adessarman Muhammad Sahlan[1], Bart Dewancker[1], Mohammad Albaroudi[2], Raji Alahmad[2], Fahd Moumni[2,3], Ornella Okogo [4]
([1]The University of Kitakyushu, Japan) ([2]Kyushu Institute of Technology, Japan) ([3]MicroOrbiter Inc, Japan) ([4]Engineering School of the City of Paris, EIVP, France)

GS1-4 *Modeling Sleep-Stage Transitions in EEG with a Recurrent Neural Network*
Nikolas Acquaviva, Yutaka Yamaguti (Fukuoka Institute of Technology, Japan)

14:20-15:50 OS12 Mathematical Informatics-1 (6)
Chair: Amane Takei (University of Miyazaki, Japan)
Co-Chair: Ryuusuke Kawamura (University of Miyazaki, Japan)

OS12-1 *Broadening Access to Creative Experiences with MR 3D Painting*
Takumi Ishimaru, Yu Oshikawa, Shizuki Nokura, Satoshi Ikeda, Kenji Aoki, Kaoru Ohe, Amane Takei, Ryuusuke Kawamura, Makoto Sakamoto
(University of Miyazaki, Japan)

OS12-2 *Proposal of a Muscle Training Method using EMG Visualization via Machine Learning*
Yu Oshikawa, Takumi Ishimaru, Shizuki Nokura, Satoshi Ikeda, Kenji Aoki, Kaoru Ohe, Amane Takei, Ryuusuke Kawamura, Makoto Sakamoto
(University of Miyazaki, Japan)

OS12-3 *Unsupervised Defect Detection for Automatic Shiitake Sorting*
Shizuki Nokura[1], Leona Kimura[1], Takumi Ishimaru[1], Yu Oshikawa[1], Satoshi Ikeda[1], Kenji Aoki[1], Kaoru Ohe[1], Amane Takei[1], Ryuusuke Kawamura[1], Makoto Sakamoto[1], Kazuhide Sugimoto[2]
([1]University of Miyazaki, Japan), ([2]SUGIMOTO Co., Ltd., Japan)

OS12-4 *Language Modeling of Discretized Numerical Time Series: An Empirical Study Using Transformers*
Daiya Matsuyo[1], Makoto Sakamoto[1], Takao Ito[2], Satoshi Ikeda[1]
([1]University of Miyazaki, Japan), ([2]Hiroshima University, Japan)

OS12-5 *Raising Issues with Evaluation Metrics for Predicting Highly Volatile Cryptocurrencies*
Hyuma Kai[1], Makoto Sakamoto[1], Takao Ito[2], Satoshi Ikeda[1]
([1]University of Miyazaki, Japan), ([2]Hiroshima University, Japan)

OS12-6 *Development of a Crisis-Avoidance Simulator Based on the Boids Model*
Taiyo Hidaka, Makoto Sakamoto, Kenji Aoki
(University of Miyazaki, Japan)

16:00-17:00 OS12 Mathematical Informatics-2 (4)
Chair: Amane Takei (University of Miyazaki, Japan)
Co-Chair: Ryuusuke Kawamura (University of Miyazaki, Japan)

OS12-7 *Microwave Parallel FEM based on Iterative Domain Decomposition Method*
Amane Takei, Makoto Sakamoto (University of Miyazaki, Japan)

OS12-8 *Study on GPGPU Computing of Subdomain Solver in High-Frequency Electromagnetic Field Analysis*
Biki Bidesh Biswas[1], Kento Ohnaka[1], Makoto Sakamoto[1], Amane Takei[1], Sota Goto[2]
([1]University of Miyazaki, Japan), ([2]University of Tokyo, Japan)

OS12-9 *Investigation of Features for Mango Yield Prediction using Long Short-Term Memory Networks*
Hiroshi Kurita[1], Ryuusuke Kawamura[1], Kazunori Yamaguchi[2], Makoto Sakamoto[1]
([1]University of Miyazaki, Japan), ([2]Miyazaki Agricultural Experiment Station, Japan)

OS12-10 *Comparative Study of Metal-Ion Adsorption and Gold Reduction by Crosslinked and non-crosslinked Sericin*
Kaoru Ohe, Yudai Yamaguchi, Tatsuya Oshima (University of Miyazaki, Japan)

Meeting Room 4
9:00-10:00 OS15 Human Machine Interface I (4) Online Presentation
Chair: Norrima Mokhtar (Universiti Malaya, Malaysia)
Co-Chair: Siti Sendari (Universitas Negeri Malang, Indonesia)

OS15-1 *Engineering Design and Numerical Simulations of Upper Limb Exoskeleton for Rehabilitation*
Pringgo Widyo Laksono[1], Eko Wahyu Abryandoko[1], Lobes Herdiman[1], Norrima Mokhtar[2]
([1]Universitas Sebelas Maret, Indonesia), ([2]Universiti Malaya, Malaysia)

OS15-2 *Performance Evaluation of Deep Learning-Based Resnet, MobileNetV2 and DenseNet Models for Road Lane Detection*
Joko Slamet Saputro[1], Ananda Putra Kanieza[1], Pringgo Widyo Laksono[1], Norrima Mokhtar[2]
([1]Universitas Sebelas Maret, Indonesia), ([2]Universiti Malaya, Malaysia)

OS15-3 *CommCity: An Integrated Multi-Modal Platform for Urban Disaster Resilience through Hybrid Route Optimization and AI-Driven Community Intelligence*
Mohd Heikal Husin[1], Azleena Mohd Kassim[1], Nor Shamira Sabri[1], Noor Farizah Ibrahim[1]
Siti Rahyla Rahmat[2]
([1] Universiti Sains Malaysia, Malaysia), ([2] Universiti Sains Malaysia, Malaysia)

OS15-4 *Bridging Design for Manufacturing and Assembly (DFMA) with High-Speed Vision -Robotics: Toward Integrated Design and Cycle Time Reduction in High-Mix Low-Volume Production*
Hendi Herlambang[1], Pringgo Widyo Laksono[1], Ilham Priadythana[1], Norrima Mokhtar[2]
([1]Universitas Sebelas Maret, Indonesia), ([2]Universiti Malaya, Malaysia)

11:00-11:45 OS17 Human Machine Interface II (3) Online Presentation
Chair: Norrima Mokhtar (Universiti Malaya, Malaysia)
Co-Chair: Pringgo Widyo Laksono (Universitas Sebelas Maret, Indonesia)

OS17-1 *Experimental Analysis of Energy-Aware Reward Function for Q-Learning in Single-Joint Robotic Manipulator*
Giri Wahyu Wiriasto[1,2], Dyah Lestari[1], Muhamad Syamsu Iqbal[2], Siti Sendari[1*] Norrima Mokhtar[3]
([1] Universitas Negeri Malang, Indonesia) ([2] Universitas Mataram, Indonesia)
([3] Universiti Malaya, Malaysia)

OS17-2 *Bearing Fault Identification System of Three-Phase Induction Motor Using Vibration Signal-based Backpropagation Neural Network*
Dwiky F. Syahbana[1], Muhammad Shandar F. Faseh[1], Fauzi I. Adhim[1], Norrima Mokhtar[2]
([1] Institut Teknologi Sepuluh Nopember, Indonesia), ([2] Universiti Malaya, Malaysia)

OS17-3 *Assistive Navigation Stick for the Blind*
Norul Ashikin Norzain, Mohd Azwan Ramlan, Hanisah Mohd Zali, Nik Nur Zuliyana Binti Mohd Rajdi, Maisarah Binti Lutfi (MAHSA University, Malaysia)

14:20-15:20 OS18 Human Machine Interface III (4) Online Presentation
Chair: Norrima Mokhtar (Universiti Malaya, Malaysia)
Co-Chair: Heshalini Rajagopal (MILA University, Malaysia)

OS18-1 *Ensemble of Convolutional Neural Networks (CNN) to classify different classes of demented Alzheimer's disease patients*
Amutha S[1], Nitish Menon[1], Dhanush R[1*], Heshalini Rajagopal[2]
([1]Vellore Institute of Technology Chennai, India), ([2]MILA University, Malaysia)

OS18-2 *Transfer Learning for Chinese Herbal Leaves Recognition: A Comparative Study of ResNet-50, DarkNet-53, SqueezeNet, EfficientNet-B0, and GoogLeNet*
Lyu SiQian[1], Heshalini Rajagopal[1*], Zaris Izzati Mohd Yassin[1], Peng Lean Chong[1], Norrima Mokhtar[2]
([1] MILA University, Malaysia), ([2] Universiti Malaya, Malaysia)

OS18-3 *Deep Learning for Paddy Leaf Dssssisease Segmentation: An Exploratory Study*
Muhammad Amirul Aiman Asri[1], Wenjunliang Zhang[1], Norrima Mokhtar[1*], Raza Ali[2], Takao Ito[3], M. Aziz Muslim[4], Siti Sendari[5], Pringgo Widyo Laksono[6], Tsutomu Ito[7]
([1]Universiti Malaya, Malaysia), ([2]Balochistan University of Information Technology, Pakistan), ([3]Hiroshima University, Japan), ([4]Universitas Brawijaya, Indonesia), ([5]Universitas Negeri Malang, Indonesia), ([6]Universitas Sebelas Maret, Indonesia), ([7]Ube National College of Technology, Japan)

OS18-4 *Performance Analysis of Paddy Disease Classification Using Multiple Yolo Models*
Wenjunliang Zhang[1], Shunta Kimura[2], Muhammad Amirul Aiman Asri[1], Norrima Mokhtar[1*], Heshalini Rajagopal[3], Ryosuke Harakawa[2], Masahiro Iwahashi[2], Rahmadwati[4], Takao Ito[5], Siti Sendari[6], Pringgo Widyo Laksono[7]
([1]Universiti Malaya, Malaysia), ([2]Nagaoka University of Technology, Japan), ([3]MILA University, Malaysia), ([4]Universitas Brawijaya, Indonesia), ([5]Hiroshima University, Japan), ([6]Universitas Negeri Malang, Indonesia), ([7] Universitas Sebelas Maret, Indonesia)

16:00-17:15 OS19 Research Towards the Renewable Energy and the Sustainable Development Goals (SDG's)-2 (5) Online Presentation
Chair: Ammar A.M. Al Talib (UCSI University, Malaysia)
Co-Chair: Takao Ito (Hiroshima University, Japan)

OS19-6 *Air Purifier and Humidifier using Water as Filter*
Koh Yong Chuan[1], Ammar A.M. Al-Talib[1], Sarah 'Atifah Saruchi[2], Firas Basim Ismail[3], ([1]UCSI University, Malaysia), ([2]Universiti Malaysia Pahang Al-Sultan Abdullah, Malaysia), ([3]Universiti Tenaga Nasional, Malaysia)

OS19-7 *Compact High Efficiency Solar Water Heater*
Lee Shi Wei[1], Ammar A.M. Al-Talib[1], Sarah 'Atifah Saruchi[2] ([1]UCSI University, Malaysia) , ([2]Universiti Malaysia Pahang Al-Sultan Abdullah, Malaysia)

OS19-8 *Smart Safety Features for Motorcyclists' Safety Using IoT: Integrated Blind-Spot Monitoring, Forward-Collision Alerts, and Crash Detection with Real-Time Notification*
Ismailarta Ali Mohamoud, Ahmed Suliman Khaled, Samy Elmasri, Faisal Yaqoob, Omar Wael, Noor Idayu Binti Mohd Tahir, Ammar A. M. Al-Talib (UCSI University, Malaysia)

OS19-9 *Weed Mapping and Management Prediction using Image Processing*
Osama Gariballa[1], Ammar A.M. Al-Taliby[1], Noor Idayu Mohd Tahir[2] ([1]UCSI University, Malaysia), ([2]King Fahd University Petroleum, Malaysia)

OS19-10 *Navigating the Future: Skills and Job Market Trends in Malaysia's Construction Sector*
Cheah Ye Qun, Salihah Surol, Deprizon Syamsunur (UCSI University, Malaysia)

Meeting Room 5

14:20-15:35 OS4 Applied Machine Learning and Intelligent Systems-1 (5) Online Presentation

Chair: Kasthuri Subaramaniam (Universiti Malaya, Malaysia)

Co-Chair: Abdul Samad Bin Shibghatullah (Universiti Tenaga Nasional, Malaysia)

OS4-1 *Comparative Performance Analysis of Random Forest and SVM Classifiers in Food Image Recognition*

Eason Yan Yi Chen[1], Kasthuri Subaramaniam[2], Shayla Islam[3], Oras Baker[4], Raenu Kolandaisamy[5]

([1,3,5]UCSI University, Malaysia, [2]Universiti Malaya, Malaysia, [4]Ravensbourne University London, UK)

OS4-2 *Optimized Ensemble Learning Framework for Early Cardiac Risk Prediction Using Random Forest and XGBoost*

Oras Baker[1], Kasthuri Subaramaniam[2], Sellappan Palaniapan[3], Abdul Samad Bin Shibghatullah[4]

([1]Ravensbourne University London, UK, [2]Universiti Malaya, Malaysia,
[3]Help University, Malaysia, [4]Universiti Tenaga Nasional, Malaysia)

OS4-3 *A Bayesian Approach to Pilot Trial Inference in Rare Disease Research: Application to Spinal Muscular Atrophy*

Sellappan Palaniapan[1], Kasthuri Subaramaniam[2], Oras Baker[3]

([1]Help University, Malaysia, [2]Universiti Malaya, Malaysia, [3]Ravensbourne University London, UK)

OS4-4 *Ensemble Learning Framework for Robust Malware Classification: Integrating Feature-Optimized Voting Classifiers*

Oras Baker[1], Kasthuri Subaramaniam[2], Sellappan Palaniapan[3], Abdul Samad Bin Shibghatullah[4]

([1]Ravensbourne University London, UK, [2]Universiti Malaya, Malaysia,
[3]Help University, Malaysia, [4]Universiti Tenaga Nasional, Malaysia)

OS4-5 *Behavioural Analysis and Machine Learning for Social Media Bot Detection: A Comparative Study of Random Forest, SVC, and Decision Trees*

Kasthuri Subaramaniam[1], Oras Baker[2], Sellappan Palaniapan[3], Umm E Mariya Shah[4], Chit Su Mon[5]

([1]Universiti Malaya, Malaysia, [2]Ravensbourne University London, UK,
[3]Help University, Malaysia, [4]International Islamic University Malaysia, Malaysia,
[5]Heriot-Watt University Malaysia, Malaysia)

16:00-17:15 OS4 Applied Machine Learning and Intelligent Systems-2 (5) Online Presentation

Chair: Kasthuri Subaramaniam (Universiti Malaya, Malaysia)

Co-Chair: Abdul Samad Bin Shibghatullah (Universiti Tenaga Nasional, Malaysia)

OS4-6 *Design and Development of a Web-Based Enrichment Management System with Academic Progress (EMSAP)*

Tee Wen Jun[1], Kasthuri Subaramaniam[2], Saleh Abdulalem Ali Mohammed[3], Oras Baker[4], Abdurrahman Bin Jalil[5]

([1,3]UCSI University, Malaysia, [2]Universiti Malaya, Malaysia,
[4]Ravensbourne University London, UK, [5]Universiti Teknologi Mara, Malaysia)

OS4-7 *High-Accuracy Machine Learning Models for Cervical Cancer Prediction Using Ensemble Techniques and Class Imbalance Correction*
Oras Baker[1], Kasthuri Subaramaniam[2], Sellappan Palaniapan[3]
([1]Ravensbourne University London, UK, [2]Universiti Malaya, Malaysia, [3]Help University, Malaysia)

OS4-8 *Machine Learning-Based Detection of Cyberbullying in Social Media Texts: A New Zealand Contextual Study*
Oras Baker[1], Kasthuri Subaramaniam[2], Sellappan Palaniapan[3], Dobrila Lopez[4], Abdurrahman Bin Jalil[5]
([1]Ravensbourne University London, UK, [2]Universiti Malaya, Malaysia,
[3]Help University, Malaysia, [4]Eastern Institute of Technology, New Zealand,
[5]Universiti Teknologi Mara, Malaysia)

OS4-9 *On a Hybrid Modeling of Specific Biohydrodynamic Phenomena*
Asiya Zhumanazarova[1] and Tabiga Zhumanazarova[2]
([1]Almaty Technological University, Kazakhstan and [2]Independent Researcher, Kazakhstan)

OS4-10 *FruitSense: An Android-Based Fruit Quality Detection Mobile Application Using Machine Learning and Image Processing*
Evelyn Levina Diva (UCSI University, Malaysia), Umm E Mariya Shah (International Islamic University, Malaysia), Samar Ghazal Mohammed Abdullah (UCSI University, Malaysia), Heshalini Rajagopal (MILA University, Malaysia), Kasthuri Subaramaniam (Universiti Malaya, Malaysia), Yasir Mehmood (Syslab Technologies Sdn Bhd, Malaysia), Atif Mahmood (INTI International University, Malaysia)

February 1 (Sunday)

Meeting Room 32

9:00-10:30 OS7 AI System and Space Design Toward Co-Existence of Humans and Robots -1(6)

Chair: Yuichiro Tanaka (Kyushu Institute of Technology, Japan)

Co-Chair: Hakaru Tamukoh (Kyushu Institute of Technology, Japan)

OS7-1 *Pose Diversity Improves Object Detection Generalization*
Tomoya Shiba, Akihiro Suzuki, Naoki Yamaguchi, Ryoga Maruno, and Hakaru Tamukoh
(Kyushu Institute of Technology, Japan)

OS7-2 *A Robot Grasping Framework for Flexible and Amorphous Objects Using Skeleton Estimation*
Ryoga Maruno, Naoki Yamaguchi, Akihiro Suzuki, Tomoya Shiba, and Hakaru Tamukoh
(Kyushu Institute of Technology, Japan)

OS7-3 *Preliminary Study of Speech Denoising Using One-Dimensional Convolutional Reservoir Computing*
Digisha, Rohan Saini, Aryan Rakheja, Hakaru Tamukoh, and Yuichiro Tanaka
(Kyushu Institute of Technology, Japan)

OS7-4 *Deep Reservoir Computing Based Lightweight Model for Isolated Sign Language Recognition*
Nitin Kumar Singh, Arie Rachmad Syulistyo, Yuichiro Tanaka, and Hakaru Tamukoh
(Kyushu Institute of Technology, Japan)

OS7-5 *Real-Time Religious Ritual Body Recognition Using an FPGA System*
Dinda Pramanta (Kyushu Institute of Information Sciences, Japan) and
Hakaru Tamukoh (Kyushu Institute of Technology, Japan)

OS7-6 *Development of an Action Planning System using Explainable AI for Home Service Robots*
Takashi Akamatsu and Yuma Yoshimoto
(National Institute of Technology, Kitakyushu College, Japan)

10:50-11:35 OS7 AI System and Space Design Toward Co-Existence of Humans and Robots -1(3)

Chair: Yuichiro Tanaka (Kyushu Institute of Technology, Japan)

Co-Chair: Hakaru Tamukoh (Kyushu Institute of Technology, Japan)

OS7-7 *The Development of a Control System for Robot Operation Using EEG*
Haruki Miura and Yuma Yoshimoto (National Institute of Technology, Kitakyushu College, Japan)

OS7-8 *Application and Impression Evaluation of AI Robot Technology in Biophilic Design*
Kairi Manabe, Hiroaki Miyauchi, Keitaro Ito, Tomomi Sudo, Naoto Ishizuka, Akinobu Mizutani, Hakaru Tamukoh, Yuichiro Tanaka, Leon Furuya, Kei Wakabayashi, and Hirofumi Tanaka
(Kyushu Institute of Technology, Japan)

OS7-9 *Basic Research on Movement Failure Condition for Home Service Robots — Mock-up Evaluation of Step Heights, Corridor Widths, and Under-Furniture Clearances —*

Suzuka Tachibana, Ren Matsuoka, Naoto Ishizuka, Akinobu Mizutani, Tomomi Sudo, Keitaro Ito, Hakaru Tamukoh, and Hirofumi Tanaka (Kyushu Institute of Technology, Japan)

Meeting Room 33
9:00-9:45 GS5 Robotics & AI (3)
Chair: Akira Nakamura (Saitama Institute of Technology, Japan)

GS5-1 *Selection of Error Recovery Path Using Optimization of Evaluation Functions*
Akira Nakamura*[1] and Kensuke Harada*[2]
(*[1] Saitama Institute of Technology, *[2] Osaka University, Japan)

GS5-2 *Learning Interpretable Latent Representations from Single-Cell RNA-seq with VAE and Mutual Information*
Tomohito Yamamura, Yutaka Yamaguti (Fukuoka Institute of Technology, Japan)

GS5-3 *A Preliminary Study on Morphological Component Analysis for Arrhythmia Detection in ECG Signals from the MIT-BIH Arrhythmia Database*
Faustine Faccin[1,3,4], Diunuge Buddhika Wijesinghe[2], Rena Kato[2], Kosei Shibata[2], Shabbir Mahmood[2], Hodaka Inoue[1], Pauline Guyot[4], Laurent Bougrain[3,5] and Hiroaki Wagatsuma[2]
([1]Université de Lorraine, CNRS, CRAN, France, [2]Kyushu Institute of Technology, Japan, [3]Université de Lorraine, CNRS, LORIA, France, [4]NOVIGA, France, [5]Sorbonne Université, Institut du Cerveau – Paris Brain Institute (ICM), France)

10:50-11:35 OS8 Software Development Support Method (3)
Chair: Tetsuro Katayama (University of Miyazaki, Japan)
Co-Chair: Tomohiko Takagi (Kagawa University, Japan)

OS8-1 *A Design Testing Method Using Formal Models Based on EPNAT and ESTG for Web Applications*
Takeru Amo[1], Tetsuro Katayama[2], Tomohiko Takagi[1]
[1] Kagawa University, Japan, [2] University of Miyazaki, Japan

OS8-2 *Extension to Support Multi-Class Specification in BWDM that Generates Test Cases from VDM++ Specification*
Tomohiro Takahashi*, Nobuya Takahashi*, Tetsuro Katayama*, Yoshihiro Kita†
*University of Miyazaki, Japan, †University of Nagasaki, Japan

OS8-3 *Extension of ASLA Which Is a Segmentation and Labeling Tool for Application to New Document Formats and Improvement of Label Generation Accuracy*
Chihaya Takuma*, Nobuya Takahashi*, Tetsuro Katayama*, and Yoshihiro Kita†
*University of Miyazaki, Japan, †University of Nagasaki, Japan

Meeting Room 4
10:50-12:35 OS9 Biological and Intelligent Information System (7)
Chair: Masayuki Fujiwara (Komatsu University, Japan)
Co-Chair: Kazuma Sakamoto (Komatsu University, Japan)
Co-Chair: Masaya Nakahara (Osaka Electro-Communication University, Japan)

OS9-1 *Speaker Identification Method Using Textual Data and Acoustic Features in Multi-Speaker Meetings with Focus on Meeting Progress*
Teruya Minakuchi, Kazuma Sakamoto, Iori Iwata, Yoshihiro Ueda (Komatsu University, Japan)

OS9-2 *Basic Research on Automating Edge and Side Determination in Table Tennis*
Reo Ishii, Kazuma Sakamoto, Iori Iwata, Riku Kaiba, Yoshihiro Ueda (Komatsu University, Japan

OS9-3 *Basis Research on Attended Objects Estimation Using Gaze Information and Object*
Hiroto Kawabe, Kazuma Sakamoto, Tomoya Senda, Yoshihiro Ueda (Komatsu University, Japan)

OS9-4 *Research on Supporting Detection of Communication Fraud Using BERT*
Ryuta Okabe, Kazuma Sakamoto, Iori Iwata, Yoshihiro Ueda (Komatsu University, Japan)

OS9-5 *Influence of Comment Sentiment on YouTube Subscribers and View Counts by Genre*
Kyoya TAKIGUCHI, Masaya NAKAHARA (Osaka Electro Communication University, Japan)
Kazuma SAKAMOTO (Komatsu University, Japan)

OS9-6 *Evaluation of the Effectiveness of a Voice-Based Special Fraud Experience System Using Generative AI*
Masaya Nakahara, Kyoya Takiguchi, Taketo Ueno, Yuya Doi, Ryusei Noguchi, Tenma Matsumoto, Ryotaro Teranishi (Osaka Electro Communication University, Japan)

OS9-7 *Electroencephalographic Responses to Three Types of Auditory Stimuli*
Akihiro Matsumoto[1], Koushi Nishioka[1], Hironari Machida[1] and Masayuki Fujiwara[1,2]
([1]Komatsu University, Japan), ([2]Japan Advanced Institute of Science and Technology, Japan)

Farewell Party

Abstracts

PS Abstracts (3)

PS1 Multimodal AI Framework for Urban Environmental Intelligence Integrating Hazard and Risk Prediction

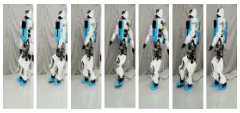
Young-Im Cho (Gachon University, Republic of Korea)

The study presents an integrated AI framework for environmental intelligence in smart cities, combining 3D ecological analysis with multivariate risk prediction. The proposed system unifies LiDAR-based tree-structure modeling with real-time underground hazard and carbon-emission forecasting. A PointNet++-based module extracts structural indicators from urban trees, while a Temporal Fusion Transformer (TFT) predicts emissions and facility risks using multimodal public and sensor data. To enhance interpretability, a SHAP-based cause-contribution layer quantifies feature influence, and a constraint-aware action model generates operational recommendations. Experimental evaluation demonstrates that multimodal integration improves predictive accuracy and provides interpretable decision support. The framework introduces a generalizable theoretical model for cross-domain urban environmental analytics.

PS2 AI Enabled Intelligent Robotics: Evolving Applications and Opportunities

Ren C. Luo (National Taiwan University, Taiwan)

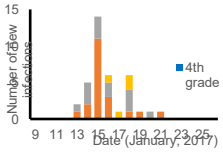
Recently the development of AI enabled large-scale models has given robots the ability to be applied to more complex scenes. That is, the robot will rely on the large model to give embodied artificial intelligence, which means that the robot has intelligent behavior and adaptability, and it can interact with the environment and implement actions. It is estimated that the global market size of robots in the intelligent manufacturing automation and many services such as hospital, elder care, hotel, restaurant etc. will reach tens of billions of dollars per year after 2030. It is perceived that embodied intelligent robots consist of components such as sensors controllers, robotic arms, and dexterous hands to achieve perception and interaction with the environment. Enhanced by artificial intelligence, they have the capabilities of semantic understanding, human-computer interaction, and autonomous decision-making to achieve task understanding and response. The aforementioned issues, challenges and opportunities will be discussed including some research results on intelligent robotics control and manufacturing automation with video demo from our NTU intelligent robotics and automation (iCeiRA) Lab.



PS3 Multi-Agent Simulation of Influenza Epidemics and Evaluation of Infection Control Measures

Saori Iwanaga (Japan Coast Guard Academy, Japan)

Influenza patients are contagious even before symptoms appear, making it difficult to determine the infection status, such as when, where, and from whom they were infected. In this study, we first collected, recorded, and analyzed the spatiotemporal behavioral history and clinical information of all students at a boarding school during multiple influenza epidemics. Next, we proposed a spatiotemporal mathematical model based on this data and conducted multi-agent simulations (MAS). The results confirmed that the infection rate was high until the first patient was discovered, and that infection control measures reduced the infection rate. Finally, we evaluated the effectiveness of several infection control measures against influenza epidemics.



OS Abstracts

OS1 Industrial Artificial Intelligence Robotics (11)

Chair Eiji Hayashi (Kyushu Institute of Technology, Japan)

OS1-1 Design and Development of a ROS2–Android Based Remote Control System for an Autonomous Beach Cleaning Robot

Weizheng Pan, Chi Jie Tan, Eiji Hayashi (Kyushu Institute of Technology, Japan)

This study presents a ROS2–Android based remote control framework for an autonomous beach cleaning robot. The system employs a FastAPI–Retrofit architecture to enable seamless bidirectional communication between the Android application and ROS2 nodes. High-level control functions, including robot startup, tracking, and camera streaming, are implemented via RESTful APIs, while real-time GPS and video feedback provide situational awareness. OpenStreetMap is integrated for intuitive path visualization and route planning. By combining modular ROS2 node design with lightweight network protocols, the proposed approach ensures robust connectivity, scalability, and user accessibility in outdoor environments. Experimental evaluation demonstrates reliable performance and responsiveness, confirming the system's effectiveness for remote operation and real-time monitoring of autonomous coastal cleaning robots.

OS1-2 Improved Multi-Object Tracking System Using 3D–2D Image Data Fusion for Beach Cleaning Robot

Rut Yatigul, Tan Chi Jie, M.A Munjer, Wisanu Jitviriya, Teppakorn Sittiwanchai, Watcharin Tangsuksant, Eiji Hayashi
(Kyushu Institute of Technology, Japan, King Mongkut's University of Technology Thailand)

This research introduces a 3D-2D image data fusion mechanism to enhance Multi-Object Tracking for marine debris detection. Traditional systems relying solely on 2D data cannot identify long-occluded objects that leave and re-enter the frame. The proposed system combines RGB and depth data from an RGBD camera on a Beach Cleaning Robot, registering each tracked object with 3D coordinates referenced to the robot's starting point for accurate ID reassignment. The system achieved 80.02% reidentification accuracy in simulation and 78.33% in real-world tests despite odometry drift. Results demonstrate that 3D-2D fusion provides robust tracking for long-occluded objects, offering practical value for Multi-Object Tracking across computer vision applications.

OS1-3 LLM-Supervised Genetic Programming for Multi-Robot Behavior Tree Evolution

Chi Jie Tan, M.A Munjer, Weizheng Pan, Eiji Hayashi, Way Soong Lim
(Kyushu Institute of Technology, Japan, Multimedia University, Malaysia)

A genetic programming framework supervised by large language models (LLMs) is presented for the evolution of multi-robot behavior trees. In this framework, LLMs are utilized as adaptive supervisors to regulate evolutionary processes. The method consists of two phases: (i) mutation rate adaptation, in which convergence patterns, diversity metrics, and fitness trajectories are evaluated at epoch boundaries to adjust evolutionary parameters; and (ii) diversity injection, in which targeted population seeding and intervention strategies are applied when premature convergence is detected. By incorporating context-aware parameter control and systematic diversity management, several limitations of traditional genetic programming are mitigated. Preliminary results indicate improvements in both convergence speed and solution quality under LLM-supervised guidance.

OS1-4 Tree Mapping in Forests with LiDAR–RGB Fusion

M.A Munjer, Tan Chi Jie, Boufaroua Vincent, Eiji Hayashi (Kyushu Institute of Technology, Japan)

This study presents a LiDAR–RGB fusion framework for automated tree stem detection and mapping, emphasizing Kalman filter–based estimation. YOLO detections are fused with LiDAR point clouds and accumulated in a global frame using odometry. The Kalman filter integrates sequential observations, suppresses noise, and ensures stable mapping. Field experiments show that predicted inter-tree distances align closely with laser-based ground truth, with minor deviations under partial visibility. Detection performance confirms robustness, achieving near-perfect Precision, 0.89 Recall, 0.91 Accuracy, and an F1-score of 0.94. Results demonstrate that Kalman filtering enables reliable tree position mapping, suitable for automated forest inventory and monitoring.

OS1-5 System development of autonomous mobile field robots - Feature Matching Method for Expanding Human Tracking Functions -

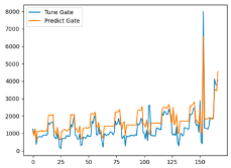
Satoshi Yamaguchi, Eiji Hayashi (Kyushu Institute of Technology, Japan)

In recent years, the increase in marine litter has become a serious environmental issue. To reduce the number of debris washed ashore, coastal cleanup activities are being conducted nationwide. However, collecting large and heavy debris is extremely difficult in coastal areas with unstable footing. Therefore, we are developing an autonomous mobile field robot for collaborative tasks, in which humans collect debris and the robot transports it. In this study, we propose a method to re-identify the target person using AKAZE-based feature point matching, with the aim of enabling the robot's human-following function to automatically resume tracking when the target re-enters the frame after leaving it.

OS1-6 Support System for Editing Performance Information for an Automatic Piano -Construction of a System to Extract Elements from Score and Real Performance-

Ryuta Matsuda, Eiji Hayashi (Kyushu Institute of Technology, Japan)

This study developed a new element extraction system to create expressive MIDI data for an automatic piano, replacing a prior system that relied on outdated software. The system extracts parameters from MusicXML scores and real MIDI performances (e.g., from Ashkenazy's playing). The extraction component showed high precision, achieving up to 100% agreement with the score's note count, outperforming the previous study. However, when inputting the extracted data into the inference system, the prediction accuracy was low (e.g., Velo correlation 0.41, Step correlation 0.39). This is attributed to the inadequate matching system used to combine the score and performance elements. Future work will focus on improving the element matching system to enhance inference accuracy.



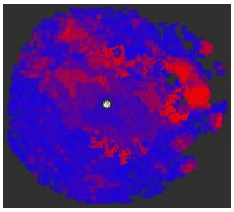
OS1-7 Enhancing Squeeze-and-Excitation Networks with Mixed Pooling for Image Classification

Rut Yatigul, Teppakorn Sittiwanchai, Aran Blattler, Eiji Hayashi, Wisanu Jitviriya
(King Mongkut's University of Technology Thailand, Kyushu Institute of Technology, Japan)

This research introduces a mixed pooling mechanism to improve Squeeze-and-Excitation Networks for image classification. Traditional Squeeze-and-Excitation Networks use average pooling for squeeze operations to extract feature information fed to fully connected layers for channel weight assignment. The proposed mixed pooling approach fuses max pooling and min pooling at equal ratios, replacing average pooling in the SE attention block. Evaluation on SE-VGG16 architecture using a five-class tomato ripeness dataset with 10-fold cross-validation shows superior performance, with VGG16+SE (Mixed Pool) achieving an average F1 score of 0.8562. Mixed pooling proves to be a robust strategy that improves feature representation in Squeeze-and-Excitation Networks.

OS1-8 Merging of Geometric and 3D Semantic Costmaps for Navigation in Complex Outdoor Environments

Boufaroua Vincent, Chi Jie Tan, Eiji Hayashi
(Kyushu Institute of Technology, Japan)



Outdoor autonomous navigation presents several challenges, including the nature and geometry of the terrain on which the robot evolves. These characteristics of the environment must be carefully considered to compute the safest and most efficient path towards the robot's goal, while avoiding obstacles or getting stuck. This study aims to integrate these terrain characteristics into the robot's path planning by generating and merging two complementary costmaps. The first costmap represents the terrain's geometry, computed from the slopes derived from the LiDAR point cloud projected to a 2D grid. The second costmap models the terrain's nature, obtained through semantic segmentation of RGB-D images, in combination with the RTAB-Map SLAM framework, to generate a semantically enriched map.

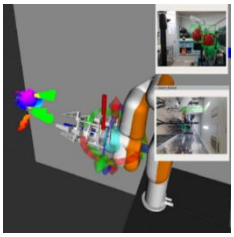
OS1-9 The research on food segmentation technology in the ready-to-eat food industry

Yamato Fukuiri, Gamolped Prem, Eiji Hayashi (Kyushu Institute of Technology, Japan)

In recent years, the externalization of food has progressed in Japan, leading to increased demand in the ready-to-eat meal industry. Meanwhile, the decline in the labor force and the aging population have made improving labor productivity an urgent issue. Previous studies enabled the grasping of karaage (fried chicken) and onigiri (rice balls) using real-time object detection; however, challenges remain in the accuracy of instance segmentation and in handling high-demand foods such as tamagoyaki (rolled omelets) and hanba-gu(hamburgers). This study aims to identify the most suitable deep learning model for improving recognition accuracy and to construct a food dataset for bento meals that meets consumer needs.

OS1-10 Deep Reinforcement Learning with NVBlox TSDF Mapping for Grasp Optimization Using a Custom Force-Sensing Three-Finger Gripper

Yon Pang Ja Sin, Bytyqi Vjosa, Gamolped Prem, Eiji Hayashi (Kyushu Institute of Technology, Japan)



This study aims to develop a deep reinforcement learning (DRL) framework for optimizing grasping poses of an xArm7 robotic manipulator equipped with a custom three-finger gripper integrated with force sensors. The system focuses on combining YOLO-based tomato detection and NVBlox-generated TSDF and ESDF mapping with a Soft Actor-Critic (SAC) agent that outputs roll–pitch–yaw orientation and XYZ positional offsets for the gripper. Multi-point collision evaluation is performed using STL-sampled finger points with ESDF-based distance feedback and force-sensor responses for safe contact assessment. The framework is designed for real-time operation on ROS2 Humble with GPU acceleration, aiming for adaptive and robust online grasp learning in agricultural environments.

OS1-11 Robust round object occlusion identification and localization using an algebraic nine-field method for local exploitation

Anna Biedermann, Eiji Hayashi (Kyushu Institute of Technology, Japan)

Occlusions of fruit and vegetables in natural orchard environments diminish accurate harvesting success rates. The random distribution of fruit cluster growth and complexity in occlusion areas poses challenges in the identification of key points required for fully automated picking. This paper presents an algebra-based approach to occlusion detection and localization of round objects such as tomatoes seen in 2D planes. We have proposed an automated enrichment of 2D object relations by identification and localization of occlusion, which utilizes second order Polynomials fitted to nine zones of segmentation masks to determine the direction and area of occlusion.

OS2 Safety Intelligent Life Trend and Challenge (4)

Chair I-Hsien Liu (National Cheng Kung University, Taiwan)
Co-Chair Chu-Fen Li (National Formosa University, Taiwan)

OS2-1 A Dynamic Bayesian Game Model for Emergency Vehicle Evasive Decision-Making at Unsignalized Intersections

Zhi-Yuan Su, Wei-Xiang Li, Jung-Shain Li, I-Hsien Liu, Kuan-Ting Lee
(National Cheng Kung University, Taiwan)

This study addresses the complex challenge of decentralized decision-making for mixed-V2X and non-V2X-equipped vehicles at unsignalized intersections. We propose a Dynamic Bayesian Game framework where the game is re-evaluated at each simulation step based on the evolving traffic environment. To capture real-world uncertainty, we introduce incomplete information stemming from a detailed V2X communication simulation. This layer models physical-layer properties, including Signal-to-Noise Ratio based on path loss and AWGN, to determine packet reception success. The framework is validated in a MATLAB-SUMO co-simulation, demonstrating robust safety and efficiency under communication uncertainty. A key component of our framework is the decentralized process of belief formation. Each agent autonomously constructs a probabilistic belief over its opponents' unobserved types (e.g., driving styles). This belief is updated dynamically, using precise information from successfully received V2X messages or reverting to a shared prior distribution upon communication failure.

OS2-2 Challenges of Self-Driving Cars at Unsignalized Intersections

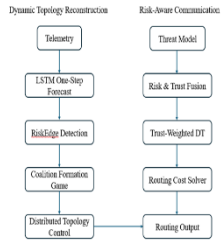
Kuan-Ting Lee, I-Hsien Liu, Wei-Xiang Li (National Cheng Kung University, Taiwan)
Chu-Fen Li (National Formosa University, Taiwan)

Autonomous driving in mixed traffic remains one of the most challenging topics in intelligent transportation systems (ITS). This study focuses on the interaction between autonomous vehicles (AVs) and human-driven vehicles (HVs) at unsignalized intersections, where right-of-way decisions are made without external coordination. A comprehensive set of microscopic simulation scenarios was constructed to analyze yielding and non-yielding behaviors under varying approach conditions, including combinations of straight, left-turn, and right-turn movements, as well as variations in approach speed and acceleration. The results show that, despite the high overlap among time-related features, the proposed analytical framework can still distinguish between behavioral outcomes, revealing the intrinsic uncertainty and variability of human–machine decision interactions. This work highlights the behavioral challenges faced by self-driving vehicles in complex urban environments and provides a reproducible foundation for future studies on intelligent transportation and vehicle-to-everything (V2X) systems in mixed traffic.

OS2-3 Endogenous Anti-Jamming Strategies for UAV Swarms: Dynamic Topology Reconstruction and Risk-Aware Communication

Ching-Fang Yang (Cheng Shiu University, Taiwan)
Kuan-Ting Lee (National Cheng Kung University, Taiwan)

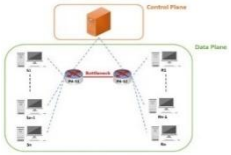
In adversarial environments, unmanned aerial vehicle (UAV) swarms require resilient communication to maintain coordinated operations. An endogenous anti-jamming framework is proposed that couples Dynamic Topology Reconstruction (DTR), driven by one-step link-quality forecasting and coalition formation, with Risk-Aware Communication (RAC), a trust-weighted decision tree classifier (TWDT) that steers routing away from compromised links and nodes. The system and threat models are formalized, per-link risk and trust fusion are derived, and distributed algorithms with complexity bounds are presented, covering barrage, reactive, and smart jamming. A reference implementation targets resource-constrained onboard processors and edge coordinators. The approach is designed to improve packet-delivery ratio, reduce outage time, and limit handover churn under strong interference, while keeping computation and signaling overhead bounded.



OS2-4 Lyapunov-Driven Adaptive Queue Management for P4-Programmable SDN: Stability-Guaranteed Low-Latency Control against Bufferbloat

Wei-Xiang Lin[1], Ming-Syuan Wu[1], Ya-Chen Li[1]*, Wen-Shyang Hwang[1], Cheng-Han Lin[2], Yu-Chi Lin[1]
[1](National Kaohsiung University of Science and Technology, Taiwan), [2](Fooyin University, Taiwan)

As Internet applications continue to expand, maintaining efficient network transmission has become increasingly challenging. Oversized router buffers often cause excessive queuing delays, a phenomenon known as bufferbloat. To address this problem, we propose a Lyapunov-based Adaptive Queue Management mechanism for Software-Defined Networking. The data plane utilizes P4-programmable switches for packet parsing and delay monitoring, enabling timely packet dropping during congestion. Meanwhile, the control plane dynamically adjusts queue thresholds to maintain stability under varying traffic conditions. Simulation results show that the proposed mechanism reduces queue length and latency compared with the CoDel algorithm, demonstrating its effectiveness in mitigating bufferbloat and improving network Quality of Service.



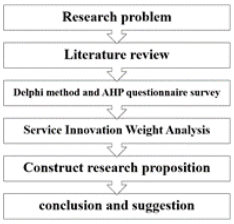
OS3 Trust and Innovation in AI-Driven Intelligent Living (4)

Chair I-Hsien Liu (National Cheng Kung University, Taiwan)
Co-Chair Jung-Shian Li (National Cheng Kung University, Taiwan)

OS3-1 Exploring the key factors of innovation in AI health management services using FAHP

Li-Min Chuang, Zong-Sheng Li (Chang Jung Christian University, Taiwan)

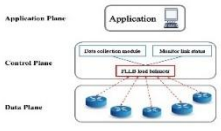
This study explores service innovation in AI-powered healthcare management, employing the four-facet theory (New service concept, new client interface, new service delivery system and technological options) combined with the Delphi method and the Fuzzy Analytic Hierarchy Process (FAHP) for analysis. The results indicate that the most critical indicators are cross-platform data integration, remote care and monitoring, AI algorithm accuracy, and data privacy and security. Experts emphasize that medical data standardization, remote application integration, algorithm reliability, and privacy protection will be core to the future development of AI-powered healthcare management.



OS3-2 Critical Success Factors of Taiwan's Multi-Level Marketing Industry in the AI-Driven Digital Era

Li-Min Chuang, Hsieh Tsung Hsien (Chang Jung Christian University, Taiwan)

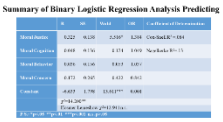
In recent years, AI and digital technology have developed rapidly, becoming deeply integrated into people's daily lives. Various business models and consumer habits are increasingly influenced by digitalization. Traditional multi-level marketing (MLM) models, centered around person-to-person, face-to-face communication, face the risk of becoming obsolete if they fail to adapt to the AI-driven digital age through digital transformation. The findings of this study will help companies develop effective strategies to address the rapidly changing market environment and consumer demands during this digital transformation. This study aims to explore the strategies and sustainable development of Taiwan's MLM industry in the AI-driven digital age. First, based on relevant domestic and international literature, including research findings on the multi-level marketing industry and international marketing strategies in the digital age, this study employed a modified Delphi method, inviting eight scholars and experts to discuss and reach a consensus. They identified four primary dimensions: "cross-border feasibility," "internet reach," "shopping convenience," and "marketing innovation." These dimensions were further broken down into three secondary dimensions, for a total of twelve. A Fuzzy Analytic Hierarchy Process questionnaire was then developed, with 13 industry representatives extracting the weights and rankings of each primary and secondary dimension regarding the "Key Success Factors of Taiwan's Multi-Level Marketing Industry in the AI Digital Era." This research then summarized its conclusions and constructed five major propositions. It is hoped that these findings will provide concrete advice for Taiwanese multi-level marketing practitioners, helping them to continue to thrive in the AI digital age.



OS3-3 Exploring the Relationship Between Moral Development and Internet-Triggered Academic Dishonesty Behavior among Cadets in Taiwan

Shu-Hua Huang (Air Force Institute of Technology, Taiwan)
I-Hsien Liu (National Cheng Kung University, Taiwan)

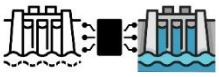
This study investigated the relationship between moral development and Internet-Triggered Academic Dishonesty (ITAD) behavior among military cadets in Taiwan. A mixed-methods design was employed, gathering data from 161 cadets who use a standardized moral development scale and a structured questionnaire assessing ITAD attitudes and behaviors. Quantitative analysis indicated that while cadets generally reported high levels of moral development, binary logistic regression revealed that higher moral maturity significantly predicted a reduced likelihood of engaging in ITAD. However, the overall explanatory power of this model was limited. Qualitative data analysis provided crucial context for this finding, revealing that cadets often held lenient moral judgments toward ITAD. Participants frequently rationalized these behaviors, indicating a belief that such actions do not necessarily constitute a fundamental moral defect. These findings highlight a complex interplay, and a potential disconnect, between cadets' moral reasoning and their situational ethics regarding academic integrity in the era of artificial intelligence.



OS3-4 A Novel Digital Twin Framework for Industrial Control System: Cybersecurity Testbed Trends and Challenges

Han-Yang Yu, Jung-Shain Li, I-Hsien Liu (National Cheng Kung University, Taiwan)

Conducting practical experimentation on live Industrial Control Systems is exceptionally difficult due to the significant risk of operational disruption. However, much cybersecurity research, relying on simplified simulations, is often challenged by its significant gap with real-world scenarios. Digital Twin technology is widely regarded as a key solution to this challenge, providing a safe virtual environment for testing and analysis. This study develops the CySEC-vRT virtualized testbed, integrating both IT and OT components within a segmented network architecture composed of a virtual firewall and dual Network Intrusion Detection Systems to achieve comprehensive observation and traffic monitoring. This study compares CySEC-vRT with representative Digital Twin solutions to analyze the trends and challenges of existing frameworks in ICS applications. It demonstrates how CySEC-vRT implements the core concepts of Digital Twin to enhance model observability and reproducibility, providing a feasible experimental foundation for subsequent application and validation in the ICS domain.



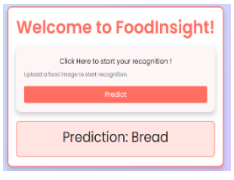
OS4 Applied Machine Learning and Intelligent Systems (10) Online Presentation

Chair Kasthuri Subaramaniam (Universiti Malaya, Malaysia)
Co-Chair Abdul Samad Bin Shibghatullah (Universiti Tenaga Nasional, Malaysia)

OS4-1 Comparative Performance Analysis of Random Forest and SVM Classifiers in Food Image Recognition

Eason Yan Yi Chen[1], Kasthuri Subaramaniam[2], Shayla Islam[3], Oras Baker[4], Raenu Kolandaisamy[5]
([1,3,5]UCSI University, Malaysia, [2]Universiti Malaya, Malaysia, [4]Ravensbourne University London, UK)

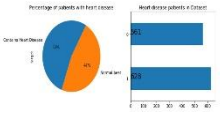
This research presents the design and implementation of an AI-based Food Recognition System capable of classifying food items from images to support dietary monitoring, health assessment, and automated meal tracking. The system employs machine learning algorithms trained on an extensive food image dataset, with Random Forest (RF) and Support Vector Machine (SVM) models evaluated for classification accuracy and robustness. Performance metrics, including accuracy, precision, recall, and F1-score, were computed to assess model effectiveness. A web-based interface was integrated to enable real-time image classification and user feedback, demonstrating the system's practicality and usability.



OS4-2 Optimized Ensemble Learning Framework for Early Cardiac Risk Prediction Using Random Forest and XGBoost

Oras Baker[1], Kasthuri Subaramaniam[2], Sellappan Palaniapan[3], Abdul Samad Bin Shibghatullah[4]
([1]Ravensbourne University London, UK, [2]Universiti Malaya, Malaysia,
[3]Help University, Malaysia, [4]Universiti Tenaga Nasional, Malaysia)

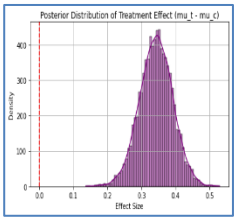
Cardiovascular disease remains a leading global cause of mortality, underscoring the urgent need for accurate, early-stage diagnostic systems that can reduce the burden on healthcare infrastructure. This study develops an autonomous machine learning framework for early cardiac risk detection using ensemble-based predictive modelling. This research employs a rigorous multi-phase methodology encompassing comprehensive literature analysis, data engineering, feature extraction, and algorithmic optimisation using Kaggle-sourced clinical datasets. Among the models evaluated, Random Forest (RF) and XGBoost. The study's significance lies in demonstrating that an optimised hybrid ensemble can achieve near real-time, high-fidelity cardiac risk prediction, offering a robust alternative to conventional diagnostic practices.



OS4-3 A Bayesian Approach to Pilot Trial Inference in Rare Disease Research: Application to Spinal Muscular Atrophy

Sellappan Palaniapan[1], Kasthuri Subaramaniam[2], Oras Baker[3]
([1]Help University, Malaysia, [2]Universiti Malaya, Malaysia, [3]Ravensbourne University London, UK)

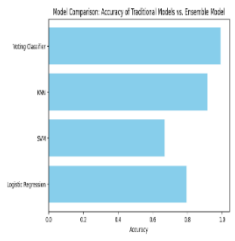
This study investigates a Bayesian framework for extrapolating evidence from limited pilot data to support the design of larger clinical trials, using spinal muscular atrophy as a representative case. Simulated pilot data were analysed through Bayesian linear regression. Posterior distributions were generated using Markov Chain Monte Carlo (MCMC) sampling, with diagnostic checks confirming convergence and credible posterior estimates. The results revealed a positive treatment effect with a 95% Highest Density Interval excluding zero, indicating strong evidence of efficacy even under data scarcity. The significance of this study lies in demonstrating that Bayesian modelling can enhance transparency, reproducibility, and regulatory readiness in rare disease trials.



OS4-4 Ensemble Learning Framework for Robust Malware Classification: Integrating Feature-Optimized Voting Classifiers

Oras Baker[1], Kasthuri Subaramaniam[2], Sellappan Palaniapan[3], Abdul Samad Bin Shibghatullah[4],
Chit Su Mon[5]
([1]Ravensbourne University London, UK, [2]Universiti Malaya, Malaysia,
[3]Help University, Malaysia, [4]Universiti Tenaga Nasional, Malaysia
[5]Heriot-Watt University Malaysia, Malaysia)

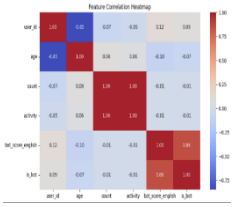
This study presents a novel ensemble learning framework that integrates Random Forest, Gradient Boosting, and a meta-level Voting Classifier to enhance malware detection performance. The methodology incorporates advanced feature engineering techniques, including entropy-based feature selection and structural byte analysis, using the ClaMP Integrated-5184 dataset. Experimental evaluation demonstrates that the proposed ensemble model significantly outperforms conventional classifiers such as Logistic Regression, Support Vector Machines, and K-Nearest Neighbours across all major metrics. The significance of this research lies in establishing classifier fusion as an effective paradigm for next-generation cybersecurity systems, providing a balanced solution to the persistent accuracy-adaptability trade-off in malware detection.



OS4-5 Behavioural Analysis and Machine Learning for Social Media Bot Detection: A Comparative Study of Random Forest, SVC, and Decision Trees

Kasthuri Subaramaniam[1], Oras Baker[2], Sellappan Palaniapan[3], Umm E Mariya Shah[4], Chit Su Mon[5]
([1]Universiti Malaya, Malaysia, [2]Ravensbourne University London, UK,
[3]Help University, Malaysia, [4]International Islamic University Malaysia, Malaysia,
[5]Heriot-Watt University Malaysia, Malaysia)

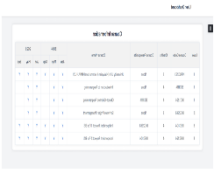
This study investigates the application of behavioural analytics and machine learning to the detection of social media bots, employing a quantitative research design implemented in Python. A labelled dataset of user activity was used to train and evaluate multiple models, including Random Forest, Support Vector Classifier, and Decision Tree algorithms. Model performance was assessed through cross-validation using accuracy, precision, recall, and F1-score metrics. The findings demonstrate that traditional machine learning models, when supported by robust feature engineering, can equal or surpass more complex approaches such as deep learning. The study's significance lies in advancing scalable, transparent, and computationally efficient frameworks for combating malicious automation on social platforms.



OS4-6 Design and Development of a Web-Based Enrichment Management System with Academic Progress (EMSAP)

Tee Wen Jun[1], Kasthuri Subaramaniam[2], Saleh Abdulalem Ali Mohammed[3], Oras Baker[4], Abdurrahman Bin Jalil[5]
([1,3]UCSI University, Malaysia, [2]Universiti Malaya, Malaysia,
[4]Ravensbourne University London, UK, [5]Universiti Teknologi Mara, Malaysia)

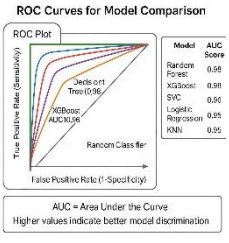
This study presents the design and development of the Enrichment Management System with Academic Progress (EMSAP), a web-based prototype aimed at enhancing workflow efficiency, reducing administrative delays, and improving user experience for students, event organisers, and administrators. A user requirement analysis was conducted using survey questionnaires. The prototype was implemented using HTML, CSS, JavaScript, PHP, and MySQL. Results indicated high user satisfaction, improved time management, and system efficiency. Future enhancements involve analytics dashboards, automated certificate generation, and mobile application integration to extend accessibility and performance.



OS4-7 High-Accuracy Machine Learning Models for Cervical Cancer Prediction Using Ensemble Techniques and Class Imbalance Correction

Oras Baker[1], Kasthuri Subaramaniam[2], Sellappan Palaniapan[3], Umm E Mariya Shah[4]
([1]Ravensbourne University London, UK, [2]Universiti Malaya, Malaysia,
[3]Help University, Malaysia, [4]International Islamic University Malaysia, Malaysia)

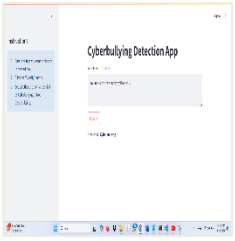
This study develops a machine learning-based predictive model for cervical cancer detection using a dataset of 835 patient records encompassing 36 clinical and demographic features. A systematic methodology was employed, including mean imputation for missing data, StandardScaler for feature normalisation, and the Synthetic Minority Oversampling Technique (SMOTE) to address class imbalance. Multiple algorithms, Decision Tree, Random Forest, XGBoost, Support Vector Machine, Logistic Regression, and K-Nearest Neighbours, were trained and evaluated using an 80/20 train-test split. The results confirm the feasibility of using ensemble-based models as reliable clinical decision-support tools for early cancer screening.



OS4-8 Machine Learning-Based Detection of Cyberbullying in Social Media Texts: A New Zealand Contextual Study

Oras Baker[1], Kasthuri Subaramaniam[2], Sellappan Palaniapan[3], Dobrila Lopez[4], Abdurrahman Bin Jalil[5]
([1]Ravensbourne University London, UK, [2]Universiti Malaya, Malaysia,
[3]Help University, Malaysia, [4]Eastern Institute of Technology, New Zealand,
[5]Universiti Teknologi Mara, Malaysia)

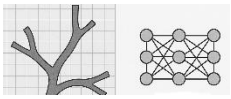
This study investigates the use of machine learning approaches to identify cyberbullying within social media text, focusing on New Zealand. The research develops and evaluates supervised machine learning models trained on a labelled dataset of X (Twitter) posts obtained from Kaggle. Text preprocessing involved data cleaning, tokenisation, lemmatisation using WordNetLemmatizer, and vectorisation through Term Frequency–Inverse Document Frequency (TF–IDF). Several algorithms, including Support Vector Machine (SVM), Naïve Bayes, Logistic Regression, and Random Forest, were implemented and compared using performance metrics. A Streamlit-based web application was developed to operationalise the most effective model, allowing users to detect cyberbullying in real time.



OS4-9 On a Hybrid Modeling of Specific Biohydrodynamic Phenomena

Asiya Zhumanazarova[1] and Tabiga Zhumanazarova[2]
([1]Almaty Technological University, Kazakhstan and [2]Independent Researcher, Kazakhstan)

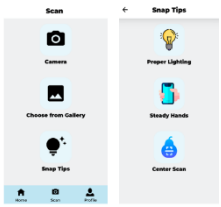
This paper investigates modeling approaches for specific biohydrodynamic processes associated with impaired vascular elasticity and other pathological blood flow conditions. It considers the potential generalization of mathematical models and their integration with machine learning techniques to enhance the accuracy of analysis and prediction. The theoretical foundations and conceptual structure of a proposed hybrid approach are presented, highlighting its scientific and practical relevance as a promising direction in applied mathematics and biomedical modeling.



OS4-10 FruitSense: An Android-Based Fruit Quality Detection Mobile Application Using Machine Learning and Image Processing

Evelyn Levina Diva (UCSI University, Malaysia), Umm E Mariya Shah (International Islamic University, Malaysia), Samar Ghazal Mohammed Abdullah (UCSI University, Malaysia), Heshalini Rajagopal (MILA University, Malaysia), Kasthuri Subaramaniam (Universiti Malaya, Malaysia), Yasir Mehmood (Syslab Technologies Sdn Bhd, Malaysia), Atif Mahmood (INTI International University, Malaysia)

Fruit quality is crucial for human nutrition and health, however, traditional visual inspection for fruit freshness is time-consuming and inconsistent. The growing adoption of AI offers new possibilities for improving traditional methods. Accordingly, FruitSense was developed to classify the ripeness of bananas, apples, and tomatoes using machine learning techniques. Implemented with TensorFlow Lite and Google Teachable Machine, it analyzes color, defects, and size. A diverse dataset of fruit images representing various ripeness stages was obtained from Kaggle to train separate models for each fruit. The models were integrated into an Android app for real-time ripeness detection. Evaluation of the application through system, usability, and performance testing revealed that it meets the project objectives and was positively received.



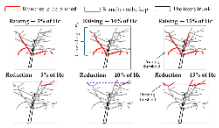
OS5 Advances in Field Robotics and Their Applications (16)

Chair Shinsuke Yasukawa (Kyushu Institute of Technology, Japan)
Co-Chair Kazuo Ishii (Kyushu Institute of Technology, Japan)

OS5-1 Semi-Automated Urban Tree Pruning Using a Rule-Based 2D Vision Approach

Mohammad Albaroudi, Abdullah Alraee, Raji Alahmad, Hussam Alraie, Kazuo Ishii
(Kyushu Institute of Technology, Japan)

Urban trees require regular pruning to ensure infrastructure safety. Manual pruning is labor-intensive and risky, whereas 3D-based approaches require high computational power. This study presents a semi-automated 2D vision method that combines machine learning with safety thresholds. Branch positions were derived from the YOLO-OBB detection outputs trained on diverse urban tree data. Branches for pruning are selected based on position and safety thresholds using raising and reduction methods. The framework balances automation and expert oversight, thereby enabling efficient and consistent urban tree management.



OS5-2 Automatic Scenario Generation for Agricultural Robots Using Natural Language Instructions

Takuya Fujinaga (Osaka Metropolitan University, Japan)

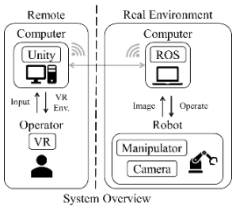
Foundation models have advanced rapidly. However, their applications in outdoor environments remain limited. This study aims to develop a large language models (LLMs)-based framework for automatic scenario generation in agricultural robots. The framework interprets natural language instructions and generates executable scenarios. Experiments in a virtual environment demonstrated that the framework achieved comparable accuracy to a menu-based approach while exhibiting superior operational efficiency and linguistic flexibility. Furthermore, the framework effectively handled ambiguous instructions through interactive clarification with the user. However, the response time of the LLM increased with scenario complexity. Future work will focus on improving processing speed and integrating real-robot experiments.

User interface for scenario generation using LLM

OS5-3 Development of a Tele-Operation Control System for a Tomato-Harvesting Robot Using VR Interfaces

Takuma Ushiroji, Takuya Fujinaga (Osaka Metropolitan University, Japan)

Agricultural robots are used to automate and improve the efficiency of farming tasks. In particular, tele-operation of robots is an efficient approach to managing large farm areas, especially for tasks such as monitoring, planting, and harvesting. This study aims to develop a tele-operation control system for a tomato-harvesting robot using VR interface. The camera view of the actual robot is displayed in a virtual environment by this system. The operator uses the VR interface to control the arm of the robot more intuitively than with conventional screen-based operation. The system is evaluated for harvest success rate, harvesting speed, and operability through real-world experiments. This study contributes to improving harvesting efficiency and usability in the tele-operation of agricultural robots.

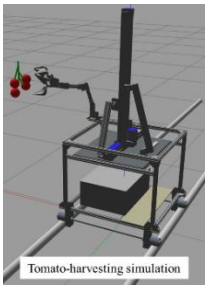


System Overview

OS5-4 Evaluation of an Optimal Approach Direction for a Tomato-Harvesting Robot Using a Digital Twin

Kouya Taitou, Takuya Fujinaga (Osaka Metropolitan University, Japan)

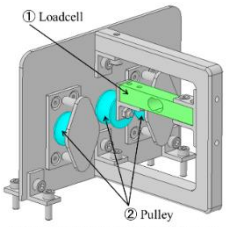
This study aims to optimize the approach direction of a tomato-harvesting robot using a digital twin. The success of tomato harvesting depends on various factors, one of which is the approach direction of the end effector. To examine the effect of the approach direction, a digital twin environment of the robot was constructed using Gazebo and ROS. Tomato models were then generated in the environment to simulate the harvesting motions. Several approach directions were tested and evaluated based on whether the gripper could properly grasp the fruit while avoiding the peduncle. The optimal direction was determined through simulation experiments, and field tests were subsequently conducted based on the obtained results. The experiments demonstrated the effectiveness of the optimized approach direction using the developed digital twin.



OS5-5 Tension Measurement Sensor for a Surface Vehicle Equipped with an Underwater Vehicle

Naoto Shirahama, Takuya Fujinaga (Osaka Metropolitan University, Japan)

Tethered underwater robots are widely used for underwater inspection, mapping, and observation because they can operate efficiently in complex environments. However, managing the tether cable remains a critical challenge, as fluctuating tether tension can affect the maneuverability, stability, and safety of the robot. This study aims to develop a tension measurement sensor mounted on a surface vehicle that assists an underwater vehicle. The developed sensor mainly consists of a load cell and pulleys to measure tether tension. The measured data can be used to analyze variations in tether tension caused by the motion of the underwater robot. The proposed sensor is expected to contribute to safer and more efficient cooperative operations between surface and underwater vehicles through improved tether management.

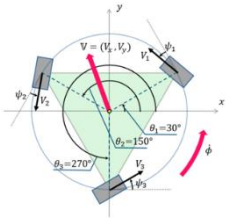


Tension measurement sensor

OS5-6 Proposal of New Kinematics for Mobile Robots adapted Three-Rollers

[1]Kenji Kimura, [2]Kazuki Nakayama, [3]Katsuaki Suzuki, [4]Kazuo Ishii,
([1]National Institute of Technology, Matsue College, Japan, [2] Toyohashi University of Technology, Japan,[3]Kumamoto Industrial Research Institute, Japan, [4]Kyushu Institute of Technology, Japan)

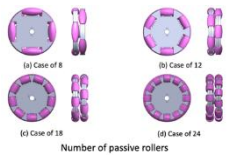
Mobile robots can be used in a variety of fields, including the logistics industry. The wheels used in these mobile robots are primarily omni-directional wheels and are commonly called omni-rollers. Omni-rollers have countless passive wheels attached to the rotating wheel, allowing them to move passively in directions perpendicular to the direction of rotation. Previous research has derived the kinematics of mobile mechanisms equipped with these three omni-rollers. This was done using a geometric method, clarifying the relationship between roller placement position and roller speed. In this study, we propose an algebraic derivation method that focuses on the speed and contact points of each roller.



OS5-7 A Study on the Number of Passive Rollers and Trajectory of Omni-Roller in Mobile Robot

[1]Kenji Kimura, [2]Katsuaki Suzuki, [3]Kazuo Ishii,
([1]National Institute of Technology, Matsue College, Japan,[2]Kumamoto Industrial Research Institute, Japan
[3]Kyushu Institute of Technology, Japan)

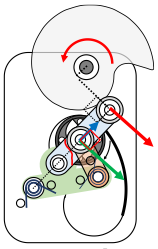
Mobile robots come in a variety of configurations with three or four rollers, and these mobile mechanisms are used in a wide range of fields, including the logistics industry. Mobile robots use omni-roller or Mecanum roller wheels. These allow for omnidirectional movement thanks to multiple passive wheels positioned along the direction of roller rotation. Previous research has determined the number of passive rollers and verified the kinematics of the trajectory and movement speed of a mobile mechanism equipped with rollers for a given number of passive wheels. In this study, we investigate the behavior of the mobile robot's running trajectory and vertical displacement when the passive wheels of the omni-roller are changed.


Number of passive rollers

OS5-8 Development of a Self-Locking Cam Mechanism for Spring Compression

[1]Katsuaki Suzuki, [2]Yuya Nishida, [3]Kenji Kimura, [2]Kazuo Ishii
([1]Kumamoto Industrial Research Institute, Japan, [2]Kyushu Institute of Technology, Japan, [3]National Institute of Technology, Matsue College, Japan)

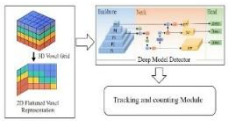
In production equipment, achieving both energy efficiency and cost reduction is a key requirement. One effective approach is to develop a mechanism that restrains rotation of the output shaft without relying on an electromagnetic brake. This study focuses on a cam mechanism that achieves an optimal reduction ratio depending on the applied load via its contour design, thereby improving energy efficiency through efficient power transmission. Furthermore, targeting spring-compression applications, we propose a novel mechanism with a self-locking function that generates frictional resistance only during backdriving by integrating a one-way bearing and other mechanical elements with the cam mechanism.



OS5-9 Voxel-Grid Based Deep Learning for Robust People Counting and Tracking with Event-Based Vision Sensors

Raji Alahmad, Zitong Zhou, Mohammad Albaroudi, Abdullah Alraee, Hussam Alraie, Shinsuke Yasukawa
(Kyushu Institute of Technology, Japan)

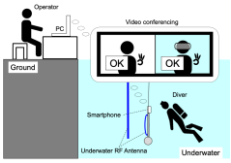
Abstract: Accurate people counting in crowded or low-light environments remains challenging for conventional cameras due to limited dynamic range, poor contrast sensitivity, and privacy concerns. Event-based vision sensors (EVS) address these issues by asynchronously capturing brightness changes with microsecond temporal resolution. This work introduces a voxel-grid deep learning framework that converts EVS event streams into spatial-temporal tensors, enabling lightweight detection and Byte Track-based tracking for reliable counting. The proposed system delivers real-time, privacy-preserving performance on embedded platforms, achieving high accuracy and efficiency under extreme illumination, fast motion, and densely populated scenes.



OS5-10 An Underwater Operation Method for a Diver Using Underwater Radio Frequency Communication and a Smartphone

Daigo Katayama[***], Raji Alahmad[*], Kazuhiro Eguchi[*], Toshiyuki Wakisaka[***], Tohlu Matsushima[*], Yuki Fukumoto[*], Kazuo Ishii[*] ([*]Kyushu Institute of Technology, [**]Kobe City College of Technology, [***]Panasonic Holdings Co., Ltd., Japan)

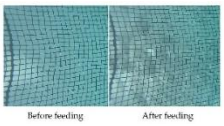
For safety reasons, the time available for diving operations is limited, so improving efficiency is necessary. Effective coordination with shore-based operators is essential. However, current voice communication methods can only convey a limited amount of information, meaning more information needs to be transmitted and received to ensure that operations run smoothly. We propose a communication system that uses underwater radio frequency technology and smartphones to facilitate communication between divers performing underwater operations and operators on land. To verify the usefulness of this system, we conducted tests in freshwater tanks and real sea environments. This paper describes the outline of operation methods and presents the results of the verification experiments.



OS5-11 Computer Vision-Based Monitoring of Feeding Consistency in Aquaculture

Abdullah Alraee, Mohammad Albaroudi, Hussam Alraie, Raji Alahmad, Irmiya R Inniyaka, Kazuo Ishii
(Kyushu Institute of Technology, Japan)

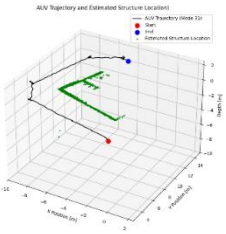
Automatic feeding in aquaculture optimizes feed and reduces labor; however, reliability is crucial because malfunctions cause economic losses. In this study, we proposed a computer vision framework to monitor feeder performance by analyzing real-time fish movement patterns using three metrics: fish count, density, and group disorder. Each successful feeding showed a distinct behavioral signature, a simultaneous spike in all three metrics, the absence of which signals feeder malfunction. This approach ensures reliable automation and improves efficiency.



OS5-12 The processing of acoustic sonar data for the underwater robot self-localization

Ryo Miyakawa, Kazuo Ishii, Yuya Nishida (Kyushu Institute of Technology, Japan)

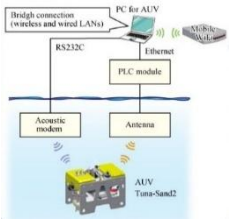
To improve the inspection efficiency of underwater structures, there is a demand for the development of inspection methods that utilize underwater robots. The employment of autonomous underwater vehicles (AUV), which are not constrained by cables, is of paramount importance. To achieve automated inspection by AUV, it is imperative that these vehicles maintain a constant position relative to underwater structures. Acoustic sonar, which is less susceptible to environmental light and suspended particles, is useful for this purpose. However, the integrity of sonar data is compromised by significant noise due to echoes and scattering, which complicates the estimation of the structure's position. The present study proposes a method for developing a filter to reduce noise in sonar data and estimate the position of structures.



OS5-13 Remote Operation of an Underwater Vehicle equipped with a Radio communication Device

Yuya Nishida, Ryo Miyakawa, Kazuo Ishii,
Tohlu Matsushima, Daisuke Nakayama, Kazuhiro Eguchi, Yuki Fukumoto
(Kyushu Institute of Technology, Japan)

In recent years, considerable expectations have been placed on the utilization of untethered, remotely operated UUVs for marine resource surveys and underwater structure inspections. Consequently, various research institutes are developing high-speed underwater communication devices essential for UUVs. The authors have developed an underwater radio communication device capable of high-speed communication within a range of 20m x 15m x 2m, demonstrating communication speeds of approximately 1Mbps within this area. This paper reports on remote operation experiments conducted using the developed radio communication device mounted on an AUV.



OS5-14 Multimodal RF-Enabled iPhone-Based Diver-in-the-Loop strategy for Underwater communication and UUV control

Irmiya R. Inniyaka, Kazuhiro Eguchi, Toshiyuki Wakisaka, Yuya Nishida, Kazuo Ishii
(Kyushu Institute of Technology, Japan)

Signal attenuation and multipath effects remain key barriers to underwater communication. A novel RF-enabled strategy supports Operator–Diver communication over Zoom/OBS but lacks Diver–Diver communication and diver-initiated UUV control. This limitation is due to restricted touchscreen access in sealed housing. We present a multimodal RF-enabled iOS framework that supports three modes: Operator–Diver communication, Diver–Diver communication, and Diver–UUV control. System concept and RF pathway are described, demonstrating how the proposed architecture overcomes the current constraints.

OS5-15 Comparative Performance Analysis of YOLOv5 and YOLOv8 for Tomato Detection in Agricultural Robotics.

Eslem Kıvrak, Orhun Erke Simav, Arda Şahin (Middle East Technical University, Türkiye),
Abdullah Alraee, Mohammad Albaroudi, Raji Alahmad (Kyushu Institute of Technology, Japan),
Hussam Alraie, Tayfun Nesimoğlu (Middle East Technical University, Türkiye)

The research aimed to develop a precise and dependable program that can accurately recognize tomatoes in photos and label them clearly. The goal was to help farmers automate picking by saving time. Modern farms increasingly rely on cameras and computers. Tomatoes are tricky: they come in different shades of red, sizes, and ripeness levels. We picked tomatoes to test whether AI could handle these real-world variations. By using YOLOv5 on a comparison analysis of our project with YOLOv8, this project experiments with different real-time object detection algorithms. In the tests, the software correctly finds nearly every tomato, making the project feasible. The tomato detector proves that machine learning can make farm work faster and smarter.

OS5-16 Resolving Object Overlap in Agricultural Imagery Using a Modified Watershed Transform

Oğuzhan Çalışkan, Naime Ayça Sezginer, Elifnaz Bilgili, Mustafa Eray Erdoğan,
(Middle East Technical University, Türkiye),
Abdullah Alraee, Mohammad Albaroudi, Raji Alahmad (Kyushu Institute of Technology, Japan),
Hussam Alraie, Tayfun Nesimoğlu (Middle East Technical University, Türkiye).

Agriculture is losing its popularity in Türkiye because of outdated techniques. Object detection is essential for enhancing productivity, harvesting, and yield estimation for farmers. In this study, an autonomous tomato detector utilizing an image processing approach in Python is developed, leveraging a dataset comprising diverse tomato types under various environmental and lighting conditions to enhance the application. This approach utilized some traditional image processing techniques, such as masking and filtering. To overcome the overlap problem that occurred in crowded tomato images, the watershed split algorithm was used to separate overlapping tomatoes to improve detection precision. The application can effectively distinguish tomatoes in the field to be harvested. Removing the overlap problem significantly raises the detection performance. The outcome of this study let it be said that computer-based techniques can help agriculture while lowering labor costs.

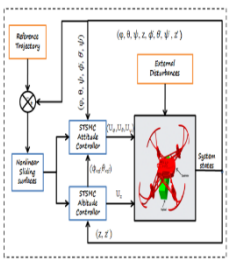
OS6 Advanced Techniques for UAVs and Structural Heritage (7)

Chair Hazry Desa (Universiti Malaysia Perlis (UniMAP), Malaysia)
Co-Chair M. Azizi Azizan (Universiti Malaysia Perlis (UniMAP), Malaysia)

OS6-1 Variants of Robust Sliding Mode Control for Quadrotor UAVs under Parametric Uncertainties

Hazry Desa[1], Azmat Saeed[2], M. Azizi Azizan[1], S. B. Yaakob[1], Abadal-Salam T. Hussain[3], Taha Almulaisi[4], M. Hassan Tanveer[5]
([1]UniMAP, Malaysia; [2]NUST, Pakistan; [3]Al-Kitab University, Iraq; [4]Northern Technical University, Iraq; [5]Kennesaw State University, USA)

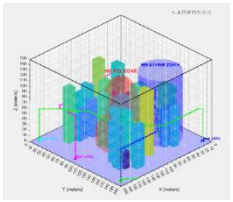
Super-Twisting Sliding Mode Control has emerged as a robust and efficient strategy for flight control system design, providing strong resilience against model uncertainties while effectively mitigating the chattering phenomenon inherent in conventional Sliding Mode Control (CSMC) schemes. This paper presents a Nonlinear Surface–Based Super Twisting Sliding Mode Control (NSTSMC) scheme for the attitude and altitude control of a quadrotor. The performance of the NSTSMC is evaluated through numerical simulations under parameter variations and benchmarked against the CSMC and Nonlinear Sliding Mode Control (NSMC) schemes. Results demonstrate that NSTSMC improves its time rise by 25 to 56% over CSMC and 32 to 47% over NSMC, chattering index by 94 to 95% and integral absolute error by 34 to 56% for both attitude and altitude.



OS6-2 Unmanned Aerial Vehicle Fleet Management and Control System

Thines Vasanthan[1], Hazry Desa[1], Azmat Saeed[2], M. Azizi Azizan[1], S. B. Yaakob[1], Abadal-Salam T. Hussain[3], Taha Almulaisi[4], M. Hassan Tanveer[5]
([1]UniMAP, Malaysia; [2]NUST, Pakistan; [3]Al-Kitab University, Iraq; [4]Northern Technical University, Iraq; [5]Kennesaw State University, USA)

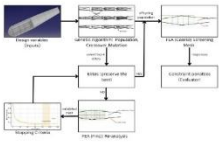
The Unmanned Fleet Management and Control System (UFMC) use pathfinding algorithms and simulated IoT sensors to safely manage and scale high-density UAV traffic in cities. A core component is its grid-based airspace model, which was tested comparing an A* algorithm against a Perimeter (Shortest Boundary) method. Simulation results for a test mission showed the A* algorithm's path was 8.54% more efficient (shorter) than the Perimeter path, also completing the mission 8.75% faster. IoT sensors track key metrics like path length and time, feeding data into the robust simulation platform to validate performance under various conditions. The UFMC sets a new standard for urban UAV management, enabling efficient and safe drone operations for smart city applications.



OS6-3 AI-Driven Structural Optimization of a Fixed Wing UAV Composite Airframe

Afnan Nazmy[1], Hazry Desa[1], M. Azizi Azizan[1], S. B. Yaakob[1], Abadal-Salam T. Hussain[3], Taha Abdulsalam Almulaisi[4], M. Hassan Tanveer[5]
([1]UniMAP, Malaysia; [2]NUST, Pakistan; [3]Al-Kitab University, Iraq; [4]Northern Technical University, Iraq; [5]Kennesaw State University, USA)

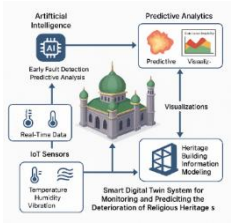
AI-assisted workflow to lighten the Fixed Wing UAV airframe using sandwich-composite structures. Finite-element analyses under cruise, manoeuvre, and gust loads are coupled with a genetic algorithm to minimize mass while enforcing strength, stiffness, and modal limits. With manufacturable layups, graded cores, and verification via mesh convergence, the optimized design achieves ~24–25% structural mass reduction and raises f_1 to ≥30–35 Hz. These gains increase payload capacity and endurance without compromising safety or durability. The workflow is reproducible, implementation-ready, reliable, and enables rapid iteration for robotics and aerospace teams moving from digital preliminary sizing to buildable composite structures.



OS6-4 Smart Digital Twin System for Monitoring and Predicting the Deterioration of Religious Heritage Structure

Ainur Fariha Mahhassan, M. Azizi Azizan, Hazry Desa
(UniMAP, Malaysia)

A Smart Digital Twin System is proposed to enhance the monitoring and preservation of Malaysia's religious heritage structures. The system integrates IoT sensors, Artificial Intelligence (AI), and Heritage Building Information Modelling (HBIM) to provide real-time data acquisition and predictive condition assessment. IoT sensors record key environmental and structural parameters, while AI algorithms analyse these inputs to detect early deterioration and forecast potential damage. The processed data are visualized within an HBIM-based 3D model, enabling clearer interpretation of structural risks and maintenance needs. This integrated approach supports proactive, data-driven conservation, reduces restoration costs, and strengthens the long-term sustainability of historic religious monuments.



OS6-5 Smart Technologies for Sustainable Conservation of Malaysia's National Heritage Buildings: A Triple-Bottom-Line Perspective

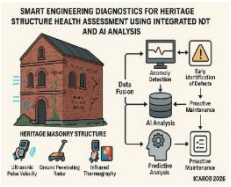
Muhammad Nazrul Naim Md Zain, M. Azizi Azizan, Hazry Desa
(UniMAP, Malaysia)

The application of smart technologies to promote sustainable conservation of Malaysia's heritage buildings. By integrating Non-Destructive Testing (NDT), Structural Health Monitoring (SHM), nanotechnology coatings, and Heritage Building Information Modelling (HBIM), the framework supports preventive and data-driven maintenance. Guided by the Triple-Bottom-Line approach, it advances environmental protection, cultural preservation, and economic resilience. The adoption of intelligent diagnostics and digital management enhances structural safety, reduces restoration costs, and extends the life of historic assets. This strategy reflects Malaysia's commitment to sustainable heritage conservation through innovation and technology.

OS6-6 Smart Engineering Diagnostics for Heritage Structure Health Assessment Using Integrated NDT and AI Analysis

Muhammad Adib Syahmi Muhammad[1], M. Azizi Azizan[1], Hazry Desa[1]
([1]UniMAP, Malaysia)

Heritage masonry structures in Malaysia face progressive deterioration caused by moisture ingress, biological decay, and internal cracking that often go undetected through conventional visual inspection. This research presents an intelligent diagnostic framework that integrates non-destructive testing methods including ultrasonic pulse velocity, ground penetrating radar, and infrared thermography with artificial intelligence for data fusion, anomaly detection, and predictive analysis. The framework enables early identification of hidden defects and supports proactive maintenance through data-driven decision making, contributing to sustainable and reliable conservation of heritage structures.



OS6-7 Intervention Measures and Culturally Formed Engineering in Heritage Buildings

Mimi Natasha Jamal[1], M. Azizi Azizan[1], Hazry Desa[1]
([1]UniMAP, Malaysia)

This study focused on the Chow Kit Mansion and the Floral Tea Mansion to explore the integration of traditional and modern engineering methods in heritage preservation. A quantitative survey of fifty-two heritage experts and users evaluated architectural influences, preservation techniques, and heritage elements relevant to contemporary design. Findings showed that modern technologies improved efficiency, while traditional methods-maintained authenticity. Architectural style, structure, and ornamentation were key to cultural identity, and adaptive reuse enhanced aesthetics. The study emphasized the need for tailored strategies, resources, and expert support for sustainable preservation.

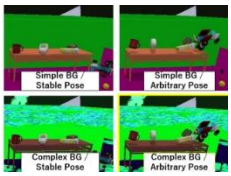
OS7 AI System and Space Design Toward Co-Existence of Humans and Robots (9)

Chair Yuichiro Tanaka (Kyushu Institute of Technology, Japan)
Co-Chair Hakaru Tamukoh (Kyushu Institute of Technology, Japan)

OS7-1 Pose Diversity Improves Object Detection Generalization

Tomoya Shiba, Akihiro Suzuki, Naoki Yamaguchi, Ryoga Maruno, and Hakaru Tamukoh
(Kyushu Institute of Technology, Japan)

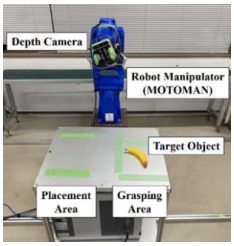
The performance of object detection models strongly depends on the distribution of object poses in training data. While previous studies have focused on dataset size and background diversity, the effect of pose variation remains unclear. This study investigates how pose diversity influences detection generalization. We generated synthetic datasets with controlled pose ranges using a 3D simulator and trained detectors under different pose conditions. Experiments on the YOLO-Video dataset show that models trained with wider pose distributions achieved higher accuracy on unseen poses. These results indicate that designing pose diversity in training datasets is essential for improving the robustness and generalization of object detection models.



OS7-2 A Robot Grasping Framework for Flexible and Amorphous Objects Using Skeleton Estimation

Ryoga Maruno, Naoki Yamaguchi, Akihiro Suzuki, Tomoya Shiba, and Hakaru Tamukoh
(Kyushu Institute of Technology, Japan)

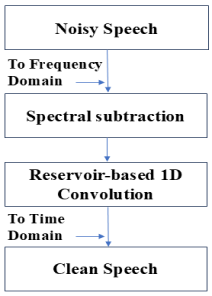
This paper proposes a framework for the flexible and amorphous object grasping of robots. In prior work, we developed methods for automatically assigning skeletons that faithfully reproduce object shape without excess or deficiency. This study builds on the previous research by applying it to grasp point estimation and implementing it on the robot manipulator. A skeleton estimation model was trained on automatically assigned skeletons, and the inference results were obtained. Then, the results were combined with the object's mask image and depth measurements from the robot-mounted camera to determine the grasp point and gripper angle. The experimental results confirmed that the proposed framework can achieve high-precision grasping of target objects.



OS7-3 Preliminary Study of Speech Denoising Using One-Dimensional Convolutional Reservoir Computing

Digisha, Rohan Saini, Aryan Rakheja, Hakaru Tamukoh, and Yuichiro Tanaka
(Kyushu Institute of Technology, Japan)

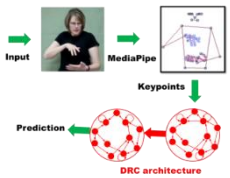
This study presents an efficient speech denoising framework based on one-dimensional convolutional reservoir computing (1D-CRC). Deep-learning approaches for speech enhancement require high computation, whereas the proposed 1D-CRC provides a low-cost, adaptive alternative. The framework integrates a reservoir-based convolution mechanism to extract local spectro-temporal features and capture recurrent temporal dependencies in speech. A comparative analysis with the conventional spectral subtraction method was conducted using the VoiceBank-DEMAND dataset. Experimental results show that the proposed model effectively suppresses background noise and reconstructs smoother, more natural waveforms, achieving an average signal-to-noise ratio improvement of 5.6 dB, compared to 3.5 dB for spectral subtraction.



OS7-4 Deep Reservoir Computing Based Lightweight Model for Isolated Sign Language Recognition

Nitin Kumar Singh, Arie Rachmad Syulistyo, Yuichiro Tanaka, and Hakaru Tamukoh
(Kyushu Institute of Technology, Japan)

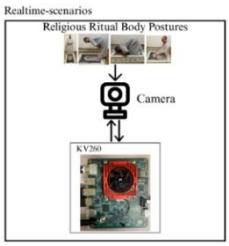
Sign language recognition (SLR) is an emerging technology that enhances communication between hearing and hearing-impaired individuals. Deep learning is widely used for SLR, however, its suitability for edge devices is limited due to computational constraints. To address this issue, we propose an approach to SLR that combines MediaPipe with deep reservoir computing (DRC). MediaPipe extracts key points from sign language videos, which are further processed through DRC to class labels using ridge regression. This method offers low computational cost and faster training, suitable for edge devices. Our proposed method achieves a competitive accuracy on the Word-Level American Sign Language (WLASL) dataset with a shorter training time than deep learning-based SLR systems.



OS7-5 Real-Time Religious Ritual Body Recognition Using an FPGA System

Dinda Pramanta (Kyushu Institute of Information Sciences, Japan) and
Hakaru Tamukoh (Kyushu Institute of Technology, Japan)

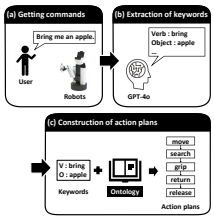
This study proposes a real-time recognition system for religious ritual body movements. The system focuses on structured movements from Islamic prayer, including raising, bowing, sitting, and sujud, aiming to support educational and assistive applications in Edge-AI platforms such as Field-Programmable Gate Arrays (FPGA). A machine learning model, Faster Objects, More Objects (FOMO), was trained and deployed on the KV260 board. Using 94×94 images, the system was trained for 0.33 hours over 50 epochs. The system achieves a total inference latency of 5 ms, with 1 ms used for image processing and 4 ms for detection, enabling practical real-time operation. Despite modest accuracy performance, this work demonstrates the feasibility of implementing a real-time recognition system on FPGA.



OS7-6 Development of an Action Planning System using Explainable AI for Home Service Robots

Takashi Akamatsu and Yuma Yoshimoto (National Institute of Technology, Kitakyushu College, Japan)

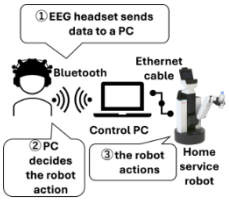
When home service robots are deployed into home environment, robots must perform “Command Understanding Tasks (CUT)” to execute commands given by users. Robots need to construct action plans—combinations of predefined actions such as going to the kitchen and grabbing an object—, to perform CUT from the commands. In recent years, methods using large language models (LLMs) have become mainstream due to their high flexibility. However, LLMs lack of explainability, when accidents or malfunctions occur and cannot explain the cause. In this research, we use Ontology, an explainable AI, to provide explainability to the construction of action plans in CUT.



OS7-7 The Development of a Control System for Robot Operation Using EEG

Haruki Miura and Yuma Yoshimoto (National Institute of Technology, Kitakyushu College, Japan)

Home service robots, capable of performing a wide range of tasks in homes and stores, must be controlled by anyone through simple procedures. As the operating procedures that robots understand use buttons, remote controls, and voice commands, these methods have shortcomings. And it is difficult to verify the command. Therefore, this study proposes a method for commanding robots using only motor imagery via electroencephalography (EEG). EEG is a method that measures the electrical activity within the brain using small electrodes attached to the scalp. In the proposed system, (1) the EEG headset sends data to a PC, (2) the PC decides the robot action, and (3) the robot actions. In the experiments, the robot reached a destination room using the EEG headset.



OS7-8 Application and Impression Evaluation of AI Robot Technology in Biophilic Design

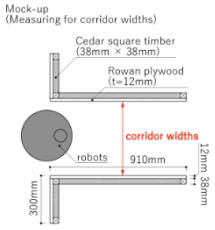
Kairi Manabe, Hiroaki Miyauchi, Keitaro Ito, Tomomi Sudo, Naoto Ishizuka, Akinobu Mizutani, Hakaru Tamukoh, Yuichiro Tanaka, Leon Furuya, Kei Wakabayashi, and Hirofumi Tanaka
(Kyushu Institute of Technology, Japan)

In recent years, biophilic design has received increased attention for enhancing human well-being. This study presents a system in which robots autonomously relocate plants to optimal positions based on illuminance, temperature, and humidity, while examining psychological effects of this movement on humans. Environmental gradient maps generated by sensors determine relocation destinations, showing distinct spatial differences between conditions with and without human presence. Heart rate variability and subjective impressions are measured at varying distances as the plant-carrying robot moves around participants. Results suggest that integrating robotic movement and environmental sensing can create dynamic, responsive spaces bridging human–nature interaction, providing new insights into biophilic design applications.

OS7-9 Basic Research on Movement Failure Condition for Home Service Robots — Mock-up Evaluation of Step Heights, Corridor Widths, and Under-Furniture Clearances —

Suzuka Tachibana, Ren Matsuoka, Naoto Ishizuka, Akinobu Mizutani, Tomomi Sudo, Keitaro Ito, Hakaru Tamukoh, and Hirofumi Tanaka (Kyushu Institute of Technology, Japan)

As home service robots become more common, design standards for their smooth operation in typical residences remain insufficient. In this study, as basic research to understand performance tendencies, we conducted experiments using 12 cleaning robots, 1 pet-type robot, and 1 small transport robot, totaling 14 devices. We employed a mock-up that replicated a range of residential conditions—including typical step heights, corridor widths, and under-furniture clearances—to measure mobility limits and compare them with housing conditions. The results showed that common step heights posed only minor issues, whereas large robot body size significantly limited mobility, particularly for clearances and corridor widths. These findings are expected to inform future spatial standards for home robot integration.



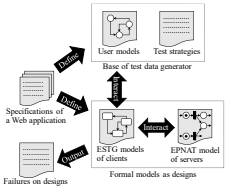
OS8 Software Development Support Method (3)

Chair Tetsuro Katayama (University of Miyazaki, Japan)
Co-Chair Tomohiko Takagi (Kagawa University, Japan)

OS8-1 A Design Testing Method Using Formal Models Based on EPNAT and ESTG for Web Applications

Takeru Amo[1], Tetsuro Katayama[2], Tomohiko Takagi[1]
[1] Kagawa University, Japan, [2] University of Miyazaki, Japan

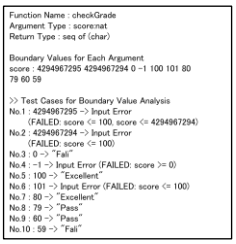
This study shows a method to test designs of Web applications using formal models. In the method, designs of servers and clients of a Web application are defined as EPNAT and Extended Screen Transition Graph (ESTG) models, respectively. The EPNAT model represents concurrent distributed behavior to provide services to the clients, and the ESTG model represents behavior to request and receive the services through a Web browser. A test data generator based on user models and testing strategies interacts with the ESTG models, and the ESTG models interact with the EPNAT model. The EPNAT and ESTG models contain assertions that detect failures on the designs, that is, detect violations of constraints derived from specifications. The procedure, effectiveness, and future work will be discussed in this paper.



OS8-2 Extension to Support Multi-Class Specification in BWDM that Generates Test Cases from VDM++ Specification

Tomohiro Takahashi*, Nobuya Takahashi*, Tetsuro Katayama*, Yoshihiro Kita†
*University of Miyazaki, Japan, †University of Nagasaki, Japan

Writing test cases from the formal specification description VDM++, which is a method for eliminating ambiguity in software specification, is time-consuming and labor-intensive. Therefore, our laboratory has developed BWDM, a tool that automatically generates test cases from VDM++ specification. However, the existing BWDM has a problem in that it cannot generate test cases from VDM++ specification having multiple classes. Therefore, in order to improve the usefulness of BWDM, this study extends BWDM to solve the above problem. Consequently, it has confirmed that the extended BWDM can reduce the test case generation time compared to manual test case generation for VDM++ specification having multiple classes.



OS8-3 Extension of ASLA Which Is a Segmentation and Labeling Tool for Application to New Document Formats and Improvement of Label Generation Accuracy

Chihaya Takuma*, Nobuya Takahashi*, Tetsuro Katayama*, and Yoshihiro Kita†
*University of Miyazaki, Japan, †University of Nagasaki, Japan

We have developed ASLA (Automatic Segmentation and Labeling tool using AI) to divide electronic documents into elements and generate labels for new applications. However, the existing ASLA has two problems: (1) low segmentation accuracy for document formats other than scientific papers, and (2) occasionally generating incorrect labels. This study generates a new document image dataset with three additional formats, generates a segmentation model, and extends ASLA to use a multimodal LLM for label generation. Evaluation results have shown that the generated segmentation model achieved a score of at least 0.78 in mAP@[0.75] for each of the four format types in the test data. Additionally, it has been confirmed that the multimodal LLM generates correct labels with higher accuracy than the existing ASLA method.

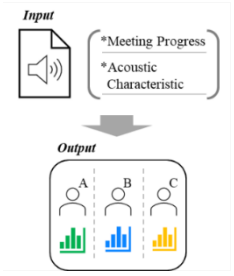
OS9 Biological and Intelligent Information System (7)

Chair Masayuki Fujiwara (Komatsu University, Japan)
Co-Chair Kazuma Sakamoto (Komatsu University, Japan)
Co-Chair Masaya Nakahara (Osaka Electro-Communication University, Japan)

OS9-1 Speaker Identification Method Using Textual Data and Acoustic Features in Multi-Speaker Meetings with Focus on Meeting Progress

Teruya Minakuchi, Kazuma Sakamoto, Iori Iwata, Yoshihiro Ueda (Komatsu University, Japan)

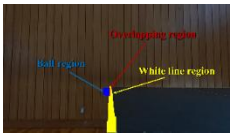
Recent advancements in speech recognition technologies have expanded the potential applications of speaker identification. Conventional approaches generally fall into two categories: models trained to learn acoustic characteristics using artificial intelligence, and text-based methods that infer speakers solely from linguistic information. However, the former is highly dependent on acoustic features, resulting in high training costs and sensitivity to recording conditions, whereas the latter is strongly affected by automatic speech recognition errors and inconsistencies in punctuation insertion, and thus depends heavily on transcription accuracy.
In this research, we propose a novel method that integrates both textual data and acoustic characteristics for identifying speakers in multi-speaker turn-taking settings with a focus on meeting progress.



OS9-2 Basic Research on Automating Edge and Side Determination in Table Tennis

Reo Ishii, Kazuma Sakamoto, Iori Iwata, Riku Kaiba, Yoshihiro Ueda (Komatsu University, Japan

Accurate judgment in sports is difficult to achieve solely with the human eye. Consequently, judgment support systems that utilize deep learning are gaining attention. According to extant research, judgments have been made indirectly on the basis of trajectories subsequent to ball contact. This research proposes a method to automate edge and side judgments in table tennis. Specifically, it directly determines contact by extracting the “ball region” and “white line region” using instance segmentation and analyzing their overlap. This approach enables concise and intuitive judgment without trajectory estimation, reducing analytical complexity and computational processing. The efficacy of the proposed method in automating edge and side judgments is demonstrated by the results obtained from experiments utilizing experimentally captured footage. These results suggest the potential for fair and consistent support for table tennis judgment.



OS9-3 Basis Research on Attended Objects Estimation Using Gaze Information and Object

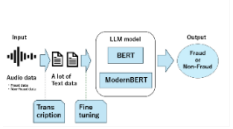
Hiroto Kawabe, Kazuma Sakamoto, Tomoya Senda, Yoshihiro Ueda (Komatsu University, Japan)

Appropriate product placement in stores is directly linked to reducing lost sales opportunities. Therefore, it is imperative to understand the differences in attention levels that arise from product and display positions is essential. While online shops can estimate popularity through browsing time, in physical stores making it difficult to directly observe customer attention comparable to viewing time. The present research proposes a methodology for addressing this issue. The methodology utilizes a single image and to calculate the attention duration toward that object from camera footage. The proposed method enables quantification of product and layout-specific attention levels all by utilizing existing cameras. Ultimately, the goal of this study is to present a data-driven guideline for designing new product layouts.

OS9-4 Research on Supporting Detection of Communication Fraud Using BERT

Ryuta Okabe, Kazuma Sakamoto, Iori Iwata, Yoshihiro Ueda (Komatsu University, Japan)

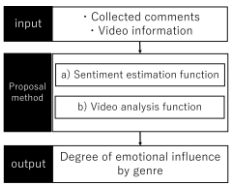
Communications fraud has become a serious social problem in Japan, with 13,213 reported cases and total damage amounting to 59.7 billion yen in the first half of 2025, marking record highs. Implementation of awareness campaigns, the number of victims continues to increase, suggesting that the sophistication of fraudulent techniques may be a contributing factor. The mitigation of such damage is contingent upon the early detection of communications fraud, a strategy that has been demonstrated to be effective. In this research, we conducted token prediction related to communications fraud using Large Language Models. The prediction accuracy of BERT and ModernBERT was compared, with a focus on the differences in the maximum input sequence length that each model can process. The objective of this research is to provide a foundation for the prevention of communications fraud.



OS9-5 Influence of Comment Sentiment on YouTube Subscribers and View Counts by Genre

Kyoya TAKIGUCHI, Masaya NAKAHARA (Osaka Electro Communication University, Japan)
Kazuma SAKAMOTO (Komatsu University, Japan)

With the spread of video platforms such as YouTube, viewers have more opportunities to express their opinions and emotions through comments. These comments complement qualitative responses that are difficult to capture through viewing history and rating numbers alone, making them an important form of feedback for video creators. Emotional expressions in comments, in particular, can potentially affect a video's view count and popularity, but systematic verification of this effect has yet to be conducted. Previous research has confirmed that videos with more subscribers and views tend to have more "strongly emotional" comments and has also shown that the distribution of emotions varies by video genre. Therefore, this study compares and examines the impact of comment emotions on subscriber counts and view counts by genre. Specifically, we index the intensity and polarity of emotions for each genre and use regression analysis to evaluate their relationship with viewing indicators (subscribers and views).



OS9-6 Evaluation of the Effectiveness of a Voice-Based Special Fraud Experience System Using Generative AI

Masaya Nakahara, Kyoya Takiguchi, Taketo Ueno, Yuya Doi, Ryusei Noguchi, Tenma Matsumoto, Ryotaro Teranishi (Osaka Electro Communication University, Japan)

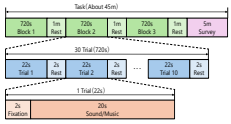
In recent years, losses from specialized fraud schemes have been expanding worldwide, both domestically and internationally. As countermeasures, methods such as publicizing fraud cases through media and developing AI to detect specialized fraud have been implemented. However, actual specialized fraud attempts deceive victims using various patterns, lacking fixed formulas, and losses among the elderly continue unabated. Furthermore, monitoring every call using detection AI is impractical. Therefore, there is a need for technology that enables people to experience various actual fraud scenarios. This research developed a fraud experience system capable of video calling. It utilizes an LLM model pre-trained on fraud scenarios and avatars that generate human-like speech using generative AI. Through proof-of-concept experiments, the effectiveness of experiential learning using this system was confirmed.

Image of the developed system

OS9-7 Electroencephalographic Responses to Three Types of Auditory Stimuli

Akihiro Matsumoto[1], Koushi Nishioka[1], Hironari Machida[1] and Masayuki Fujiwara[1,2]
([1]Komatsu University, Japan), ([2]Japan Advanced Institute of Science and Technology, Japan)

Sounds and music are known to influence human psychological and physiological states, potentially modulating emotion and behavior. Previous electroencephalography (EEG) studies have mainly focused on event-related potentials (ERPs), but oscillatory brain activity across different types of auditory stimuli and under repeated listening conditions may provide additional insights. In this study, EEG recordings were conducted while participants listened to three types of auditory stimuli: classical music, natural sounds (flowing water), and environmental noise (classroom chatter). Time–frequency analysis was applied to examine oscillatory brain activity across conditions. As a result, characteristic neural activity was observed in response to the three types of auditory stimuli, and significant differences were found.



OS10 Robotics and Intelligent Systems (9)

Chair Kuo-Hsien Hsia (National Yunlin University of Science and Technology, Taiwan)
Co-Chair Jr-Hung Guo (National Yunlin University of Science and Technology, Taiwan)

OS10-1 Design and Implementation of a Four-Wheel Steering Mechanism for Educational Demonstration

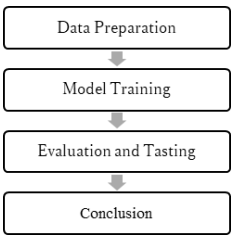
Kuo-Hsien Hsia, Chun-Chi Lai, Yi-Ting Liu (National Yunlin University of Science and Technology, Taiwan)

With the advancement of autonomous driving and intelligent vehicle technologies, the demand for enhanced maneuverability and stability is increasing. This study presents the design and implementation of a four-wheel steering mechanism intended for educational demonstration. The platform enables independent directional control of each wheel, supporting multiple steering modes such as front-wheel, rear-wheel, same-direction, and opposite-direction configurations. Ackermann steering geometry was applied to ensure all wheels align toward a common turning center, reducing sideslip and improving accuracy. The mechanism provides a tangible tool for exploring vehicle dynamics and steering behavior in a controlled, observable setting.

OS10-2 Comparative Analysis of Speech Recognition Training Using Real and Synthetic Data

Chung-Yu Li, Kuo-Hsien Hsia (National Yunlin University of Science and Technology, Taiwan)

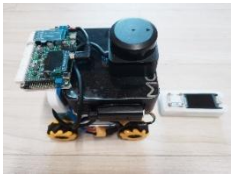
Speech recognition, as one of the most commonly used methods in language models, has always been a focus in terms of accuracy and latency. The appropriate standards vary depending on the application scenario. Traditional real-recorded speech data is commonly used in model training. However, the emergence of artificial intelligence synthesized speech has provided new options for training methods. This study will compare the training results of speech recognition using traditional real-recorded speech data and artificial intelligence synthesized speech data, analyze whether there are significant differences in accuracy, latency, and overall model performance, and explore the reasons for these differences.



OS10-3 Development of a Flexible ROS-based Robot Architecture

Jr-Hung Guo, Kuo-Hsien Hsia (National Yunlin University of Science and Technology, Taiwan)

The Robot Operating System (ROS) is widely adopted in robotics development due to its modular and open architecture, which supports diverse robotic platforms. However, its reliance on Linux limits its applicability to smaller robots or systems unable to run Linux environments. This paper proposes a universal architecture that leverages ROS's openness to bridge non-ROS-capable robots and peripheral devices with ROS-based systems. By integrating core ROS components—such as nodes, topics, and messages—this design enables external systems to interact with ROS functionalities, facilitating broader compatibility and extending ROS's utility beyond native Linux platforms.



OS10-4 Implementation of Water-Washing Blackboard Cleaning Mobile Robot

Jia-Ming Hsiao, Shao-I Hsiao, Yu-En Tien (National Yunlin University of Science and Technology, Taiwan)

This device was originally designed to help students and teachers clean the blackboard. Although it's designed for water-washing blackboards, the robot uses a tracked and magnetic design for movement, making it suitable for regular blackboards with magnetic attachment. The combination of a single-board computer and a motor driver is utilized as the robot control core, and the motor and magnetic tracks allow it to adhere to the blackboard and move. A cleaning cloth is placed around the bottom perimeter to ensure the corners of the blackboard are reached. A water sprayer is located inside the robot, and the robot cleans the blackboard by moving. Considering safety, a safety rope is placed near the blackboard to prevent damage to the machine and personal injury.

OS10-5 Image Recognition of UAV Photographed Ground Targets

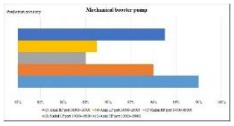
Kuo-Da Chou, Huang-Li Wang (National Formosa University, Taiwan)

This study uses the Jetson Nano development board and a camera serial interface camera to build a test environment. Using an unmanned aerial vehicle (UAV) to capture images, this study compares two neural networks, YOLOv5 and SSD-Net, to evaluate the performance of object detection. Evaluation metrics include mean average precision (mAP) and frames per second (FPS). By incorporating object recognition and edge computing, YOLOv5 performs better on key performance metrics such as mAP, FPS, precision, and recall, with mAP outperforming SSD-Net. Test results demonstrate that the system can accurately identify a car at a range of 120 meters and an altitude of 60 meters, with a confidence score exceeding 82%.

OS10-6 A Fault Prediction Method for Electron Beam Welding Equipment

Kuo-Da Chou, Huang-Li Wang (National Formosa University, Taiwan)

In electron beam welding, the process has to be carried out in vacuum to prevent gases in the air from scattering high-energy electrons. Therefore, the vacuum pump acts as a very important role in the process, and its feature parameters are the critical factors in the fault prediction of a vacuum pump in the electron beam welding equipment. This study adopts neural networks to calculate the weight of individual features, to help establish a vacuum pump fault diagnosis model. And thereby increasing available maintenance time for equipment engineers to reduce losses caused by unexpected downtime. Through experiment verification results, it shows that the accuracy of the prediction model is 92%, proving the effectiveness of the method proposed in this study and can be used to improve the reliability of the welding process.



OS10-7 Concept Design of Foot Massager

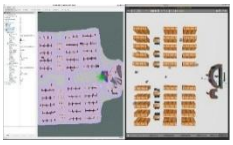
Yuting Hsiao, Dengchuan Cai, Chung-Wen Hung, Chen-Wei Tu, Zi-Jie Xu
(Nation Yunlin University of Science and Technology, Taiwan)

In Taiwan, there is a shortage of skilled personnel for foot reflexology. To make this method more widely available, this study aims to automate the technique and develop a new foot massage product. This study measured the foot dimensions of 40 Taiwanese adults and photographed their soles. Professional foot therapists marked key areas to create a massage program, which was automated through a machine learning system and integrated into the product design, resulting in a unique foot massager. The features of this design include: 1) adjustable footrest size according to the user's foot size; 2) selectable massage speed; 3) selectable number of massages; 4) voice prompts for easy operation; and 5) safety considerations.

OS10-8 Preliminary Design and Simulation Verification of an Autonomous Book Returning System Based on Navigation and Visual Recognition

Chun-Chieh Wang*, Chung-Wen Hung, Chun-Lung Hsiao, Kuo-Hsien Hsia, Chian-Cheng Ho
(National Yunlin University of Science and Technology, Taiwan)

This study aims to develop an autonomous book returning system with navigation and visual recognition capabilities. A mobile robot platform was built in the Gazebo simulation environment, achieving single-point navigation and obstacle avoidance as a foundation for integrating book recognition and slot localization modules. The system supports a complete workflow in a smart library, from autonomous positioning and navigation to precise book shelving. Future work will incorporate image recognition and deep learning techniques to enhance the automation and intelligence of library management.



OS10-9 Development of a SOTIF-Based Safety Evaluation Platform for Lane Keeping Assist (LKA) Systems

Chien-An Chen, Yan-Hua Chen, Yi-Feng Tsou
(National Kaohsiung University of Science and Technology, Taiwan)

To reduce unexpected incidents involving vehicles equipped with autonomous driving (assistance) systems on real roads and to examine the operational range and limitations of such systems, this study focuses on the image perception module of the lane detection function within a Lane Keeping Assist (LKA) system. A test platform based on Safety of the Intended Functionality (SOTIF) is established to identify functional shortcomings and performance limits. The results can serve as references for defining the system's Operational Design Domain (ODD) and for proposing functional improvements, thereby assisting system developers in completing verification and solutions for known unsafe scenarios defined in SOTIF.

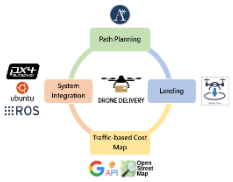
OS11 Intelligent Control (8)

Chair Ching Ju Chen (National Yunlin University of Science and Technology, Taiwan)
Co-Chair Chun-Chieh Wang (National Yunlin University of Science and Technology, Taiwan)

OS11-1 Development of a Flight-Path Planning and AprilTag-based Landing System for Drone Logistics

Yu-Ming Li, Jia-Ming Xu, Jia-Wen He, and Chau-Chung Song
(National Formosa University, Taiwan)

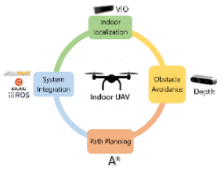
This research integrates multiple subsystems to achieve safe, reliable, and fully autonomous UAV flight in urban areas. Real-time traffic data are collected through the Google API, while cost maps generated from OpenStreetMap (OSM) illustrate congestion levels, obstacles, and no-fly zones. The A* algorithm is employed to calculate the optimal flight path, minimizing travel cost and improving route efficiency. For landing, AprilTags are detected by an onboard camera to perform accurate position estimation and autonomous descent. By combining these techniques, the proposed system enables UAVs to plan intelligent routes, avoid dangerous regions, and complete missions with high precision.



OS11-2 Development of an Indoor VIO-Based Navigation System for Unmanned Vehicles

Chih-Hao Chen, Lin, Jian Jhih, Li-Hao Chen and Chau-Chung Song
(National Formosa University, Taiwan)

The widespread lack of stable GPS signals in indoor environments poses a critical challenge to autonomous UAV operation. To overcome this core limitation, our study is motivated to design and implement a highly robust, infrastructure-free navigation system. This novel solution integrates the RealSense T265 (VIO) for high-accuracy localization and the D435i for environment perception. All processing is efficiently executed on the Jetson Orin NX platform. The deployed system enables the unmanned vehicle to achieve precise localization, efficient path planning, and robust real-time obstacle avoidance. Ultimately, this work verifies the feasibility of VIO and depth sensing solutions in GPS-denied environments.



OS11-3 YOLOv11 Wormhole Detection System based on ESRT and EGA Enhancements

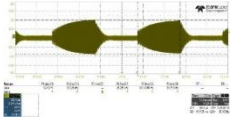
Jun-Lin WU, Chung-Wen HUNG*
(Nation Yunlin University of Science and Technology, Taiwan)

A YOLOv11(You Only Look Once) wormhole detection system based on ESRT (Efficient Transformer for Single Image Super-Resolution) and EGA (Edge–Gaussian Aggregation) enhancements is proposed in this paper. The detection of tiny wormholes embedded in richly textured carved wood surfaces is a challenge, due to an extreme small-object. To improve performance, one lightweight model and one module are introduced: the ESRT model to boost pixel resolution; and the EGA module to enhance shallow edge features and suppress deep noise. All components are integrated with SAHI (Slicing Aided Hyper Inference). Based on the method proposed in this paper, the parameters were increased from 2.6M to 2.7M, mAP was increased from 0.796 to 0.859, and F1 from 0.779 to 0.829.

OS11-4 Modulation Control Strategies for Ultrasonic Transducers

Chi-Wei Li, Chung-Wen HUNG*, Chun-Chieh Wang
(Nation Yunlin University of Science and Technology, Taiwan)

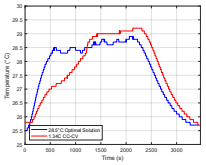
The modulation control strategies for ultrasonic transducers are discussed in this paper. In liquid atomization process, the output power needs to be modulated to control the particles and their distribution. The pulse width modulation (PWM) is used to adjust the amplitude of an ultrasonic oscillator, which is driven by an LC resonant circuit with automatic power point tracking to maintain stable oscillation. Three modulation methods: sinusoidal-, trapezoidal-, and intermittent on–off modulations are implemented and compared in this paper. The experimental results show that the intermittent start-up and cut-off is the most suitable method for power point tracking and meeting the atomization requirements.



OS11-5 Temperature-Controlled Multi-Segment Constant Current Charging Technique Based on PSO Algorithm

Chun-Liang Liu, Guan Jhu Chen, Ching Ju Chen*, Ting-An Chang, Jin-Chen Zhuo
(National Yunlin University of Science and Technology, Taiwan)

This paper introduces an optimized Constant Temperature-Constant Voltage (CT-CV) charging method with three stages. The initial stage uses a high current to quickly raise the battery temperature to a target level. The second stage maintains a stable temperature using twenty Constant Current segments optimized through Particle Swarm Optimization (PSO). The final stage applies a fixed voltage until the current reaches a cutoff. Experimental results at 28.5 °C demonstrate a 1.12% reduction in charging time, 1.73% in average temperature, and 1.08% in maximum temperature compared to other methods.



OS11-6 AIoT-Driven Smart Ecological Restoration of Sasakia Charonda Habitat

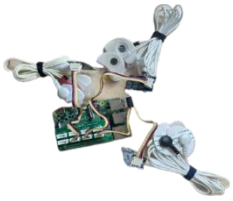
Ching-Ju Chen*, Zhao-Sheng Chen, Chun-Liang Liu, Candera Wijaya
(National Yunlin University of Science and Technology, Taiwan)

This study presents a smart ecological monitoring system for the Purple Emperor butterfly (Sasakia Charonda), an indicator species in Taiwan. Integrating NB-IoT and MQTT technologies, the system establishes a microclimate network for real-time environmental data collection. Combined with AI modeling, remote sensing, and GIS analysis, it evaluates the growth and distribution of Chinese hackberry (Celtis sinensis) and examines environmental effects on habitat restoration. Results demonstrate improved monitoring accuracy and management efficiency, supporting sustainable ecological conservation.

OS11-7 Swallowing Training Monitor

Nai-Hui Chien, Po-Ting Wang (Chang Gung University of Science and Technology, Taiwan)

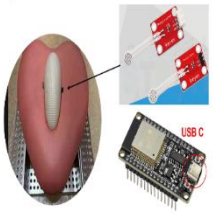
Dysphagia affects about 8% of the global population, leading to aspiration pneumonia, and reduced quality of life. Current rehabilitation depends on medical professionals, yet resources are limited and existing devices are costly. To address this, we developed a wearable AI-powered swallowing training device integrating Raspberry Pi and electromyography sensors. The system features real-time monitoring, voice guidance, vibration feedback, and cloud-based tracking via LINE. It analyzes muscle activity and adaptively adjusts training intensity, enabling caregivers and physicians to monitor rehabilitation progress remotely. The device provides a comfortable, cost-effective solution for dysphagia management. Future developments include AI optimization, VR/APP-based training, and clinical validation to improve patients' quality of life.



OS11-8 Assisted Pelvic Floor Muscle Training Device

Nai-Hui Chien, Tsai-Er Ho, Po-Ting Wang (Chang Gung University of Science and Technology, Taiwan)

Urinary incontinence (UI) affects ~20% of adults, with prevalence in older women up to 50–70%, causing physical discomfort, anxiety, depression, and social isolation. Pelvic floor muscle training (PFMT), such as Kegel exercises, is recommended but verbal instruction often fails to ensure correct activation, with ~40% of patients using compensatory muscles and adherence declining over time. To address this, we developed the Smart Pelvic Trainer, integrating AI, thin-film pressure sensors, and a mobile app. It provides guidance, real-time feedback, long-term data analysis, and gamified motivation, ensuring accurate muscle activation, improving PFMT effectiveness, supporting clinical practice, and enhancing patient quality of life and healthcare outcomes.



OS12 Mathematical Informatics (10)

Chair Amane Takei (University of Miyazaki, Japan)
Co-Chair Ryuusuke Kawamura (University of Miyazaki, Japan)

OS12-1 Broadening Access to Creative Experiences with MR 3D Painting

Takumi Ishimaru, Yu Oshikawa, Shizuki Nokura, Satoshi Ikeda, Kenji Aoki, Kaoru Ohe,
Amane Takei, Ryuusuke Kawamura, Makoto Sakamoto
(University of Miyazaki, Japan)

Access to arts experiences varies by income and locality, creating an experience divide. We present a low-barrier mixed-reality (MR) 3D-painting system that anchors strokes to real surfaces on a desk. At a university festival with local children, we used a within-participant, counterbalanced protocol (2-min 2D task, 2-min MR task, 4-min free MR creation). After each condition, participants rated five items—immersion, accomplishment, perceived creativity, self-efficacy, and intention to continue—on a 5-point Likert scale. We summarize condition-wise medians and within-participant differences. Findings will indicate whether MR can deliver meaningful creative experiences with minimal setup in everyday spaces, suggesting a practical path to broadening access irrespective of place or household income.

OS12-2 Proposal of a Muscle Training Method using EMG Visualization via Machine Learning

Yu Oshikawa, Takumi Ishimaru, Shizuki Nokura, Satoshi Ikeda, Kenji Aoki, Kaoru Ohe,
Amane Takei, Ryuusuke Kawamura, Makoto Sakamoto
(University of Miyazaki, Japan)

Strength training is essential for maintaining health and building an attractive physique, yet many people struggle to stick with it. One reason for this is that they fail to feel the effects of strength training. To maximize the effects of strength training, mastering proper form is essential. Therefore, I embarked on this research to reduce the number of people who quit strength training by visualizing muscle load in real time during workouts.We are developing a system that uses machine learning to visualize muscle load from user form, enabling muscle load visualization without requiring electromyography. At present, it is possible to estimate muscle load, but the accuracy of this estimation is low. Therefore, we are currently experimenting to improve the accuracy of muscle load estimation.

OS12-3 Unsupervised Defect Detection for Automatic Shiitake Sorting

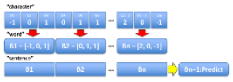
Shizuki Nokura[1], Leona Kimura[1], Takumi Ishimaru[1], Yu Oshikawa[1], Satoshi Ikeda[1], Kenji Aoki[1],
Kaoru Ohe[1], Amane Takei[1], Ryuusuke Kawamura[1], Makoto Sakamoto[1], Kazuhide Sugimoto[2]
([1]University of Miyazaki, Japan), ([2]SUGIMOTO Co., Ltd., Japan)

Automated shiitake sorting faces data imbalance and annotation difficulties. We compared data augmentation and unsupervised detection. First, augmenting scarce defective data with GANs failed; models either lost subtle defect features (e.g., discoloration) during pre-processing or overfit to augmentation patterns, proving label-less augmentation difficult. We then shifted to unsupervised anomaly detection (VAE+OC-SVM) trained only on good data. This model achieved perfect Recall (100%) for the defective class, identifying all bad items without a single miss. This "zero-miss" capability demonstrates its high practical utility as a primary screening tool for quality control.

OS12-4 Language Modeling of Discretized Numerical Time Series: An Empirical Study Using Transformers

Daiya Matsuyo[1], Makoto Sakamoto[1], Takao Ito[2], Satoshi Ikeda[1]
([1]University of Miyazaki, Japan), ([2]Hiroshima University, Japan)

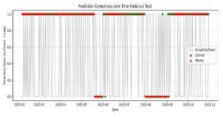
By discretizing daily stock price changes into five categories {−2, −1, 0, 1, 2}, the time series can be represented as a sequence over a five-symbol alphabet (e.g., [−1, 0, 2, 1, …]). By grouping every three consecutive days into a single token, the series can be viewed as a compact “language” with a 125-word vocabulary defined over these symbols. In this study, we apply a Transformer-based language model to learn patterns in this symbolic representation of stock movements. Using this approach, we evaluate the feasibility and effectiveness of treating financial time series as natural language and explore the affinity between such discrete temporal data and Transformer architectures.



OS12-5 Raising Issues with Evaluation Metrics for Predicting Highly Volatile Cryptocurrencies

Hyuma Kai[1], Makoto Sakamoto[1], Takao Ito[2], Satoshi Ikeda[1]
([1]University of Miyazaki, Japan), ([2]Hiroshima University, Japan)

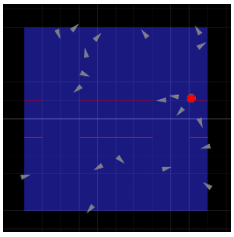
Cryptocurrencies exhibit substantial price volatility, and commonly used error metrics such as RMSE and MAPE do not necessarily reflect performance in ways that align with practical investment decisions. In particular, for Ethereum (ETH), which is the focus of this study, there are instances where numerical prediction errors remain small despite low directional accuracy, revealing inherent limitations in these metrics. This study systematically investigates this discrepancy by comparing regression and binary classification models within systems that incorporate algorithms suited to ETH price behavior as well as external factors. Furthermore, it proposes a new evaluation framework tailored to the unique characteristics of cryptocurrency markets.



OS12-6 Development of a Crisis-Avoidance Simulator Based on the Boids Model

Taiyo Hidaka, Makoto Sakamoto, Kenji Aoki
(University of Miyazaki, Japan)

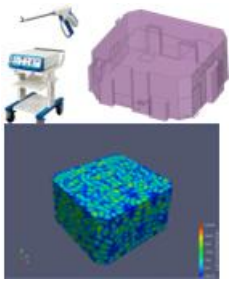
This study presented the development of a crisis avoidance simulator based on Reynolds' Boids model, designed to replicate crowd escape behavior in two-dimensional environments under attack scenarios. The simulator incorporated structural elements such as walls with openings, wall-induced reflection and repulsion, and line-of-sight occlusion. It featured a single attacker who pursued the nearest visible agent and multiple agents who attempted to flee. Simulation experiments conducted across various room configurations revealed that spatial structure and inter-agent attraction significantly influenced escape dynamics. These findings suggested that the proposed simulator could serve as a valuable tool for optimizing evacuation route design and emergency behavior planning.



OS12-7 Microwave Parallel FEM based on Iterative Domain Decomposition Method

Amane Takei, Makoto Sakamoto
(University of Miyazaki, Japan)

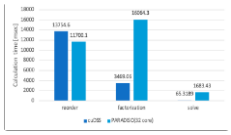
This paper describes large-scale parallel microwave numerical calculations based on the finite element method (FEM) with an iterative domain decomposition method. A stationary vector wave equation for the high-frequency electromagnetic field analysis is solved by taking an electric field as an unknown function. Although this solver is capable of detailed, fast and efficient FEM of large-scale high-frequency electromagnetic problems using the iterative domain decomposition method (IDDM) and the corresponding parallel distributed processing environment, it still requires a large number of iterative computation trials and computation time. In this study, we found that increasing the size of the subdomain in the IDDM improves the convergence of the accuracy of the iterative method and reduces the computation time. We are also considering replacing the solver with a subdomain solver that can handle larger subdomains.



OS12-8 Study on GPGPU Computing of Subdomain Solver in High-Frequency Electromagnetic Field Analysis

Biki Bidesh Biswas[1], Kento Ohnaka[1], Makoto Sakamoto[1], Amane Takei[1], Sota Goto[2]
([1]University of Miyazaki, Japan), ([2]University of Tokyo, Japan)

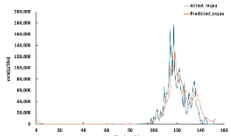
This study presents GPU acceleration of a subdomain solver for high-frequency electromagnetic field analysis using the finite element method (FEM). The solver is a direct sparse solver based on a parallel multi frontal algorithm implemented using NVIDIA's cuDSS library for sparse matrix factorization and solution. Implemented within the ADVENTURE_FullWave framework, the approach achieves efficient parallel computation of subdomain problems on GPGPU platforms. Benchmark results demonstrate significant speedup compared with CPU execution, confirming the effectiveness of cuDSS-based GPGPU computing for large-scale electromagnetic simulations.



OS12-9 Investigation of Features for Mango Yield Prediction using Long Short-Term Memory Networks

Hiroshi Kurita[1], Ryuusuke Kawamura[1], Kazunori Yamaguchi[2], Makoto Sakamoto[1]
([1]University of Miyazaki, Japan), ([2]Miyazaki Agricultural Experiment Station, Japan)

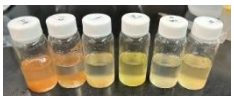
In mango cultivation in Miyazaki Prefecture, much of the production management relies on the empirical rules and intuitive judgments of agricultural workers. This study predicts mango yield using a Long Short-Term Memory (LSTM) model and investigates the impact of explanatory variables on prediction accuracy. A model developed using weather and harvest data from 2017 to 2024 demonstrated an approximate one-day error in predicting the peak harvest date; however, the overall trend in predicted yield closely aligned with the observed data. Through a comparison of feature selection, excluding unnecessary variables resulted in the highest prediction accuracy, demonstrating the importance of appropriate variable selection.



OS12-10 Comparative Study of Metal-Ion Adsorption and Gold Reduction by Crosslinked and non-crosslinked Sericin

Kaoru Ohe, Yudai Yamaguchi, Tatsuya Oshima
(University of Miyazaki, Japan)

Sericin is an underutilized biomass of hydrophilic protein removal during the refining process of silk yarn. Processing abundant functional groups such as hydroxyl, carboxyl, amide, and amino groups, sericin exhibits affinity for metal ions, making it a promising biosorbent. This study investigated the adsorption behavior of metal ions using sericin and glutaldehyde-crosslinked sericin (Glu-sericin). Glu-sericin selectively adsorbed precious metals over Cu(II) in 0.01 M HCl. In contrast, sericin showed a red color change after Au(III) adsorption from 0.01 M and 0.1 M HCl, indicating the reduction of Au(III) to Au(0). These results show that sericin non-crosslinked treatment, both adsorption and reduction functions, making it a unique biomass material for gold recovery.



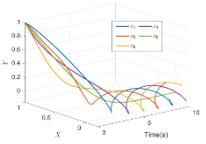
OS13 Intelligent Control (5) No Presentation

Chair Yingmin Jia (Beihang University, P.R. China)
Co-Chair Weicun Zhang (University of Science and Technology Beijing, P.R. China)
Co-Chair Lixia Yan (Tsinghua University, P.R. China)

OS13-1 Observer-Based Adaptive Prescribed-Performance Formation Control for Fully Actuated Multi-Agent Systems

Jiaming Zhang[1], Yang Liu[1], Yulin Duan[2]
([1]Beihang University (BUAA), P.R. China), ([2]Southern University of Science and Technology, P.R. China)

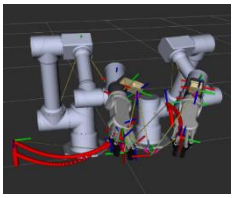
This article explores the adaptive distributed prescribed performance formation control problem for nonlinear high-order fully actuated multi-agent systems (HOFA-MASs). Firstly, we employ prescribed-time control technology to implement the observer design for the desired leader trajectory. Then, for each follower, a funnel controller is designed by using the prescribed performance funnel method and the HOFA control method, where the effect of uncertain parameter vector is eliminated by using adaptive control method. With the aid of barrier function, it can ensure that the formation errors are restricted by arbitrary accuracy at any prescribed time and realize the asymptotic formation control ultimately. Finally, the simulation studies on Unmanned Ground Vehicles (UGVs) demonstrate the effectiveness of the proposed schemes.



OS13-2 Coordinated Hybrid Visual/Force Servo Approach-Based Peg-in-Hole Assembly for a Master-Slave Dual-Arm Robot

Xuewen Zhang, Yingmin Jia, Yang Liu
(Beihang University (BUAA), P.R. China)

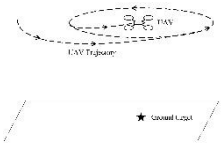
This paper proposes an efficient architecture for collaborative peg-in-hole assembly operation based on coordinated hybrid visual/force servo approach for a master-slave dual-arm robot. Equipped with an RGB camera for AprilTag identification, the master arm is responsible for grasping and screwing operations based on the visual servo algorithm. A force/torque sensor is mounted on the end of the slave arm to measure contact wrench, granting it the ability to regulate internal wrench while clamping the target. The control system is built based on ROS2, wherein the dual-arm robot is driven under the framework of Moveit! Servo, a software facilitating real-time robot control. Simulations in Gazebo are conducted, followed by experiments on a real dual-arm robot to validate the efficacy of the proposed architecture.



OS13-3 Range-Only Target Searching for Unmanned Aerial Vehicles in GPS-Denied Environments

Xuancheng You, Baoli Ma, Yue He (Beihang University (BUAA), P.R. China)

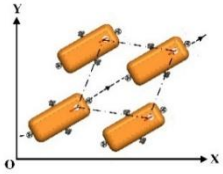
This paper proposes a UAV target searching method for GPS-denied environments relying solely on range measurements. To resolve the relative position ambiguity inherent in range-only data during linear motion, we first employ a range-based target circumnavigation control law, guiding the UAV to circle the target at a fixed distance. A designed observer then estimates the relative position, enabling the UAV to accurately move to and hover directly above the target. The method's effectiveness and feasibility are validated through numerical simulations and field experiments.



OS13-4 Formation Tracking Control of Multiple Underactuated Autonomous Underwater Vehicles

Lixia Yan, Qingqi Zhang, Yue Ma, Shiji Song (Tsinghua University, China)

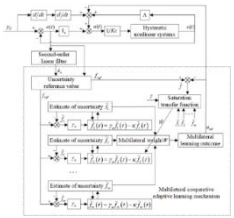
This paper investigates the formation tracking control for a group of underactuated autonomous underwater vehicles (AUVs). First, we simplify the AUV model into linear integrators by shifting the coordinated position from the center to a point in front of the AUV body. Second, the new coordinates, which incorporate neighboring communication, are utilized to derive the saturated formation tracking control law. It is proven that the formation tracking errors are convergent to zero asymptotically, and the moving directions of all AUVs are to the tangential direction of the position trajectory. Numerical simulations are carried out to validate theoretical results.



OS13-5 A Multilateral Cooperative Adaptive Learning Control Scheme for Hysteretic Nonlinear Systems

Yao Wang[1], Qunpo Liu[1,2], En-guang Yang[1], Guotai Li[1]
([1]Henan Polytechnic University, China)
([2]Henan International Joint Laboratory of Direct Drive and Control of Intelligent Equipment, China)

For a class of single-input single-output nonlinear systems with Backlash-like hysteresis and external disturbance, a multilateral cooperative adaptive learning controller is proposed to improve the response speed and tracking accuracy of the system trajectory tracking. The adaptive update rate is designed for the uncertainty estimate of the multilateral branch to complete the local update iteration. The multilateral learning result is exported by weighted fusion, and the uncertainty in the system is compensated. The differential of the error signal is obtained by a second-order linear filter, and the saturation conversion function is introduced to deal with the challenge caused by the rapid parameter change, and then the adaptive update rate of multilateral weight parameters is designed completely. The performance of PD controller and sliding mode neural network controller is compared to verify the effectiveness of the proposed control scheme.



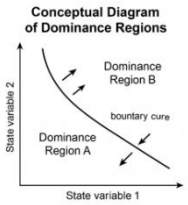
OS14 Natural Computing (3)

Chair Marion Oswald (Vienna University of Technology, Austria)
Co-Chair Yasuhiro Yasuhiro Suzuki (Nagoya University, Japan)

OS14-1 Dominance Regions: Geometric Framework for Multi-Component Dynamical Systems

Yasuhiro Suzuki (Nagoya University, Japan)

I introduce the concept of *dominance regions* as a new geometric framework for describing multi-component dynamical systems. A dominance region specifies where the influence of one component locally exceeds that of all others, producing a natural partition of state space through relative-rate comparisons. This structure reveals directional biases, highlights transition boundaries, and exposes latent organizing principles that govern system trajectories. It provides a minimal yet broadly applicable tool for analyzing the internal structure of high-dimensional interacting systems.



OS14-2 Algorithmic Observation and the Reconstruction of Scientific Rationality

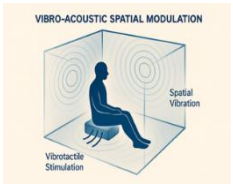
Yasuhiro Suzuki (Nagoya University, Japan)

This paper develops an algorithmic account of observation by treating Minakata Kumagusu's "koto" as a natural process generated through the observer's transformation. Subjectivity is defined as a non-formalizable algorithmic operation that produces observation rather than preceding it. Observation is thus a computational event linking natural and formal systems. This framework clarifies the structural limits of modern objectivist science and outlines a post-objective model in which observer and world co-evolve.

OS14-3 Vibro-Acoustic Spatial Modulation for Enhancing Environmental Experience in Interior Spaces

Yasuhiro Suzuki (Nagoya University, Japan)

Vibro-Acoustic Spatial Modulation for Enhancing Environmental Experience — [Your Name], Nagoya University, Japan — This study introduces a vibro-acoustic spatial modulation method that integrates controlled spatial vibration with gentle tactile stimulation to create a coherent multisensory field without audible cues; objective measurements showed reproducible changes in acoustic structure and spatial coherence, and pilot demonstrations indicated enhanced calmness, natural presence, and environmental comfort, suggesting applicability to wellbeing-oriented spatial design while technical details remain proprietary.



OS15 Human Machine Interface I (4) Online Presentation

Chair Norrima Mokhtar (Universiti Malaya, Malaysia)
Co-Chair Siti Sendari (Universitas Negeri Malang, Indonesia)

OS15-1 Engineering Design and Numerical Simulations of Upper Limb Exoskeleton for Rehabilitation

Pringgo Widyo Laksono[1], Eko Wahyu Abryandoko[1], Lobes Herdiman[1], Norrima Mokhtar[2]
([1]Universitas Sebelas Maret, Indonesia), ([2]Universiti Malaya, Malaysia)

This study presents a 4-DoF upper-arm exoskeleton for post stroke rehabilitation using integrated kinematic, dynamic, and FEA analysis. The system includes three active actuators (ball-screw linear translation, shoulder–elbow flexion–extension, and supination–pronation) and one passive spring-based wrist joint. Kinematic simulations show accurate reproduction of physiological motion. Dynamic analysis indicates a torque requirement of 22.76 Nm, and a minimum linear torque of 0.0278 Nm for actuator specification. The supination–pronation module achieved a safety factor >2. FEA results show maximum stress of 9.09×10^5 N/m², deformation of 1.96×10^{-2} mm, and a structural safety factor of 4.56×10^{11}. Overall, the design demonstrates high structural integrity and strong potential for safe, adaptive stroke rehabilitation.

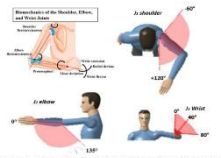
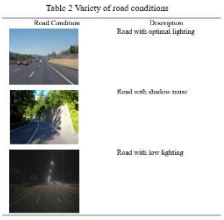


Figure 1. Biomechanical configuration of arm movement

OS15-2 Performance Evaluation of Deep Learning-Based Resnet, MobileNetV2 and DenseNet Models for Road Lane Detection

Joko Slamet Saputro[1], Ananda Putra Kanieza[1], Pringgo Widyo Laksono[1], Norrima Mokhtar[2]
([1]Universitas Sebelas Maret, Indonesia), ([2]Universiti Malaya, Malaysia)

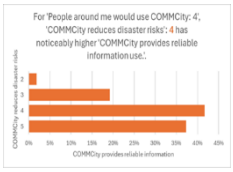
This study presents a performance comparison of three backbone architectures—MobileNetV2, ResNet, and DenseNet—for road lane detection using Mask R-CNN. The evaluation employs three key metrics: loss function, mean Intersection over Union (mIoU), and pixel accuracy, supplemented by inference time testing. Experimental results demonstrate that DenseNet achieves the highest segmentation accuracy, with the lowest training loss and mIoU exceeding 0.95. ResNet strikes a balance between accuracy and efficiency, while MobileNetV2 excels in training and inference speed, making it ideal for real-time applications. Tests were conducted on Google Colab using a Tesla T4 GPU, confirming the relevance of these findings for cloud-based computing environments with limited resources.



OS15-3 CommCity: An Integrated Multi-Modal Platform for Urban Disaster Resilience through Hybrid Route Optimization and AI-Driven Community Intelligence

Mohd Heikal Husin[1], Azleena Mohd Kassim[1], Nor Shamira Sabri[1], Noor Farizah Ibrahim[1]
Siti Rahyla Rahmat[2]
([1] Universiti Sains Malaysia, Malaysia), ([2] Universiti Sains Malaysia, Malaysia)

This study presents the CommCity Platform, an integrated System-of-Systems (SoS) designed to enhance urban resilience. CommCity covers the dynamic evacuation routing for citizens using Hybrid Genetic Algorithm and Simulated Annealing (GA-SA), the AI-driven community intelligence using Natural Language Processing approach for situational awareness derived from crowdsourced public data, as well as community-centric vehicle and asset safety management. CommCity demonstrates a paradigm for urban disaster management, shifting from isolated applications to an interconnected, multi-stakeholder platform. The results show that the hybrid GA-SA achieves strong performance, and integrating AI with validated community input is feasible and valued by potential users.



OS15-4 Bridging Design for Manufacturing and Assembly (DFMA) with High-Speed Vision - Robotics: Toward Integrated Design and Cycle Time Reduction in High-Mix Low-Volume Production

Hendi Herlambang[1], Pringgo Widyo Laksono[1], Ilham Priadythana[1], Norrima Mokhtar[2]
([1]Universitas Sebelas Maret, Indonesia), ([2]Universiti Malaya, Malaysia)

This paper reviews how Design for Manufacturing and Assembly (DFMA) can be integrated with Vision-Guided Robotics to improve High Mix Low Volume (HMLV) production. Using publications from 2015–2025, the review analyzes trends in DFMA, robotic vision, and automation through bibliometric mapping and thematic synthesis. Three key research themes emerge: cycle time reduction, real-time adaptability, and design for perception. While many studies highlight DFMA features that improve detection and robotic grasping, there is still a lack of quantitative models linking DFMA parameters to robotic performance. The review identifies future opportunities such as design-for-perception guidelines, digital twin–based design and scheduling analysis, and transferable perception systems for highly variable environments. These directions strengthen DFMA–robotics integration and support significant improvements in automation efficiency.

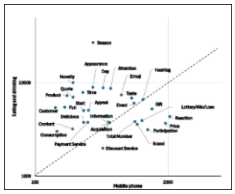
OS16 Narrative, Sensibility, and Cognition: Post-narratological Discussion for Humans and Robots (12)

Chair Jumpei Ono (Aomori University, Japan)
Co-Chair Hiroki Fxyma (Kobe University, Japan)
Co-Chair Yukiko Furuya (Chiba University, Japan)
Co-Chair Takashi Ogata (Yamato University, Japan)

OS16-1 An Analysis of Post Content and Like Ratings - Differences by Product Category and Media –

Yoji Kawamura (Kindai University, Japan)

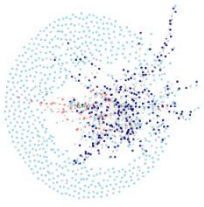
The purpose of this study is to analyze "like" ratings for posts made by official social media accounts, and to clarify trends in post content and "like" ratings, as well as differences between product categories and media.
First, the content of official account posts and ratings (number of "likes," "retweets," and "replies") over a one-year period were collected from database services such as social media. Next, morphological analysis software was used to extract keywords from the posts, and similar keywords were grouped together and classified into hypernyms. The classified hypernyms were then compared by product brand and media.



OS16-2 Disinformation Narrative Distribution and Generation Using Generative AI

Jumpei Ono (Aomori University, Japan), Takashi Ogata (Yamato University, Japan)

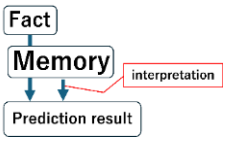
In recent years, concepts such as cognitive security and cognitive warfare have attracted increasing attention, and the mechanisms by which disinformation distorts the cognition of societies and individuals are being actively studied. Although this issue has become an urgent topic in Japan, research in this field remains in its developmental stage. This study aims to simulate the distribution process of disinformation in a virtual scenario where a group targets an individual on social media, based on real-world data, and to analyze the generation of disinformation narratives using generative AI. The results of this research are expected to contribute to the development of systems for detecting and countering disinformation narratives.



OS16-3 Graph-Based Next-Event Prediction Methods Considering the Interrelationships among Game Players' Memories: Focusing on a Card Game

Koki Nishiyama (Yamato University, Japan), Hiroki fxyma (Kobe University, Japan)
Takashi Ogata (Yamato University, Japan)

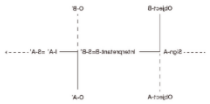
The aim of this study is to understand the process by which humans form a hierarchy of predictions when anticipating future developments of events and taking actions accordingly. Predictions are not necessarily based on probabilistic judgments; rather, even in situations where probabilities cannot be quantitatively assessed, people make guesses by referring to memory and constructing their own theories in relation to the current situation. In this paper, we compare and examine three computational models that represent "relational values" to investigate how experience-based theory construction contributes to predicting future developments.



OS16-4 Category-Theoretic View of Social Repair: Minimal Supplementation in Human Dialogue

Yukiko Furuya, Akinori Abe (Chiba University, Japan)

This study proposes a framework for how humans detect and repair interpretation gaps in dialogue and collaborative narrative construction. We argue that repair is not a full stop-and-explain move, but a "minimal supplementation": supplying only the missing assumption, using previously shared relational or situational patterns, to restore continuity and mutual understanding. We reinterpret this as on-the-spot interpersonal regulation, consistent with abductive and analogical accounts of filling missing knowledge (Abe, 1999). Drawing on 5 dyadic improvisations and 10 post-performance interviews, we code where gaps are perceived and what assumption is said to have been inserted. We further model repair as a minimal structural completion of the interaction between conversational states — treating dialogue states as objects and role-relational links as morphisms — thereby situating repair in a category-theoretic, compositional view of interaction. We suggest that this principle can inform socially responsive robot behavior that maintains rapport without intrusive overcorrection.



OS16-5 Toward a Multi-layered Computational Model of Structure and Meaning in *Onna Koroshi Abura no Jigoku* for AI-based Narrative Generation

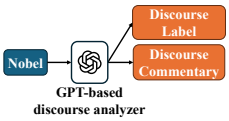
Sakura Kawai, Takashi Ogata (Yamato University, Japan)

The authors have conducted research aimed at confirming and extending the characteristics of an author's (S. Kawai) literary and artistic "empathy." In particular, we surveyed papers and books related to human sympathy and empathy and analyzed the author's cognitive characteristics based on her reading and writing tendencies. Moreover, we intentionally selected a famous narrative work, *Onna Koroshi Abura no Jigoku* by Chikamatsu Monzaemon, which has a strong storyline that does not easily attract a reader's sympathy. Through the above research process, we recognized the necessity of a detailed narrative analysis of this work. In this paper, we report on a concept of narrative analysis that includes both structural and semantic levels for a detailed examination of the narrative. The structural level deals with the discoursal process, repetition and tension-building mechanisms, and narration methods used in actual performances. In contrast, the semantic level corresponds to a set of events involving mainly characters, places, times, and objects.

OS16-6 Toward Computational Narrative Discourse Analysis with Large Language Models: A Case Study on a Japanese Short Novel

Riku Takahashi, Ayahiko Niimi (Future University Hakodate, Japan)

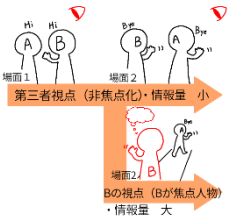
This study investigates the role of large language models (LLMs) in facilitating narrative discourse analysis for computational comprehension of narratives and robotic cognition. Narrative discourse pertains to the aspects of who narrates, what is narrated, when it occurs, and from whose perspective. The field of narrative discourse remains underexplored in computational linguistics, as traditional narrative analysis frameworks encounter challenges in modeling the perspective, temporal, and interpretive dimensions emphasized in Gérard Genette's discourse theory. To address these challenges, this study explores the potential of LLMs as an innovative approach to narrative discourse analysis. We conducted prompt-based discourse analyses of a Japanese short novel using the GPT-5, GPT-5-mini, and GPT-4o models. The findings indicate that GPT-5 demonstrates stable labeling and generates commentaries that effectively capture discourse structures, such as focalization and narrative distance.



OS16-7 Blending a Visual Novel and Narrative Discourse Theories Using Generative AI

Yuka Okayama (Yamato University, Japan), Jumpei Ono（Aomori University, Japan)
Takashi Ogata (Yamato University, Japan)

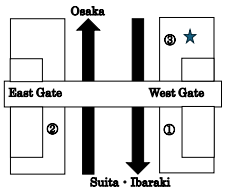
The framework of a "visual novel" on a computer allows for diverse story lines based on a single narrative world. This research aims to implement organized and systematic mechanisms for narrative representation within visual novels to enable diverse narrations. While the narrative discourse theory by Gerard Genette is an analytical framework that systematically studies narrative works, Ogata reorganized the theory from a constructive viewpoint for application in computer-based narrative generation systems. The basic idea of this paper is to use narrative discourse techniques for the visual novel to flexibly, automatically, and in real time create diverse narrative representations at various points in the user's reading. In this paper, we present our visual novel work, "Slime Cat," as a template for future integration with diverse narrative discourse mechanisms.



OS16-8 Acquiring Creative Narrative Generation Techniques from the Behaviors and Cognition of Individuals with Autism Spectrum Disorder

Misao Ichio (Yamato University, Japan), Jumpei Ono (Aomori University, Japan),
Shin'ichiro Aoki (Iwate Prefectural University, Japan), Takashi Ogata (Yamato University, Japan)

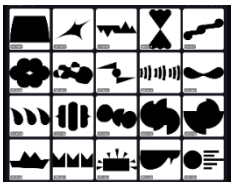
This study aims to identify and systematize creative and rhetorical narrative generation techniques inspired by the behaviors and cognition of individuals with Autism Spectrum Disorder (ASD). In our previous study, we analyzed several narratives created by people with ASD and extracted distinctive narrative generation techniques from their storytelling processes. We then conducted simulations applying these techniques to narrative generation tasks. Based on that foundation, this paper categorizes the previously acquired techniques into two hierarchical levels: macro-level and micro-level narrative techniques. We present the detailed structure and characteristics of each level and discuss how they can be applied to create novel and engaging narratives.



OS16-9 Developing a Shape Dataset for Multimodal Evaluation of Taste and Flavor

Hiroki Fxyma (Kobe University, Japan)

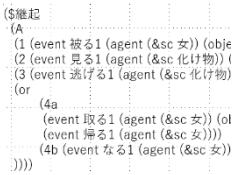
This study aims to develop a standardized set of abstract shapes for evaluating the subjective impressions of taste and aroma. To construct a perceptually diverse and experimentally usable stimulus set, I compiled a dataset of 750 abstract images and extracted 126-dimensional morphological features using WinROOF. Based on these high-dimensional shape descriptors, we performed clustering to organize the images into structurally coherent groups. The analysis yielded 48 clusters, each representing a distinct pattern of geometric and morphological characteristics. For each cluster, I examined its internal feature distribution and selected a representative image that best captured the cluster's central properties. The resulting set of 48 representative shapes provides a manageable and interpretable subset of the broader 750-image space, enabling controlled presentation in sensory and psychophysical experiments. This study establishes a quantitative foundation for nonverbal evaluation of taste and aroma and offers a systematically constructed visual stimulus set for subsequent multimodal research linking flavor perception and shape representation.



OS16-10 Toward AI-based Narrative Generation Techniques Based on the Narrative Structures of Japanese Folktales

Jumpei Ono (Aomori University, Japan), Takashi Ogata (Yamato University, Japan)

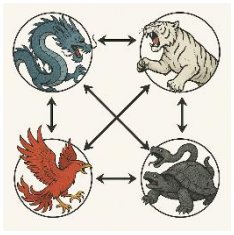
This study explores a method for generating new narrative structures by integrating structural analysis of Japanese folktales with artificial intelligence techniques. Based on *Nihon Mukashi Banashi Taisei* (*The Complete Collection of Japanese Folktales*) compiled by Keigo Seki and et, al, the authors represent Japanese folktales as hierarchical tree structures extracted from events within the text. By manipulating these tree structures through evolutionary computation and generative adversarial networks, the study attempts to edit structural features of the original folktales and merge multiple folktales, thereby generating novel and coherent narratives.



OS16-11 Design and Development of a Narrative World for a Multi-agent-based Narrative Generation Role-Playing Game

Hikaru Sugizawa (Yamato University, Japan), Ono Jumpei (Aomori University, Japan)
Takashi Ogata (Yamato University, Japan)

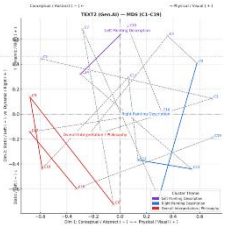
The goal of this research is to develop a novel type of role-playing game that automatically generates narratives through multi-agent simulations of diverse characters' events. In our previous study, we designed a narrative world consisting of four countries and multiple types of characters as a fundamental framework for this developmental research. In this paper, we describe the overall structure of the narrative world and the development of a prototype system based on this structure, which includes various elements, such as countries, characters, and events. Furthermore, we present several results from event simulations and narrative generation experiments to identify current challenges and future directions.



OS16-12 The Aesthetic Mindscape: Visualizing Human and AI Narratives in Abstract Art

Jun Nakamura (Chuo University, Japan), Sanetane Nagayoshi (Shizuoka University, Japan)

Recent advances in generative AI have allowed machines to produce narrative-like interpretations of artworks that evoke a sense of human reflection. This study investigates how sensibility emerges differently in human and AI cognition through the interpretation of an abstract painting by Pablo Picasso. Using multidimensional scaling (MDS), we visualize semantic structures within human and AI-generated texts to reveal their narrative tendencies. Human interpretation demonstrates a fluid interplay between perception and introspection, seamlessly shifting between physical observation and conceptual imagination. In contrast, AI constructs a coherent yet detached narrative, systematically organizing visual information into an analytical sequence. By positioning these differences along cognitive axes of conceptual–physical and static–dynamic expression, the study illuminates how narrative structure embodies distinct modes of sensibility. These findings contribute to post-narratological discussion by exploring how the act of description itself becomes a mirror of cognition for both humans and machines.



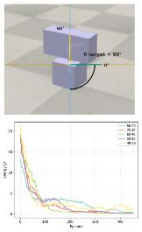
OS17 Human Machine Interface II (3) Online Presentation

Chair Norrima Mokhtar (Universiti Malaya, Malaysia)
Co-Chair Pringgo Widyo Laksono (Universitas Sebelas Maret, Indonesia)

OS17-1 Experimental Analysis of Energy-Aware Reward Function for Q-Learning in Single-Joint Robotic Manipulator

Giri Wahyu Wiriasto[1,2], Dyah Lestari[1], Muhamad Syamsu Iqbal[2], Siti Sendari[1*] Norrima Mokhtar[3]
([1] Universitas Negeri Malang, Indonesia) ([2] Universitas Mataram, Indonesia)
([3] Universiti Malaya, Malaysia)

This study proposes an Energy-Aware Q-Learning framework for a single-joint robotic manipulator to explicitly balance energy consumption and motion performance. By testing various reward weight configurations (Energy: Performance), the research found that excessive energy weighting (e.g., 70:30) results in lower minimum energy but conservative behaviour. The 60:40 configuration provided the optimal trade-off, achieving the highest efficiency score (662.25 J^{-1}), highest average reward, and a 100% success rate. The results demonstrate that integrating energy-aware reward shaping creates more adaptive, stable, and energy-efficient robotic control policies.



OS17-2 Bearing Fault Identification System of Three-Phase Induction Motor Using Vibration Signal-based Backpropagation Neural Network

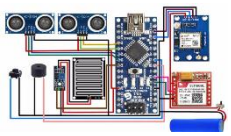
Dwiky F. Syahbana[1], Muhammad Shandar F. Faseh[1], Fauzi I. Adhim[1], Norrima Mokhtar[2]
([1] Institut Teknologi Sepuluh Nopember, Indonesia), ([2] Universiti Malaya, Malaysia)

This study proposes a Backpropagation Neural Network (BPNN) approach for classifying the condition of three-phase induction motor bearings using vibration data, a critical factor in industrial reliability. The BPNN achieved the highest accuracy on the standard SUBF v1.0 dataset, and its performance was further evaluated on a real-world conveyor prototype. While the model demonstrated highly accurate and stable detection for the normal and outer fault classes in the prototype, it showed high precision but low recall for the inner fault class, indicating frequent failures to detect actual inner race faults. Overall, the research validates the BPNN as a promising solution for vibration-based fault diagnosis in both controlled and real-world settings but highlights the necessity of further optimization to overcome practical challenges in reliably detecting inner race faults.

OS17-3 Assistive Navigation Stick for the Blind

Norul Ashikin Norzain, Mohd Azwan Ramlan, Hanisah Mohd Zali, Nik Nur Zuliyana Binti Mohd Rajdi, Maisarah Binti Lutfi (MAHSA University, Malaysia)

This paper describes the design and evaluation of a low-cost, multi-sensor Assistive Stick for the Blind developed to improve navigation safety and independence for visually impaired users. The embedded system integrates dual ultrasonic sensors for short-range obstacle detection, a water sensor for identifying slippery surfaces, a GPS module for outdoor localization, and a buzzer for real-time acoustic alerts. Experimental results confirmed the system's reliability: the ultrasonic sensors consistently detected obstacles within 30 cm, the water sensor provided rapid hazard warnings for wet surfaces, and the GPS achieved location accuracy of within 5-10 meters outdoors. The study successfully validates this compact, user-oriented device as a practical tool that combines essential environmental sensing and location tracking, offering a scalable platform for future integration of advanced features like GSM and AI



OS18 Human Machine Interface III (4) Online Presentation

Chair Norrima Mokhtar (Universiti Malaya, Malaysia)
Co-Chair Heshalini Rajagopal (MILA University, Malaysia)

OS18-1 Ensemble of Convolutional Neural Networks (CNN) to classify different classes of demented Alzheimer's disease patients

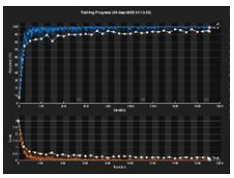
Amutha S[1], Nitish Menon[1], Dhanush R[1*], Heshalini Rajagopal[2]
([1]Vellore Institute of Technology Chennai, India), ([2]MILA University, Malaysia)

Automated Alzheimer's disease detection marks a major improvement in the effectiveness and early diagnosis of the illness compared to older techniques. Conventional approaches frequently depend on laborious and error-prone subjective clinical evaluations, cognitive testing, and manual interpretation of medical imaging. This article recommends a better AD classifier from MRI (Magnetic Resonance Image) brain images, exploring the weighted ensemble of different Convolutional Neural Networks (CNNs) with multiple layered architecture. The proposed Ensemble Models perform much better than the candidate models, such as InceptionV3, VGG-19, LeNet and MobileNet. The findings show increased diagnostic accuracy, providing a possible path for the early identification and categorization of AD using neuroimaging data.

OS18-2 Transfer Learning for Chinese Herbal Leaves Recognition: A Comparative Study of ResNet-50, DarkNet-53, SqueezeNet, EfficientNet-B0, and GoogLeNet

Lyu SiQian[1], Heshalini Rajagopal[1*], Zaris Izzati Mohd Yassin[1], Peng Lean Chong[1], Norrima Mokhtar[2]
([1] MILA University, Malaysia), ([2] Universiti Malaya, Malaysia)

Chinese herbal leaves identification is critical for traditional medicine, quality control, and biodiversity conservation. However, manual identification is time-consuming and error-prone, while existing automated methods struggle with complex leaf morphologies. Therefore, this study investigates the performance of five pre-trained convolutional neural network (CNN) models, namely DarkNet-53, EfficientNet-B0, GoogLeNet, ResNet-50 and SqueezeNet in recognizing 20 species of Chinese herbal leaves using transfer learning. The results demonstrated that EfficientNet-B0 and ResNet-50 outperformed the other three models. The proposed system aims to achieve real-time recognition with higher accuracy, providing a scalable solution for herbalists and pharmaceutical industries.



OS18-3 Deep Learning for Paddy Leaf Disease Segmentation: An Exploratory Study

Muhammad Amirul Aiman Asri[1], Wenjunliang Zhang[1], Norrima Mokhtar[1*], Raza Ali[2], Takao Ito[3], M. Aziz Muslim[4], Siti Sendari[5], Pringgo Widyo Laksono[6], Tsutomu Ito[7]
([1] Universiti Malaya, Malaysia), ([2]Balochistan University of Information Technology, Pakistan), ([3]Hiroshima University, Japan), ([4]Universitas Brawijaya, Indonesia), ([5]Universitas Negeri Malang, Indonesia), ([6] Universitas Sebelas Maret, Indonesia), ([7]Ube National College of Technology, Japan)

The study established a unified benchmark for the pixel-accurate segmentation of paddy leaf lesions using the 2,444 images, manually annotated Kaggle New Paddy Doctor dataset, which covers Bacterial Leaf Blight, Brown Spot, and Hispa. The research evaluated U-Net, U-Net++, and DeepLabV3 (with a ResNet-50 backbone) under both per-disease and pooled training protocols. DeepLabV3 achieved the best average Dice score (approx. 0.70), though performance varied significantly, with Brown Spot proving the most challenging. The key finding was that training a single pooled model resulted in slightly lower performance than training models specific to each disease. This work provides critical baselines and practical guidance on optimal architecture and training strategies for field deployment.

Figure 1 Mask for diseases

OS18-4 Performance Analysis of Paddy Disease Classification Using Multiple Yolo Models

Wenjunliang Zhang[1], Shunta Kimura[2], Muhammad Amirul Aiman Asri[1], Norrima Mokhtar[1*], Heshalini Rajagopal[3], Ryosuke Harakawa[2], Masahiro Iwahashi[2], Rahmadwati[4], Takao Ito[5], Siti Sendari[6], Pringgo Widyo Laksono[7]
([1] Universiti Malaya, Malaysia), ([2]Nagaoka University of Technology, Japan), ([3] MILA University, Malaysia), ([4]Universitas Brawijaya, Indonesia), ([5]Hiroshima University, Japan), ([6]Universitas Negeri Malang, Indonesia), ([7] Universitas Sebelas Maret, Indonesia)

This study benchmarked the classification heads of YOLOv5, YOLOv8, and YOLOv11 (nano and medium variants) for fast, field-ready rice-disease recognition using the New Paddy Doctor dataset. An eight-class leaf subset (6,627 images) was curated and evaluated under a unified 224×224 training protocol. Metrics include accuracy, Macro-F1, Weighted-F1, confusion matrices, and model complexity (parameters and FLOPs). YOLOv8-m achieves the highest accuracy for 99.9%, followed by YOLOv11 variants 99.8%, while YOLOv5 attains 95%. We further assess accuracy–complexity trade-offs and provide deployment-oriented recommendations. Dataset splits and configurations are released to ensure reproducibility.

OS19 Research Towards the Renewable Energy and the Sustainable Development Goals (SDG's) (10) Online Presentation

Chair Ammar A.M. Al Talib (UCSI University, Malaysia)
Co-Chair Takao Ito (Hiroshima University, Japan)

OS19-1 Prediction of Occupant's Head Movement during Slalom Driving via Ensemble Learning Model

Wong Wei Herng[1], Sarah 'Atifah Saruchi[2], Ammar A.M. Al-Talib[3], Sharifah Munawwarah[4], Mohd Hatta Mohamed Ariff[5], Nurhaffizah Hassan[6], Nor Aziyatul Izni[7], Alvi Khan Chowdury[8]
([1,3]UCSI University, Malaysia, [2]UMPSA, Malaysia, [4]University of Tsukuba, Japan, [5]UTM, Malaysia, [6,7]UiTM, Malaysia, [8]Monash University, Malaysia)

Research on motion sickness (MS) shows that head movement plays a crucial role during slalom driving, where the drivers commonly tilt their heads against centripetal force, whereas the passengers tilt their heads aligning with it. Existing studies rely heavily on sensors attached to occupants' heads to analyse these motion patterns. Although accurate, such intrusive sensing is impractical for continuous monitoring. To address this limitation, this study proposes an ensemble prediction model combining Artificial Neural Networks (ANN) and Support Vector Machines (SVM) to estimate head movements without physical sensors. Simulations show that the ensemble approach achieved the lowest root-mean-squared-error (RMSE), outperforming individual ANN and SVM models.

OS19-2 Smart Elderly Health Monitoring Device Via Internet-of-Things (IoT)

Eii Tze Xian[1], Sarah, Atifah Saruchi[2], Wan Zailah Wan Said[3], Ammar A.M. Al-Talib[4], Nor Aziyatul Izni[5], Nurhaffizah Hassan[6], Alvi Khan Chowdury[7], Sheikh Muhammad Hafiz Fahami[8] ([1,3,4]UCSI University, Malaysia, [2,8]UMPSA, Malaysia,[5,6]UiTM, Malaysia, [7]Monash University, Malaysia)

The ageing global population has led to a rise in older adults living alone, increasing their risk of accidents and medical emergencies. Traditional monitoring methods are often inadequate, resulting in delayed intervention and compromised care. Thus, this study proposes an IoT-based smart healthcare device designed for continuous and remote monitoring of geriatric elderly. The system integrates multiple sensors, including temperature, pulse, accelerometer, and fall detection to assess vital signs and identify abnormal events. Results show that the device is capable of sending immediate alert notification once an aberrant occurrence, such as abnormal temperature and heart rate, as well as a fall.

OS19-3 Smart Petting System Via Internet of Things (IoT)

Siah Jing Yi[1], Sarah, Atifah Saruchi[2], Wan Zailah Wan Said[3], Ammar A.M. Al-Talib[4], Nurhaffizah Hassan[5], Nor Aziyatul Izni[6], Sunmiya Fujita[7] ([1,3,4]UCSI University, Malaysia, [2,7]UMPSA, Malaysia,[5,6]UiTM, Malaysia)

Pet owners often struggle to provide consistent, nutritious meals due to time constraints, while long vacations further complicate pet care. This paper presents an Internet-of-Things (IoT) based smart petting system designed to address these challenges through automated, real-time monitoring of pet feeding activities. The developed prototype integrates an ESP32 microcontroller to manage three key subsystems: an automated feeder, an automated water dispenser, and a real-time monitoring module. The system features a user dashboard, mobile application for remote control, a camera for pet observation, and Telegram-based notifications. Experimental validation demonstrated efficient system performance, with sensor readings maintained within a 5% accuracy margin.

OS19-4 Seawater Desalination and Purifier Machine

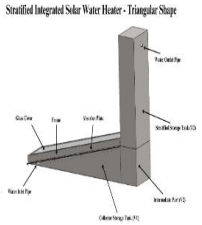
Alvin Loke Ting Foong[1], Ammar A.M. Al-Talib[1], Rodney Tan Hean Gay[1], Sarah ‘Atifah Saruchi[2] ([1]UCSI University, Malaysia), ([2]UMPSA, Malaysia)

Water scarcity remains a pressing global challenge, particularly in coastal and remote regions where access to clean drinking water is limited. This project presents the design, fabrication, and evaluation of a solar-powered seawater desalination and purification system aimed at providing a sustainable and affordable source of potable water. The system utilizes solar photovoltaic panels to supply the required energy and incorporates a distillation-based process to convert seawater into freshwater. A prototype was developed and tested under varying salinity levels of 23 ppt, 30 ppt, and 33 ppt to evaluate system performance, water quality, and efficiency. Experimental results indicated that the system consistently produced between 3.1 and 3.6 liters of distilled water per day, with desalination efficiencies ranging from 79% to 85%.

OS19-5 A Compact Stratified Integrated Solar Water Heating System

Farouk Hesham Farouk Elkholy[1], Ammar A.M. Al-Talib[1], Rodney Tan Hean Gay[1], Sarah 'Atifah Saruchi[2],
([1]UCSI University, Malaysia), ([2]UMPSA, Malaysia)

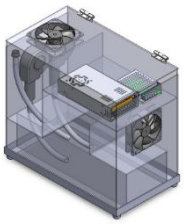
The only limitation to the effectiveness of integrated collector-storage solar water heaters in the rainy tropical areas is night cooling. This is a prototype and field-test of a 70 L Compact Stratified Integrated Solar Water Heating System (CSISWHS) that has a 30 L collector tank, a 10 L intermediate section and a 30 L stratified storage tank in SS316 with aluminum-foil bubble insulation and waterproof foil tape. K-type four thermocouples were connected to important nodes, digitized with an ESP32-CAM, and recorded in real time with a cloud spreadsheet; the SM206 solar meter was used to measure solar radiation manually. On 34 successive outdoor days (Malaysia, July August 2025) we used ISO 9459: static testing (no draw) and dynamic testing with three 25 percent draw/refill events at approximately 07:00, 13:00 and 19:00. The CSISWHS met the targets during most days when evening water regularly hit 40-50 °C and top layer was at or above 35 °C by 06:00 except in the event of persistent rain.



OS19-6 Air Purifier and Humidifier using Water as Filter

Koh Yong Chuan[1], Ammar A.M. Al-Talib[1], Sarah Atifah Saruchi[2], Firas Basim Ismail[3]
([1]UCSI University, Malaysia), ([2]UMPSA, Malaysia), ([3]Universiti Tenaga Nasional, Malaysia.)

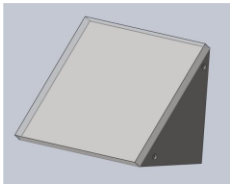
Air pollution reached alarming levels in 2021, posing a severe threat to global health. According to the World Health Organization (WHO), approximately 7 million people lose their lives each year due to prolonged exposure to polluted air. Shockingly, around 91% of the world's population breathes contaminated air daily. This not only affects outdoor environments but also means that the air inside our homes is far from clean. To address this growing concern, Author have designed a compact air purifier that eliminates the need for costly filters by utilizing water as a natural filtration system. Additionally, this device serves as an air humidifier and an essential oil diffuser, promoting relaxation while also combating certain airborne bacteria and viruses. The system operates using two high-power, low-noise centrifugal fans that effectively draw in air through a protective mesh.



OS19-7 Compact High Efficiency Solar Water Heater

Lee Shi Wei[1], Ammar A.M. Al-Talib[1], Sarah 'Atifah Saruchi[2],
([1]UCSI University, Malaysia), ([2]UMPSA, Malaysia)

This project aims at the design and manufacture of a high-efficiency solar water heater which would have a triangular tank structure. The design capacity of the system is capable of heating 30 liters of water to a desired range of temperature between 40 and 50 °C hence it is applicable in domestic setups. The tank body was made of stainless steel with flat black paint as absorber coat, polyurethane foam as insulator and acrylic sheets as transparent cover. The procedures included cutting processes, welding, coating, insulation and fitting of valves. Two approaches were undertaken, Static testing (consisting of constant heating and cooling without draw off) and Dynamic testing (under realistic conditions of 25% draw-off at 8:00 am, 2:00 pm, and 8:00 pm). Static tests demonstrated the peak temperature of over 50 °C and efficiencies ranged between 55 and 94 percent and dynamic testing confirmed systems capacity to capture heat after draw-offs and maintain a usable water temperature.



OS19-8 Smart Safety Features for Motorcyclists' Safety Using IoT: Integrated Blind-Spot Monitoring, Forward-Collision Alerts, and Crash Detection with Real-Time Notification

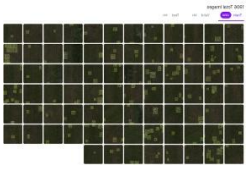
Ismailarta Ali Mohamoud, Ahmed Suliman Khaled, Samy Elmasri, Faisal Yaqoob, Omar Wael, Noor Idayu Binti Mohd Tahir, Ammar A. M. Al-Talib (UCSI University, Malaysia)

Motorcycle riders, particularly delivery and courier riders, face elevated crash risk due to high road exposure, dense traffic, and time pressure. This paper presents a low-cost IoT-enabled motorcycle safety prototype integrating (i) blind-spot monitoring, (ii) forward-collision alerts, and (iii) crash detection with real-time notification. Pre-crash functions use ultrasonic ranging to detect nearby vehicles/objects and provide immediate warnings through side LEDs and an audible buzzer. Post-crash detection uses an ESP32 with inertial sensing and GPS to detect severe events and transmit alerts to an IoT dashboard and email contact. A working prototype was developed and evaluated through controlled tests for proximity detection and crash-event triggering, demonstrating consistent warning behavior and successful notification with location reporting. The design provides a practical retrofit pathway toward improved rider safety using affordable components and a modular architecture.

OS19-9 Weed Mapping and Management Prediction Using Image Processing

Osama Gariballa, Noor Idayu Mohd Tahir, Ammar A.M. Al-Talib; (UCSI University, Malaysia)

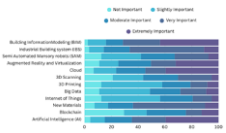
Early detection of unwanted plant issues, such as weeds, is critical in large-scale golf courses to minimize losses and preserve crop health. This study employs image processing along with deep learning methodologies to detect weeds in crops using drone imagery. The project allows detection of the weed by integrating advanced YOLO algorithms, specifically YOLOv8 and YOLOv9, with Gradio's graphical user interface (GUI). The study's findings show that the YOLOv9 algorithm outperforms YOLOv8, providing more accurate and detailed weed detection.The study demonstrates that the weed detection system is accurate and effective for the plantation field, meeting SDG 2 and SDG 13 goals.



OS19-10 Navigating the Future: Skills and Job Market Trends in Malaysia's Construction Sector

Cheah Ye Qun, Salihah Surol, Deprizon Syamsunur (UCSI University, Malaysia)

The Malaysian construction industry is rapidly transforming due to digitalization, new technologies, and changing workforce needs. This study, using a mixed-methods approach, identifies rising demand for digital skills such as BIM, automation, and sustainable construction practices, while traditional skills like manual drafting are declining. It also reveals a gap between current training programmes and industry requirements. Aligned with Sustainable Development Goal 8, the study emphasizes updating curricula, integrating emerging technologies, and strengthening industry–academia collaboration to build a future-ready workforce.



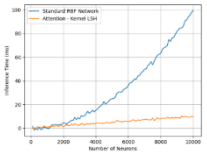
OS20 Pattern Recognition and Control (5) Online Presentation

Chair Fengzhi Dai (Tianjin University of Science and Technology, China)
Co-Chair Yunzhong Song (Henan Polytechnic University, China)

OS20-1 Efficient Approximation of RBF Networks through Attention-Kernel LSH

Qianxiao Pan[1], Fengzhi Dai[1], Yunzhong Song[2]
([1] Tianjin University of Science and Technology, [2] Henan Polytechnic University, China)

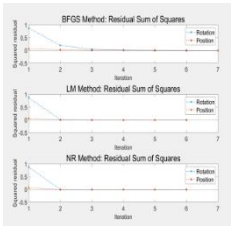
This paper presents the Attention -Kernel LSH, which is a reformulation of radial basis function (RBF) networks that are both theoretically analyzed and experimentally validated. The method employs random Fourier features for kernel approximation and locality-sensitive hashing with attention. On the basis, comparative experiments against the standard RBF networks and approximation baselines are conducted. The results confirm the effectiveness of the proposed design.



OS20-2 Performance Investigation of the Newton-Raphson Algorithm for Inverse Kinematics of a 7-DOF Robotic Manipulator

Hao He, Miao Zhang
(Tianjin University of Science and Technology, China)

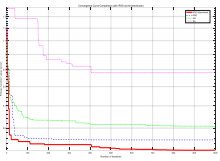
This paper investigates the performance of the Newton-Raphson (NR) algorithm in solving the inverse kinematics of a 7-degree-of-freedom (7-DOF) robotic manipulator. For a comprehensive evaluation, the performance of the NR algorithm is systematically compared with that of the Broyden-Fletcher-Goldfarb-Shanno (BFGS) and Levenberg-Marquardt (LM) algorithms in terms of convergence speed, computational time, end effector pose accuracy, and residual sum of squares. The experimental results highlight the strengths and distinctive characteristics of the NR algorithm in addressing inverse kinematics for high-degree-of-freedom manipulators, offering valuable insights for its practical implementation in 7-DOF robotic systems.



OS20-3 An Improved PSO Algorithm for Solving Robotic Six-DOF Manipulator IK

Kai Sun, Miao Zhang
(Tianjin University of Science and Technology, China)

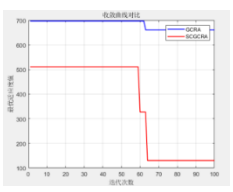
This paper presents an improved particle swarm optimization (IPSO) algorithm designed to address the inverse kinematics problem of a six-axis robotic manipulator. Building upon the Denavit-Hartenberg (DH) model, the proposed method formulates a weighted error function that simultaneously accounts for both positional and orientational deviations. To enhance optimization performance, the IPSO algorithm integrates dynamic velocity constraints, an adaptive inertia weight strategy, time-varying learning factors, and an elite retention mechanism. Experimental results indicate that the IPSO algorithm achieves superior solution accuracy, faster convergence, and enhanced computational efficiency, thereby offering an effective approach for high-precision control in robotic manipulation.



OS20-4 Improved SCGCR Algorithm for 7-DOF Redundant IK

Zhaorui Hao, Miao Zhang
(Tianjin University of Science and Technology, China)

This paper presents a geometric method-based inverse kinematics solver for a 7-degree-of-freedom (7-DOF) robotic manipulator and proposes a redundancy resolution approach integrated with global optimization. A comprehensive objective function is formulated to incorporate end-effector pose accuracy, joint limit constraints, and motion smoothness. Both the Grasshopper Reproduction (GCR) algorithm and the Sine-Cosine Grasshopper Reproduction (SCGCR) algorithm are employed to optimize the solution. Experimental comparison results demonstrate that the improved SCGCR algorithm enhanced global convergence and solution stability, validating the effectiveness of the proposed redundant inverse kinematics optimization method.



OS20-5 A New Cleaning Robot for Organisms Attached to Ocean-going Ships

Haozhe Li, Xinlin Wang, Xinyu Chen, Jiaxu Cheng, Shengzhou Chen, Xingyu Zhao, Youyang Ye, Yang Tang, Ruirui Zhang, Wei Xiao, Fengzhi Dai
(Tianjin University of Science and Technology, China)

A large number of marine organisms adhering to the hulls of ocean-going vessels can cause damage to the ship structure. To address this issue, this paper presents a cleaning robot capable of performing hull maintenance. The robot utilizes permanent magnet adhesion technology to achieve stable movement along the hull and employs high-pressure water jetting technology, widely used in the cleaning field, to perform effective cleaning. Experimental results demonstrate that it significantly reduces a series of problems caused by biofouling on the ship bottom. This provides a stable and reliable solution for the maintenance of ocean-going vessels.

GS Abstracts

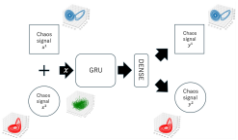
GS1 Machine Learning I (4)

Chair Dengchuan Cai (Nation Yunlin University of Science and Technology, Taiwan)

GS1-1 Development of functional differentiation in recurrent neural networks by mutual information regulation

Yuki Tomoda, Yutaka Yamaguti (Fukuoka Institute of Technology, Japan)

Functional differentiation is the process by which different brain areas become specialized for specific functions. We propose a novel method that induces functionally differentiated structures in recurrent neural networks by minimizing mutual information between neural subgroups. The RNN was trained to separate two superimposed chaotic signals. We found that dynamical modularity emerged earlier and more prominently than anatomical modularity. Functionally differentiated networks exhibited increased resistance to input noise, while responses to neuron damage showed qualitative changes in network dynamics. These findings suggest that mutual information minimization promotes both functional specialization and robustness.



GS1-2 A Deep Learning-Based Shopping Support Method for a Visually Impaired Person

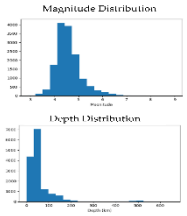
Takaya Yamaguchi, Seiji Ishikawa, Yui Tanjo (Kyushu Institute of Technology, Japan)

Shopping is one of the most important but challenging activities for visually impaired people. This paper proposes a method to help them find convenience stores and their entrances based on deep learning using the images provided from a camera mounted on the chest of a user. This paper focuses on convenience stores because they have variety of goods and nationwide coverage. The proposed method employs a transfer learning model to recognize and detect the position of a convenience store, its signboards and logos, entrances of the store, and obstacles such as vehicles parked in front of the store. Then the method gives directional instructions to the user with a voice-function based on the detected store location to guide them going into a target store. Experimental results under real environments show effectiveness of the proposed method.

GS1-3 Spatial-Temporal Analysis of Earthquakes for Urban Resilience Using Machine Learning

Adessarman Muhammad Sahlan[1], Bart Dewancker[1], Mohammad Albaroudi[2], Raji Alahmad[2], Fahd Moumni[2,3], Ornella Okogo [4]
([1]The University of Kitakyushu, Japan) ([2]Kyushu Institute of Technology, Japan) ([3]MicroOrbiter Inc, Japan)
([4]Engineering School of the City of Paris, EIVP, France)

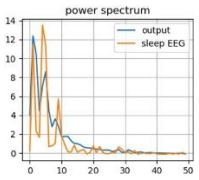
Understanding how and where earthquakes occur helps build safer and more resilient cities. This study analyzed nearly fifty years of earthquake data from Russia's Kamchatka region using machine learning techniques. By applying clustering algorithms, clear seismic hotspots emerged along major fault lines, showing that most earthquakes were shallow and highly threatening to urban areas. The classification models reached 85% accuracy in identifying high-risk zones, highlighting that cluster density and time-based activity are strong predictors of seismic hazards. These findings show that reliable earthquake risk assessments can be achieved using historical records. The results contribute to developing smarter disaster preparedness and safer urban planning in earthquake-prone regions.



GS1-4 Modeling Sleep-Stage Transitions in EEG with a Recurrent Neural Network

Nikolas Acquaviva, Yutaka Yamaguti (Fukuoka Institute of Technology, Japan)

This work aims to train a recurrent neural network to generate signals that replicate the frequency characteristics of sleep EEG. The input to the network represents the current sleep stage of the EEG. For training, EEG data including sleep state transitions is used as the target, and the loss function is defined as the difference between the power spectrum of the sleep EEG and the power spectrum of the output signal. This research may provide important clues to the dynamical mechanisms underlying the rhythmic activity of brain waves during sleep.



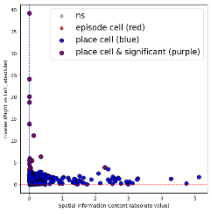
GS2 Machine Learning II (6)

Chair Ju-Jang Lee (KAIST, Korea)

GS2-1 Formation of Place and Episodic Memory in a Recurrent Neural Network

Shin Tamura, Yutaka Yamaguti (Fukuoka Institute of Technology, Japan)

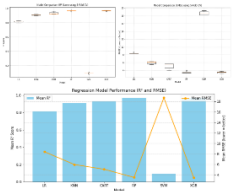
The hippocampus is a key brain region involved in spatial and episodic memory. In this study, we employed a recurrent neural network (RNN) model to reproduce rat experiments that recorded hippocampal activity related to episodic-like memory, aiming to explore its underlying functions and mechanisms. The RNN was trained to perform a spatial alternation task with navigation, selecting actions based not only on current sensory input but also on past behavioral history. Analysis of neural activity revealed place field–like and episode-like neurons, exhibiting spatially specific and memory-dependent firing, respectively.



GS2-2 A Systematic Comparison of Machine Learning Models for State of Charge Estimation in CubeSat Lithium-ion Battery System

Babu Vishwanath Hemath Kumar*, Kitamura Kentaro, Necmi Cihan Orger, Kei Sano
(Kyushu Institute of Technology, Japan)

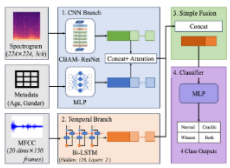
This paper presents a data-driven machine learning approach for SOC estimation of the Engineering Model (EM) battery pack designed for VERTECS mission. A SOC-open circuit voltage curve was derived to characterize the equilibrium voltage-charge relationship, and the long-duration charge-discharge data were collected under nanosatellite operational conditions. A unified experimental framework was implemented to systematically compare multiple algorithms, highlighting the superior performance of Random Forest (R-square = 0.967, RMSE=3.358%) and Extreme Gradient Boosting (R-square = 0.975, RMSE = 3.54%) without hyperparameter tuning. The results demonstrate that machine learning approach enables accurate and adaptable SOC prediction for mission-critical nanosatellite applications.



GS2-3 AuscuFuse: A Robust Parallel Dual-Branch Network for Respiratory Sound Classification

Ryusei Oshima, Tohru Kamiya
(Kyushu Institute of Technology, Japan)

Although respiratory sounds are crucial for non-invasive diagnoses, interpreting them remains subjective. We propose AuscuFuse, a multimodal deep learning model that integrates spectrograms, Mel-Frequency Cepstral Coefficients (MFCCs), and patient metadata. Unlike complex serial architecture, our model employs robust, parallel, dual-branch architecture. We evaluated the model using the ICBHI 2017 dataset and compared a streamlined fusion strategy with variants employed Temporal Gating and Multi-Head classifiers. Contrary to expectations, the simplest parallel fusion achieved the highest ICBHI score (0.816), outperforming the complex variants. These results demonstrate that, for limited data sets, minimizing architectural complexity prevents overfitting and that simple parallel integration provides the most robust performance.



GS2-4 A Method of Objects Remembrance Support Based on Object-Holding Action and Its Recognition

Taisei Shiraki, Seiji Ishikawa, Yui Tanjo (Kyushu Institute of Technology, Japan)

In a human daily life, the stress associated with searching for misplaced items cannot be ignored for his/her mental health. This paper proposes a computer vision system which records the locations of a user's belongings and assists the user in finding lost items indoors, utilizing a wearable camera attached on the user's arm and a camera of an indoor robot. The proposed method consists of the detection of an object-holding action using a deep distance learning model and the recognition of the held object employing a conversational tagging process. These two processes enable the proposed system to acquire personalized object recognition and managing capabilities leading to leveraging a user's everyday action of finding and carrying items. It realizes a personal support system of object location recall. Experimental results show effectiveness of the proposed system.

GS2-5 Development of Outdoor Autonomous Driving Robots- Improvement of the Performance with Autonomous Driving

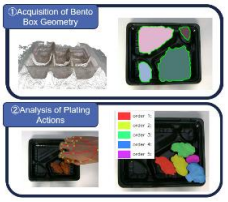
Kako Koyama, Yui Tanjo
(Kyushu Institute of Technology)

This paper proposes a safer system by integrating image-based self-localization techniques; drivable area estimation using RGB images and obstacle detection using depth images. The drivable area estimation method combines graph-based segmentation (GBS), U-net++-based road estimation, and correction using texture feature analysis. For obstacle detection, the ground and obstacle areas are extracted based on the normal information calculated. Safety scores for each direction are calculated from the estimated drivable area and detected obstacle and ground areas, determining the direction of advance toward the safer path. For global self-localization, checkpoint determination is performed through image comparison. Experimental results under outdoor autonomous drive show effectiveness of the proposed system.

GS2-6 Development of a Method of Automated Food Presentation

Ryosei Todo, Yui Tanjo (Kyushu Institute of Technology, Japan)

Existing food presentation robots simply repeat pre-registered paths that have been planned by an operator. This requires skilled operators to set parameters whenever new bento boxes or food items are introduced. This paper proposes a system that automatically extracts food presentation information from the worker's actions during food presentation. To realize this, a depth camera is used to acquire geometric features of a bento box from point-cloud data and extract each partition of the bento box by Knee detection algorithm. Media Pipe Hand and Segment Anything Model are also used to detect the worker's hand who is doing food presentation and segment each food from two successive images. From the segmented results, IOU and Resnet are introduced to match and decide the position of each segmented food in a bento box. The effectiveness of the proposed method is shown experimentally.



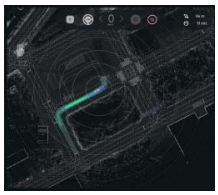
GS3 Autonomous Driving & Aircraft (5)

Chair Saori Iwanaga (Japan Coast Guard Academy, Japan)

GS3-1 Map-Based Navigation and Localization in the Autoware Simulator Using Integrated Open-Street-Map and Point-Cloud-Data

Obada Al Aama[1], Tomoki Taniguchi[1], Davaanyam Jargal[1], Hodaka Inoue[1], Junya Oishi[2], Wataru Mizushina[2], Hakaru Tamukoh[1], Hiroaki Wagatsuma[1]
([1]Kyushu Institute of Technology, Japan, [2]Aisan Technology Co., Ltd., Japan)

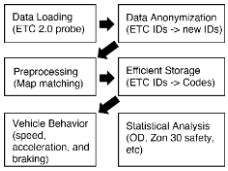
This paper introduces a simulation-oriented framework that leverages the Autoware simulator to assess autonomous vehicle navigation and localization. The approach fuses Open-Street-Map (OSM) data with Point-Cloud-Data (PCD) to generate realistic digital road environments. OSM supplies large-scale roadway structure, while PCD refines geometric detail to create high-fidelity maps. The integrated maps support testing of localization, path planning, and vehicle control under diverse scenarios. The framework enables configurable conditions to assess performance and robustness prior to on-road validation. Through integration of semantic map content with precise 3D sensing data, this approach offers an efficient platform for developing and validating autonomous driving technologies.



GS3-2 A Python-Based Framework for Preprocessing and Vehicle Flow Analysis of ETC2.0 Probe Data for Efficient Data Handling

Rena Kato[1], Souma Noguchi[1], Ahmad Altaweel[1], Haruki Sato[1], Guanyu Su[1], and Hiroaki Wagatsuma[1]
([1]Kyushu Institute of Technology, Japan)

This study presents a preliminary Python-based framework for efficient data processing and analysis of ETC2.0 probe data. The framework enables streamlined handling of large-scale traffic datasets and supports vehicle-level identification with an origin–destination specification, useful for analyzing the mechanisms of traffic jam formation and Zone 30 safety near schools. Designing flexible adaptation to target regions and historical periods, it provides a reproducible and open workflow to facilitate future research on traffic flow and ITS applications.



GS3-3 Development of a Bird-Inspired Flapping-Wing Robot Capable of Bounding Flight

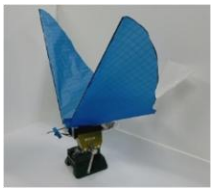
Kanato Matsui, Hiroshi Ohtake (Kyushu Institute of Technology, Japan)

In recent years, unmanned aerial vehicles (UAVs) have been widely used in various fields such as agriculture, disaster response, and meteorological observation. Among various UAV types, flapping-wing UAVs can generate both lift and thrust by flapping their wings like birds, enabling diverse flight modes. However, they suffer from short operating time due to high energy consumption. This study focuses on *bounding flight*, a characteristic flight mode of passerine birds. In bounding flight, birds flap their wings several times to gain upward momentum and then fold them to perform ballistic gliding, thereby achieving higher energy efficiency. In this study, a flapping-wing robot with foldable wings was developed, and its flight performance was evaluated using a six-axis force sensor and flight experiments. The goal is to achieve both sustained flight and bounding flight, which may help overcome one of the main limitations of flapping-wing UAVs.

GS3-4 A Study on Image Processing and Tracking Control of a Small Flapping Flight Robot with a Camera

Shuto Wakugawa, Hiroshi Ohtake (Kyushu Institute of Technology, Japan)

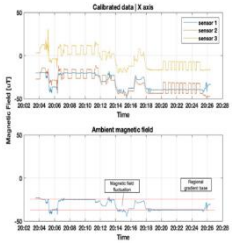
In this study, we developed a system for a small flapping-wing robot, which mimics bird flight and is designed to address noise and safety issues associated with drones, to enable object tracking. The robot is equipped with a camera and was implemented using an external laptop PC and OpenCV to detect the position of a target object in the camera coordinate system. Based on the detected position, control signals are generated in real-time to adjust the left and right flapping angles of the wings. Experiments confirmed that the system can accurately recognize the target's position and modulate wing motion accordingly. Although full tracking flight has not yet been achieved, these results demonstrate the feasibility of vision-based feedback control for flapping-wing robots and indicate potential for future autonomous object-tracking flight. The next step is to implement real-time tracking control during actual flight.



GS3-5 Separation of Stray Magnetic Fields in 3U CubeSats Using Multiple Magnetometers and Blind Source Separation method

Enkhmend Ochirsukh, Kitamura Kentaro, Necmi Cihan Orger (Kyushu Institute of Technology, Japan)

Spacecraft instruments often create unwanted magnetic noise that distorts onboard measurements. To tackle this, the Leopard 3U CubeSat introduces a compact, low-cost solution using multiple COTS magnetometers and Blind Source Separation.
Three magneto-impedance sensors mounted on its panels detect and isolate stray fields, while Independent Component Analysis (ICA) separates ambient and artificial signals. Ground experiments confirm the method's accuracy, offering a promising path toward cleaner, more reliable geomagnetic data for future CubeSat missions.



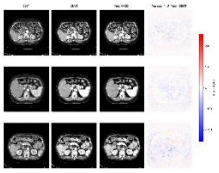
GS4 Image Processing I (8)

Chair Yui Tanjo (Kyushu Institute of Technology, Japan)

GS4-1 Evaluation of Virtual Monoenergetic X-ray Image Conversion Using U-Net

Taiga Tanimoto[1], Naohiro Iwata[1], Yohei Kamikawa[1], Shogo Baba[2], Yukito Yoshida[1]
([1] Oita University Hospital, Japan), ([2] Seinan Gakuin University, Japan)

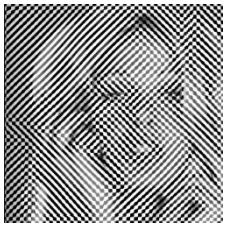
Dual-energy CT (DECT) enhances contrast by generating virtual monoenergetic images (VMI), but its use is limited by high cost and availability. This study developed a deep learning model to reconstruct MonoE 40 keV images from single-energy CT (SECT). Abdominal SECT images from a Philips Spectral CT 7500 were used to train a U-Net with mean squared error (MSE) loss. Image quality was evaluated using PSNR, SSIM, MAE, and CNR, along with residual analysis. The reconstructed images showed superior performance to SECT input, with CNR increasing about 2.5-fold. Residual analysis revealed minimal errors without structural artifacts. These results demonstrate that U-Net with MSE loss enables high-fidelity SECT-to-MonoE conversion and may provide a cost-efficient alternative to DECT for clinical practice.



GS4-2 Generation of Stripe-Patchwork Images by Selecting from Horizontal and Vertical Averages

Jia-Lin Zhang, Toru Hiraoka (University of Nagasaki, Japan)

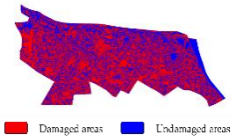
This paper proposes a method to generate stripe-patchwork images composed of more linear stripe-patchwork patterns than stripe-patchwork images of the conventional methods. Additionally, the outside stripe-patchwork patterns of the proposed method are expressed by waviness. The proposed method is executed by repeating two processes: the first process is to smooth photographic images by selecting from horizontal and vertical averages according to the position of photographic images, and the second process is to restore the smoothing images using inverse filter. To verify the effectiveness of the proposed method, experiments were conducted to apply the proposed method to various photographic images.



GS4-3 Edge-Based Image Processing for Urban Change Detection after Earthquakes

Adessarman Muhammad Sahlan[1], Bart Dewancker[1], Mohammad Albaroudi[2], Raji Alahmad[2], Fahd Moumni[2,3], Karim Hasibuan[2]
([1]The University of Kitakyushu, Japan) ([2]Kyushu Institute of Technology, Japan) ([3]MicroOrbiter Inc, Japan)

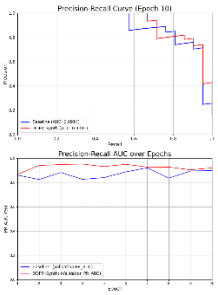
Rapid assessment after earthquakes is vital to save lives and guide recovery efforts. This study presents an image-based approach for detecting urban damage using satellite data. By applying Canny edge detection and K-means clustering, changes in building boundaries and city layouts before and after earthquakes can be clearly identified. The method highlights collapsed structures and debris zones with enhanced visual clarity. Tested on Palu, Indonesia, earthquake imagery, it detected 57.99% of damaged areas with strong accuracy and efficient computation. The results demonstrate the potential of fast, data-driven mapping to support emergency response teams with real-time spatial insights. Beyond immediate relief, this approach can also inform safer urban planning and disaster resilience in the future.



GS4-4 Diffusion-Based Data Augmentation Mitigates Class Imbalance in Circulating Tumor Cell Fluorescence

Kouki Tsuji[1], Kazue Yoneda[23], Tohru Kamiya[1]
([1]Kyusyu Institute of Technology, [2]Hyogo Medical University, [3]University of Occupational and Environmental Health, Japan)

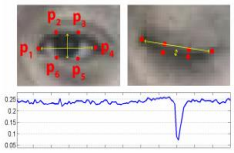
Circulating tumor cells (CTCs) are rare, making fluorescence microscopy screening labor-intensive. Automatic detection systems to help pathologists struggle with severe class imbalance between abundant normal cells and scarce CTCs. To address this challenge, we introduce denoising diffusion probabilistic model (DDPM) augmentation to synthesize realistic CTC images. Adding ~30% DDPM-generated CTCs to InceptionV3 fine-tuning improves validation PR AUC from 0.933 to 0.941 and ROC AUC from 0.978 to 0.985 while maintaining ~95% accuracy, indicating better minority-class ranking without overfitting. These results show that diffusion-based augmentation is a practical strategy for robust, computer-assisted CTC screening under extreme imbalance.



GS4-5 Estimating Driver Drowsiness Using Millimeter-Wave Radar

Yoshikazu Hirayama, Kazuya Matsuo (Kyushu Institute of Technology, Japan)

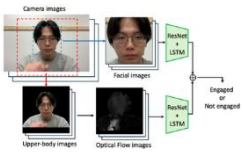
This study proposes a non-contact drowsiness estimation method combining camera-based blink detection and millimeter-wave radar-based heartbeat measurement. While conventional camera methods suffer from low accuracy in dark or occluded environments, the integration of radar sensing enables stable monitoring under various conditions. The system calculates the Eye Aspect Ratio (EAR) from facial images to detect blinks and acquires heartbeat signals using a millimeter-wave radar to extract physiological features. These multimodal data are integrated to estimate drowsiness levels. The proposed system has been implemented and is currently under experimental evaluation.



GS4-6 Engagement Estimation in E-Learning Using Facial and Upper-Body Videos

Shun Takeshita, Noriko Takemura (Kyushu Institute of Technology, Japan)

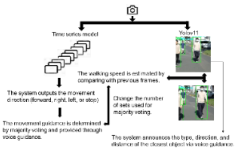
Online learning using video materials and web conferencing is widespread. However, indicators such as concentration and alertness are insufficient to capture learners' active engagement in the learning task. This study aims to estimate engagement using data collected during actual e-learning sessions. We developed a model that processes sequences of facial-region images and upper-body optical flow images, where features extracted by a ResNet and an LSTM are concatenated to estimate engagement. Evaluation experiments were conducted to compare estimation performance under different input configurations. The findings suggest that visual cues can contribute to engagement estimation and imply that incorporating multiple levels of bodily information may lead to more robust assessment.



GS4-7 Development of a Direction Indicating Navigation Method for a Visually Impaired Person

Kenyu Takahashi, Yui Tanjo (Kyushu Institute of Technology, Japan)

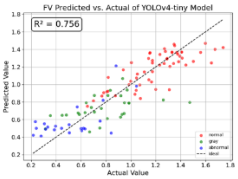
This paper proposes a wearable navigation method that provides short-term instructions on moving direction, *i.e.* forward, left, right, or stop, to a visually impaired person using a chest-mounted camera. The proposed method employs YOLOv11 to detect a pedestrian, Resnet to extract features of input images, and TimesNet to predict his/her moving direction. To stabilize the predicted direction, two rules are introduced, i.e., (i) a fixed majority-voting rule, and (ii) a speed-adaptive majority-voting rule based on the distance trajectory between the user and his/her nearest pedestrian. SORT tracking is also included in the method to prevent identity change when computing the nearest-pedestrian distance. The proposed method was evaluated by offline scenes and actual scenes under a real environment, and the results showed effectiveness of the method.



GS4-8 Two-Stage YOLOv4-Tiny for Vascular Stenosis Detection Using AVF Shunt Sound Data

Lucky Nindya Palupi, Hiroki Tamura
(University of Miyazaki, Japan)

This study presents a two-stage YOLOv4-tiny framework for identifying vascular stenosis in dialysis patients using arteriovenous fistula (AVF) shunt sound data. Shunt sounds were recorded with a digital stethoscope, stored as WAV files, and converted into spectrogram images for analysis. In the first stage, YOLOv4-tiny classified the spectrograms into normal and non-normal categories. In the second stage, the non-normal samples were further classified into gray and abnormal conditions. The first-stage model achieved an accuracy of 70.75%, while the three-class classification reached 67.92%. To evaluate the model's relevance to hemodynamic assessment, Support Vector Machine (SVM) regression was applied to estimate flow volume (FV), pulsatility index (PI), and resistance index (RI) using YOLO confidence scores. The resulting R^2 values for FV, PI, and RI were 0.756, 0.486, and 0.749, respectively. These findings indicate that the two-stage YOLOv4-tiny approach provides a promising non-invasive method for detecting vascular stenosis from AVF shunt sound data.



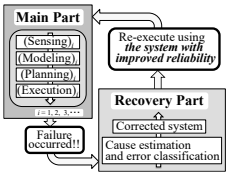
GS5 Robotics & AI (3)

Chair Akira Nakamura (Saitama Institute of Technology, Japan)

GS5-1 Selection of Error Recovery Path Using Optimization of Evaluation Functions

Akira Nakamura[*1] and Kensuke Harada[*2]
([*1] Saitama Institute of Technology, [*2] Osaka University, Japan)

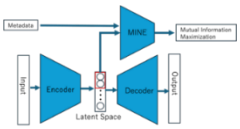
In recent years, intelligent robots have been applied not only in industry but also in various fields. In particular, robots that perform detailed tasks with precision, such as humanoid robots and medical robots, need to work safely and securely. Therefore, adaptability to errors and failures is becoming important. To address this issue, it is necessary to generalize and systematize error recovery techniques, and we have proposed a method that covers both forward recovery and backward recovery. Forward recovery is suitable for minor changes, while backward recovery is suitable for major failures. In this study, we present a new selection method to determine the optimal recovery path using evaluation functions.



GS5-2 Learning Interpretable Latent Representations from Single-Cell RNA-seq with VAE and Mutual Information

Tomohito Yamamura, Yutaka Yamaguti (Fukuoka Institute of Technology, Japan)

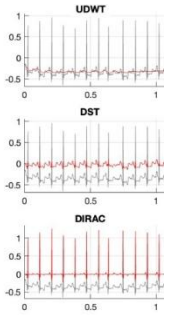
This paper applies to a Variational Autoencoder (VAE) constrained by mutual information to analyze complex biological data. The VAE efficiently compresses high-dimensional gene expression data into a lower-dimensional latent space, but its latent variables are often difficult to interpret biologically. To address this issue, we propose a method that introduces a mutual information constraint into the VAE framework. This allows the model to learn representations that are more strongly associated with metadata accompanying the scRNA-seq data, such as temporal or experimental information. The proposed approach aims to improve the interpretability of latent features and contribute to a deeper understanding of underlying structures and dynamics from single-cell gene expression data.



GS5-3 A Preliminary Study on Morphological Component Analysis for Arrhythmia Detection in ECG Signals from the MIT-BIH Arrhythmia Database

Faustine Faccin[1,3,4], Diunuge Buddhika Wijesinghe[2], Rena Kato[2], Kosei Shibata[2], Shabbir Mahmood[2], Hodaka Inoue[1], Pauline Guyot[4], Laurent Bougrain[3,5] and Hiroaki Wagatsuma[2] ([1]Université de Lorraine, CNRS, CRAN, France, [2]Kyushu Institute of Technology, Japan, [3]Université de Lorraine, CNRS, LORIA, France, [4]NOVIGA, France, [5]Sorbonne Université, Institut du Cerveau – Paris Brain Institute (ICM), France)

This study presents a preliminary explainable arrhythmia classification method using Morphological Component Analysis (MCA) and index thresholding applied to ECG signals. Cardiovascular disease remains a major global health issue, and while automated ECG analysis has advanced, data-driven AI methods often lack interpretability. We address this point by focusing on binary classification between normal beats and premature ventricular contractions using data from the MIT-BIH Arrhythmia Database. MCA decomposes ECG signals into morphological components through redundant transforms with UDWT, DST, and Dirac dictionaries. The Dirac component captures abrupt changes corresponding to the initiation of ECG cycles, while irregularities appear mainly in the UDWT component. Based on these features, an integrative classification method is proposed.



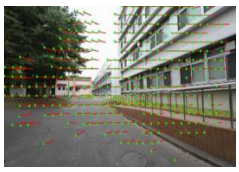
GS6 Applications I (6)

Chair Chung-Wen HUNG (Nation Yunlin University of Science and Technology, Taiwan)

GS6-1 A Method of Recognizing Health Condition Based on Walking Patterns

Kanato Tajika, Seiji Ishikawa, Yui Tanjo (Kyushu Institute of Technology, Japan)

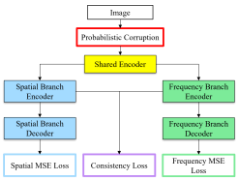
The percentage of the people who feel unhealthy tends to increase with age, highlighting the importance of early detection of physical abnormalities. This paper proposes a method of detecting changes in walking patterns that may indicate early signs of physical abnormalities using a camera attached to a human. This method records two elements, i.e., a walking path and a walking motion, and analyzes their normality by comparing it with a normal walking pattern. Change in either the walking path or the walking motion compared to the baseline is recognized as the change in walking pattern. This method is expected to enable the detection of changes in walking patterns, facilitating the early detection of changes in health status. Experimental results show the effectiveness of the proposed method.



GS6-2 Spatio-Frequency Consistency Learning for Self-Supervised Visual Representations

Zhongxi Zhang, Cunwei Lu (Fukuoka Institute of Technology, Japan)

This paper proposes a “Spatio-Frequency Consistency” learning framework to enrich self-supervised learning by integrating complementary information from both spatial and frequency domains. Our method features a dual-branch structure with a shared encoder. One branch reconstructs randomly masked spatial patches, while the other reconstructs masked discrete cosine transform coefficients. Furthermore, we introduce a consistency loss to align the feature representations from both branches. This integrated system, which leverages complementary information, is demonstrated to be highly effective and achieves superior performance compared to single-domain approaches on the ImageNet-1K dataset.



GS6-3 Experimental Comparison of Leather Rotational Torque in Vertical and Horizontal Hide-Tanning Techniques for Traditional Leather Processing in Mongolia

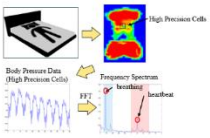
Renchinvanjil Yadam, and Dondogjamts Batbaatar
([1]Mongolian University of Science and Technology, Mongolia)

This study experimentally examines the rotational torque of leather used in traditional Mongolian hide tanning. Building on previous research on leather mechanics, a torque measurement device was developed to compare vertical and horizontal setups under controlled conditions. Results show significant differences in torque requirements between orientations, affecting tanning efficiency and energy demand. These findings provide key data for improving ergonomic, energy-efficient hide-tanning equipment for rural use and form a foundation for integrating experimental validation into future design and modeling.

GS6-4 Method for determining the optimal pressure measurement site for heart rate monitoring using a flexible sheet-type tactile sensor

Kyota Suzuki, Kazuya Matsuo (Kyushu Institute of Technology, Japan)

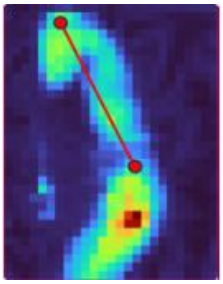
In recent years, severe labor shortages in nursing care have increased the need for labor-saving solutions. We have developed a system using flexible sheet-type tactile sensors on beds to non-invasively and continuously monitor care recipients' health conditions; however, heart rate measurement accuracy remains challenging. This study proposes a machine learning model that classifies sensor cells into three categories (successful, uncertain, unsuccessful) for heart rate measurement, using time- and frequency-domain features and local pressure distributions from body pressure waveforms.



GS6-5 Sleep Posture and Heartbeat Estimation Using a Flexible Tactile Sensor Sheet

Hibiki Shimono Kazuya Matsuo (Kyushu Institute of Technology, Japan)

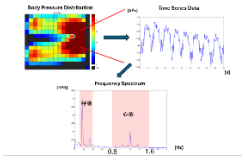
Sleep monitoring, including posture and vital sign measurement, is essential for evaluating sleep quality and health. Conventional methods require many sensors attached to the body, which are not suitable for daily use. We propose a non-invasive monitoring method using a flexible tactile sensor sheet placed on a bed. The sensor can simultaneously measure posture and biological signals such as heartbeat and respiration. A multitask model combining keypoint detection and classification is used to estimate posture and identify optimal regions for heartbeat measurement. Currently, we are generating simulation data using the SOFA Framework to analyze sensor performance. The final goal of this study is to clarify the relationship between sensor resolution and estimation accuracy for designing an optimal sensor configuration.



GS6-6 Heart Rate Measurement Using a Flexible Sheet-Type Tactile Sensor

Kamui Nagano Kazuya Matsuo (Kyushu Institute of Technology, Japan)

In recent years, nursing care facilities have faced severe labor shortages, increasing the need for technologies that reduce caregiver burden. This study aims to develop a system that measures heart rate simply by having a person sit on a chair equipped with flexible sheet-type tactile sensors installed on the seat and backrest. The system estimates heart rate from pressure fluctuations produced by subtle body movements associated with cardiac activity. By enabling non-contact and automatic monitoring, this approach can support continuous health observation in nursing environments.
Implementing this system in care facilities is expected to significantly reduce caregivers' workload while improving monitoring efficiency.



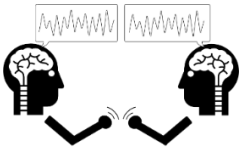
GS7 Applications II (5)

Chair Hiroaki Wagatsuma (Kyushu Institute of Technology, Japan)

GS7-1 Dynamics of Inter-Brain Phase Synchronization During the Emergence of Coordinated Behavior

Rena Kato[1], Akio Wakata[1], Kosei Shibata[1], Shabbir Mahmood[1], Diunuge Buddhika Wijesinghe[1], Yide Yang[1], Masayuki Fujiwara[2], Laurent Bougrain[3], Kiyohisa Natsume[1], and Hiroaki Wagatsuma[1]
([1]Kyushu Institute of Technology, Japan, [2]Komatsu University, Japan, [3]University of Lorraine, France)

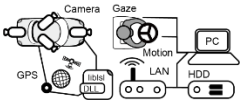
Understanding how neural synchronization emerges during coupled movements is crucial for elucidating interpersonal coordination dynamics. We investigate inter-brain phase synchronization as two individuals coordinate rhythmic arm movements across game phases. Simultaneous electroencephalographic (EEG) signals were recorded from paired participants performing a rock–paper–scissors task initiated by a synchronized arm swing. Focusing on transitions from asynchronous to synchronous states, we are developing temporal analysis methods to characterize fluctuations in inter-brain connectivity underlying coordinated behavior. This framework enables quantitative assessment of neural coupling and may inform adaptive human–robot coordination systems.



GS7-2 Extending LabStreamingLayer for Synchronized Monitoring of Expert Bus Drivers: GPS, Camera, Motion, and Eye-Tracking Integration for Risk-Point Analysis

Shabbir Mahmood, Tomoki Taniguchi, Hodaka Inoue, Rena Kato, Kosei Shibata, Obada Al Aama, Davaanyam Jargal, Diunuge Buddhika Wijesinghe, Hakaru Tamukoh and Hiroaki Wagatsuma
(Kyushu Institute of Technology, Japan)

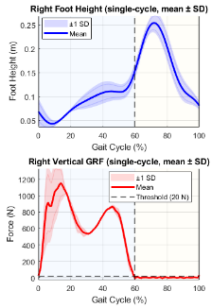
LabStreamingLayer (LSL), originally developed for real-time acquisition of biosignals such as EEG, provides a flexible framework for synchronized data streaming across devices, including gaze and behavioral motion tracking. We extended its generality to develop a system for monitoring expert bus drivers' decision-making by synchronizing GPS (vehicle location), external cameras (other vehicles), driver motion sensors (action timing), and eye-tracking data (attention). This system enables effective risk-point detection, visualization of drivers' decision processes, and mapping detected risk points onto geographic data.



GS7-3 Dynamics of Landing and Push-Off in Running for Implications on Prosthetic Limb Design

Choisuren Purevdorj[1], Abhinav Sharma[2], Kosei Shibata[1], Tomoki Taniguchi[1], Shintaro Kasai[1], Rena Kato[1], Yiqian Ge[1] and Hiroaki Wagatsuma[1]
([1]Kyushu Institute of Technology, Japan; [2]Indian Institute of Technology Kanpur, India)

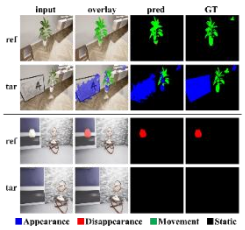
The analysis of the muscular-mechanical system during ground contact in walking and running is inevitable in biomechanics. In particular, the generation of force vectors that absorb impact at landing and convert it into forward propulsion is essential for normal locomotion, especially during running. When the heel strikes the ground, the center of mass shifts toward the forefoot, followed by a push-off that lifts the foot from the ground. This process produces two peaks in the vertical ground reaction force: the initial impact and the subsequent push-off. We hypothesize that energy is not fully conserved during push-off, as some of the impact energy dissipates as heat, resulting in a lower second peak. We conducted experiments using a treadmill capable of switching left and right limb motions. Our study aims to quantify the dynamics of landing and push-off, providing insights that can inform the design of prosthetic limbs with automatic muscle-force adjustment.



GS7-4 3D Point Cloud-based Change Detection from Image Pairs Based on Cross-Attention Networks

Kazuma Morinaga, Yui Tanjo (Kyushu Institute of Technology, Japan)

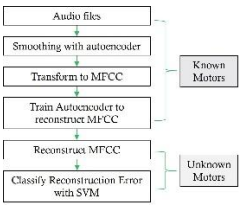
This paper proposes a method for detecting scene change patterns from a pair of images of the same location captured at different times, and classifying the change patterns into 4 types, *i.e.*, appearance, disappearance, movement and no change. To handle the difference in camera viewpoints between captured images, the proposed method reconstructs 3D point clouds from the input images and aligns them in a 3D space. Cross-attention networks are applied to the 3D point clouds to detect changed regions and sort them to the 4-types of change patterns. The proposed method is expected to support daily activities of visually impaired people. It may have further application to assistive robots, or even to enhance safety management in care facilities and medical environments.



GS7-5 Analysis of Generalization Pertinency in Autoencoder-Based Anomaly Detection for Industrial Motor Sounds Using SVM

Jamil Md Shafayet, Praveen Nuwantha Gunaratne, Hiroki Tamura
(University of Miyazaki, Japan)

Anomaly detection in industrial instruments is crucial for maintaining facility performance. Sound classification offers important attributes for automation, including information about machine type, operational state, and speed. Therefore, automatic detection of anomalous machines can reduce time, labor, cost, and human error. The core challenge addressed in this study is achieving generalization in classifying anomalous motors based on their sound. Autoencoders are widely used for anomaly detection; in this work, an autoencoder was trained on normal and abnormal motor sounds, transformed into Mel Frequency Cepstral Coefficients (MFCCs), to generate reconstruction errors. Another autoencoder was used beforehand to reduce noise in the raw audio data. The resulting reconstruction-error sequences were then classified using a Support Vector Machine (SVM) on MFCC data that was unseen in the previous stage. This approach enables generalized anomaly detection for previously unknown motor types. Various combinations of data folds were analyzed to evaluate the model's limitations.

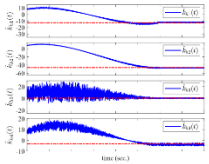


GS8 Aircraft (3) No Presentation
Chair -

GS8-1 Human Behavior Learning for A Class of Norm-Bounded Uncertain Linear HiTL Systems via Adaptive Inverse Optimal Guaranteed Cost Control

Wen-Hua Li (Beihang University, China), Huai-Ning Wu (Beihang University, Hangzhou International Innovation Institute of Beihang University, China)

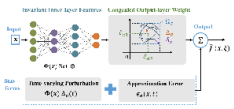
This paper presents an adaptive inverse optimal guaranteed cost control (IOGCC) approach for norm-bounded uncertain linear human-in-the-loop (HiTL) systems. The method addresses the challenge of learning human behavior modeled by an optimal guaranteed cost control (GCC). The matrix weighting the quadratic cost function is initially unknown. Our approach consists of two steps: first, an adaptive law estimates the control gain matrix from system state data in real time, with a leakage term to reduce model uncertainty effects. Then, using the learned control gain matrix, we solve a linear matrix inequality (LMI) optimization to identify the matrix that weights the human cost function. The effectiveness of the method is validated through a lane-keeping simulation.



GS8-2 Congealed Deep Neural Network-based System Identification for Morphing Aircraft

Hao-Chi Che (Beihang University, China), Huai-Ning Wu (Beihang University, China; Hangzhou International Innovation Institute, Beihang University, China)

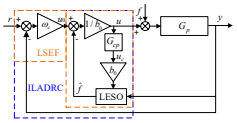
This paper proposes a new deep neural network (DNN) architecture called the congealed DNN for system identification of morphing aircraft (MA). The developed DNN consists of two parts: the invariant features of the inner layers and the time-varying weights of the output layer. For the inner invariant features, a novel meta-learning with adversarial optimization framework is developed to derive a common representation function shared by different deformation conditions. For the time-varying weights, we consider them to be composed of congealed weights and time-varying perturbations. The congealed weights are estimated using standard adaptive techniques, while a sliding mode-like function is employed to attenuate time-varying disturbance terms. The experimental results indicate that the proposed method demonstrates more precise and faster adaptation capabilities to the MA system compared to other methods.



GS8-3 Research on Active Disturbance Rejection Control for Load Coordination System of Supercritical Thermal Power Units

Li-Rong Zhang (Beihang University, China), Hai Zhang (Beihang University, China)

Enhance the flexibility and adaptability of peak shaving and frequency regulation for thermal power units is crucial for the stable operation of new energy generation and power grids. This paper proposes an Improved Linear Active Disturbance Rejection Control (ILADRC) method for the load coordination system of thermal power units to improve stability and flexibility under multi-condition peak shaving modes. Bandwidth parameterization is employed to reduce the complexity of ILADRC parameter tuning. A feedforward compensation mechanism is introduced to overcome the impact of large delays on the boiler side on dynamic performance. Combined with an extended state observer (ESO) to estimate and compensate for internal and external total disturbances in real-time. Compared with PID control, ILADRC demonstrates certain advantages in dynamic response speed, disturbance rejection capability, and cross-working-condition adaptability, significantly enhancing the system's applicability across multiple operating conditions and robustness under varying conditions.

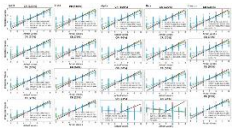


Poster Abstract (1)
Chair Takao Ito (Hiroshima University, Japan)

POS1 EEG-Based Prediction of Concentration Rank During Zentangle Practice Using Frequency-Specific Features and Machine Learning

Ting-Chien Chuang, Muhammad Usman, Yao-Tien Chen (Ming Chi University of Technology, Taiwan)
Chun-Ling Lin*(National Taipei University of Technology, Taiwan)

Predicted and actual concentration rank (CR) across five EEG frequency bands using RF, SVR, and KNNat four feature selection levels (100%, 70%, 50%, 25%)



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Notation of session name

PS: Plenary Session, OS: Organized Session, GS: General Session, POS: Poster

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Diunuge Buddhika Wijesinghe	GS5-3	46/101
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Dobrila Lopez	OS4-8	43/57
Dominic B. Solpico	OS5-11	31/61
Dondogjamts Batbaatar	GS6-3	35/102
Dyah Lestari	OS17-1	39/86
[E]		
Eason Yan Yi Chen	OS4-1	42/54
Eii Tze Xian	OS19-2	28/89
Eiji Hayashi	OS1-1	21/49
	OS1-2	21/49
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Eko Wahyu Abryandoko	OS15-1	39/81
Elifnaz Bilgili	OS5-16	31/62
En-guang Yang	OS13-5	-/79
Enkhmend Ochirsukh	GS3-5	34/98
Eslem Kıvrak	OS5-15	31/62
Evelyn Levina Diva	OS4-10	43/57

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Farouk Hesham Farouk Elkholy OS19-5 29/90
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Giri Wahyu Wiriasto OS17-1 39/86
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Hakaru Tamukoh OS7-2 44/65
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I-Hsien Liu	OS2-1	25/52
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	OS3-4	26/54
Ichiro Tanaka	OS17-2	39/86
Ilham Priadythama	OS15-4	39/82
Inniyaka R. Irmiya	OS5-11	31/61
Iori Iwata	OS9-1	47/68
	OS9-2	47/69
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Irmiya R. Inniyaka	OS5-14	31/61
[J]		
Ja Sin Yon Pang	OS1-10	22/51
Jamil Md Shafayet	GS7-5	35/104
Jia Ming Hsiao	OS10-4	24/71
Jia-Lin Zhang	GS4-2	27/98
Jia-Ming Xu	OS11-2	23/73
Jia-Wen He	OS11-2	23/73
Jiaming Zhang	OS13-1	-/78
Jian-Jhih Lina	OS11-1	23/73
Jiaxu Cheng	OS20-5	28/93
Jin-Chen Zhuo	OS11-5	23/74
Jing-Ru Chen	OS11-5	23/74
Jiro Suzuki	OS17-2	39/86
Joko Slamet Saputro	OS15-2	39/81
Jr-Hung Guo	OS10-3	24/71
Jumpei Ono	OS16-2	32/82
	OS16-7	33/84
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	OS16-10	33/85
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Jun Nakamura	OS16-12	33/86
Jun-Lin Wu	OS11-3	23/73
Jung-Shain Li	OS2-1	25/52
Jung-Shian Li	OS3-4	26/54
Junya Oishi	GS3-1	34/97
[K]		
Kai Sun	OS20-3	28/92
Kairi Manabe	OS7-8	44/67
Kako Koyama	GS2-5	32/96
Kamui Nagano	GS6-6	35/103
Kanato Matsui	GS3-3	34/97
Kanato Tajika	GS6-1	34/101
Kaoru Ohe	OS12-1	37/75
	OS12-2	37/75
	OS12-3	37/75
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Karimuddin Karim Hasibuan	GS4-3	27/99
Kasthuri Subaramaniam	OS4-1	42/54
	OS4-2	42/55
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Katsuaki Suzuki	OS5-6	30/59
	OS5-7	30/59
	OS5-8	31/60
Kazue Yoneda	GS4-4	27/99
Kazuhide Sugimoto	OS12-3	37/75
Kazuhiro Eguchi	OS5-10	31/60
	OS5-13	31/61
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Kazuki Nakayama	OS5-6	30/59
Kazuma Morinaga	GS7-4	35/104
Kazuma Sakamoto	OS9-1	47/68
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Kazunori Yamaguchi	OS12-9	38/77	Kouki Tsuji	GS4-4	27/99
Kazuo Ishii	OS5-1	30/58	Koushi Nishioka	OS9-7	47/70
	OS5-6	30/59	Kouya Taitou	OS5-4	30/59
	OS5-7	30/59	Kuan-Ting Lee	OS2-1	25/52
	OS5-8	31/60		OS2-2	25/52
	OS5-10	31/60		OS2-3	25/52
	OS5-11	31/61	Kuo-Da Chou	OS10-5	24/71
	OS5-12	31/61		OS10-6	24/72
	OS5-13	31/61	Kuo-Hsien Hsia	OS10-1	23/70
	OS5-14	31/61		OS10-2	23/71
Kazuya Matsuo	GS4-5	27/99		OS10-3	24/71
	GS6-4	35/102		OS10-8	24/72
	GS6-5	35/102	Kyota Suzuki	GS6-4	35/102
	GS6-6	35/103	Kyoya Takiguchi	OS9-5	47/69
Kei Sano	GS2-2	32/95		OS9-6	47/70
Kei Wakabayashi	OS7-8	44/67	[L]		
Keitaro Ito	OS7-8	44/67	LI-MIN	OS3-2	25/53
	OS7-9	45/67	Laurent Bougrain	GS5-3	46/101
Kenji Aoki	OS12-1	37/75		GS7-1	35/103
	OS12-2	37/75	Lee Shi Wei	OS19-7	40/90
	OS12-3	37/75	Leon Furuya	OS7-8	44/67
	OS12-6	37/76	Leona Kimura	OS12-3	37/75
Kenji Kimura	OS5-6	30/59	Li-Hao Chena	OS11-1	23/73
	OS5-7	30/59	Li-Min Chuang	OS3-1	25/53
	OS5-8	31/60		OS3-2	25/53
Kensuke Harada	GS5-1	46/100	Li-Rong Zhang	GS8-3	-/105
Kento Ohnaka	OS12-8	38/77	Lixia Yan	OS13-4	-/79
Kenyu Takahashi	GS4-7	27/100	Lobes Herdima	OS15-1	39/81
Kitamura Kentaro	GS2-2	32/95	Lucky Nindya Palupi	GS4-8	27/100
	GS3-5	34/98	Lyu SiQian	OS18-2	40/87
Kiyohisa Natsume	GS7-1	35/103	[M]		
Koh Yong Chuan	OS19-6	40/90	M. Aziz Muslim	OS18-3	40/88
Koki Nishiyama	OS16-3	32/83	M.A Munjer	OS1-2	21/49
Kosei Shibata	GS5-3	46/101		OS1-3	21/49
	GS7-1	35/103		OS1-4	21/50

Maisarah Binti Lutfi	OS17-3	39/87
Makoto Sakamoto	OS12-1	37/75
	OS12-2	37/75
	OS12-3	37/75
	OS12-4	37/76
	OS12-5	37/76
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Masahiro Iwahashi	OS18-4	40/88
Masaya Nakahara	OS9-5	47/69
	OS9-6	47/70
Masayuki Fujiwara	OS9-7	47/70
	GS7-1	35/103
Miao Zhang	OS20-2	28/92
	OS20-3	28/92
	OS20-4	28/92
Mimi Natasha Jamal	OS6-7	36/64
Ming- Syuan Wu	OS2-4	25/53
Misao Ichio	OS16-8	33/84
Mohammad Albaroudi	OS5-1	30/58
	OS5-9	31/60
	OS5-11	31/61
	OS5-15	31/62
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Mohd Azwan Ramlan	OS17-3	39/87
Mohd Hatta Mohamed Ariff	OS19-1	28/88
Mohd Heikal Husin	OS15-3	39/81
Muhamad Syamsu Iqbal	OS17-1	39/86
Muhammad Adib Syahmi Muhammad	OS6-6	36/64
Muhammad Amirul Aiman Asri	OS18-3	40/88
	OS18-4	40/88
Muhammad Azizi Azizan	OS6-1	36/62
	OS6-2	36/63
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Muhammad Hassan Tanveer	OS6-1	36/62
	OS6-2	36/63
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Muhammad Usman	POS	25/106
Munehiro Kimura	OS18-4	40/88
Mustafa Erdoğan	OS5-16	31/62
[N]		
Naime Sezginer	OS5-16	31/62
Naohiro Iwata	GS4-1	27/98
Naoki Yamaguchi	OS7-1	44/65
	OS7-2	44/65
Naoto Ishizuka	OS7-8	44/67
	OS7-9	45/67
Naoto Shirahama	OS5-5	30/59
Nazrul Naim Md Zain	OS6-5	36/64
Necmi Cihan Orger	GS2-2	32/95
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Nik Nur Zuliyana Binti Mohd Rajdi	OS17-3	39/87
Nikolas Acquaviva	GS1-4	37/95
Nitin Kumar Singh	OS7-4	44/66
Nitish Menon	OS18-1	40/87
Nobuya Takahashi	OS8-2	46/68
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Noor Farizah Ibrahim	OS15-3	39/81
Noor Idayu	OS19-8	40/91
	OS19-9	41/91
Nor Aziyatul Izni	OS19-1	28/88
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Nor Shamira Sabri	OS15-3	39/81

Noriko Takemura	GS4-6	27/99
Norrima Mokhtar	OS15-1	39/81
	OS15-2	39/81
	OS15-4	39/82
	OS17-1	39/86
	OS18-2	40/87
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Norul Ashikin Norzain	OS17-3	39/87
Nurhaffizah Hassan	OS19-1	28/88
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[O]		
Obada Al Aama	GS3-1	34/97
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Oras Baker	OS4-1	42/54
	OS4-2	42/55
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	OS4-7	43/56
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Orhun Simav	OS5-15	31/62
Ornella Akogo	GS1-3	37/94
Oğuzhan Çalışkan	OS5-16	31/62
[P]		
Pan Wei Zheng	OS1-3	21/49
Pauline Guyot	GS5-3	46/101
Peng Lean Chong	OS18-2	40/87
Praveen Nuwantha Gunaratne	GS7-5	35/104
Prem Gamolped	OS1-9	22/51
	OS1-10	22/51
Pringgo Widyo Laksono	OS15-1	39/81
	OS15-2	39/81
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	OS18-3	40/88
	OS18-4	40/88
Purevdorj Choisuren	GS7-3	35/104
[Q]		
Qianxiao Pan	OS20-1	28/92
Qingqi Zhang	OS13-4	-/79
Qunpo Liu	OS13-5	-/79
[R]		
Raenu Kolandaisamy	OS4-1	42/54
Raji Alahmad	OS5-1	30/58
	OS5-9	31/60
	OS5-10	31/60
	OS5-11	31/61
	OS5-15	31/62
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Raza Ali	OS18-3	40/88
Ren C. Luo	PS2	30/48
Ren Matsuoka	OS7-9	45/67
Rena Kato	GS3-2	34/97
	GS5-3	46/101
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	GS7-2	35/103
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Renchinvanjil Yadam	GS6-3	35/102
Reo Ishii	OS9-2	47/69
Riku Kaiba	OS9-2	47/69
Riku Takahashi	OS16-6	33/84
Rodney Tan Hean Gay	OS19-4	28/89
Rohan Saini	OS7-3	44/65
Ruirui Zhang	OS20-5	28/93
Rut Yatigul	OS1-2	21/49
	OS1-7	22/50
Ryo Miyakawa	OS5-12	31/61
	OS5-13	31/61
Ryoga Maruno	OS7-2	44/65
Ryosei Todo	GS2-6	32/96

Ryosuke Harakawa	OS18-4	40/88
Ryotaro Teranishi	OS9-6	47/70
Ryusei Noguchi	OS9-6	47/70
Ryusei Oshima	GS2-3	32/95
Ryuta Matsuda	OS1-6	22/50
Ryuta Okabe	OS9-4	47/69
Ryuusuke Kawamura	OS12-1	37/75
	OS12-2	37/75
	OS12-3	37/75
	OS12-9	38/77
[S]		
Sakura Kawai	OS16-5	33/83
Saleh Abdulalem Ali Mohammed	OS4-6	42/56
Salihah	OS19-10	41/91
Samar Ghazal Mohammed Abdullah	OS4-10	43/57
Sanetake Nagayoshi	OS16-12	33/86
Saori Iwanaga	PS3	21/48
Sarah ‘Atifah Saruchi	OS19-1	28/88
	OS19-2	28/89
	OS19-3	28/89
Satoshi Ikeda	OS12-1	37/75
	OS12-2	37/75
	OS12-3	37/75
	OS12-4	37/76
	OS12-5	37/76
Satoshi Yamaguchi	OS1-5	22/50
Seiji Ishikaw	GS6-1	34/101
Seiji Ishikawa	PS2	30/48
	GS1-2	36/94
	GS2-4	32/96
Sellappan Palaniapan	OS4-2	42/55
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Shabbir Mahmood	GS5-3	46/101
	GS7-1	35/103
	GS7-2	35/103
Shamshul Bahar Yaakob	OS6-1	36/62
	OS6-2	36/63
	OS6-3	36/63
Shao-I Hsiao	OS10-4	24/71
Sharifah Munawwarah	OS19-1	28/88
Shayla Islam	OS4-1	42/54
Sheikh Muhammad Hafiz Fahami	OS19-2	28/89
Shengzhou Chen	OS20-5	28/93
Shiji Song	OS13-4	-/79
Shin Tamura	GS2-1	32/95
Shinsuke Yasukawa	OS5-9	31/60
Shintaro Kasai	GS7-3	35/104
Shin’ichiro Aoki	OS16-8	33/84
Shizuki Nokura	OS12-1	37/75
	OS12-2	37/75
	OS12-3	37/75
Shogo Baba	GS4-1	27/98
Shu-Hua Huang	OS3-3	25/54
Shun Takeshita	GS4-6	27/99
Shunta Kimura	OS18-4	40/88
Shuto Wakugawa	GS3-4	34/98
Siah Jing Yi	OS19-3	28/89
Siti Rahyla Rahmat	OS15-3	39/81
Siti Sendari	OS17-1	39/86
	OS18-3	40/88
	OS18-4	40/88
Sota Goto	OS12-8	38/77
Souma Noguchi	GS3-2	34/97
Sultan	OS19-8	40/91
Sumiya Fujita	OS19-3	28/89
Suzuka Tachibana	OS7-9	45/67
[T]		
Tabassam	OS19-8	40/91
	OS19-9	41/91

Tabiga Zhumanazarova	OS4-9	43/57
Tabindah	OS19-8	40/91
Taha Abdulsalam Almulaisi	OS6-2	36/63
	OS6-3	36/63
Taha Almulaisi	OS6-1	36/62
Taiga Tanimoto	GS4-1	27/98
Taisei Shiraki	GS2-4	32/96
Taiyo Hidaka	OS12-6	37/76
Takao Ito	OS12-4	37/76
	OS12-5	37/76
	OS18-3	40/88
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Takashi Akamatsu	OS7-6	44/66
Takashi Ogata	OS16-2	32/82
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	OS16-8	33/84
	OS16-10	33/85
	OS16-11	33/85
Takaya Yamaguchi	GS1-2	36/94
Takeru Amo	OS8-1	46/67
Taketo Ueno	OS9-6	47/70
Takuma Ushiroji	OS5-3	30/58
Takumi Ishimaru	OS12-1	37/75
	OS12-2	37/75
	OS12-3	37/75
Takuya Fujinaga	OS5-2	30/58
	OS5-3	30/58
	OS5-4	30/59
	OS5-5	30/59
Tan Chi Jie	OS1-2	21/49
	OS1-4	21/50
	OS1-5	22/50
Tatsuya Oshima	OS12-10	38/78
Tayfun Nesimoglu	OS5-15	31/62
	OS5-16	31/62
Tee Wen Jun	OS4-6	42/56
Tenma Matsumoto	OS9-6	47/70
Teppakorn Sittiwanchai	OS1-2	21/49
	OS1-7	22/50
Teruya Minakuchi	OS9-1	47/68
Tetsuro Katayama	OS8-1	46/67
	OS8-2	46/68
	OS8-3	46/68
Thines Vasanthan	OS6-2	36/63
Ting-An Chang	OS11-5	23/74
Ting-Chien Chuang	POS	25/106
Tohlu Matsushima	OS5-10	31/60
	OS5-13	31/61
Tohru Kamiya	GS2-3	32/95
	GS4-4	27/99
Tomohiko Takagi	OS8-1	46/67
Tomohiro Takahashi	OS8-2	46/68
Tomohito Yamamura	GS5-2	46/101
Tomoki Taniguchi	GS3-1	34/97
	GS7-2	35/103
	GS7-3	35/104
Tomomi Sudo	OS7-8	44/67
	OS7-9	45/67
Tomoya Senda	OS9-3	47/69
Tomoya Shiba	OS7-1	44/65
	OS7-2	44/65
Toru Hiraoka	GS4-2	27/98
Toshiyuki Wakisaka	OS5-10	31/60
	OS5-14	31/61
Tsutomu Ito	OS18-3	40/88
[U]		
Umm E Mariya Shah	OS4-5	42/56
	OS4-10	43/57
[V]		
Vjosa Bytyqi	OS1-10	22/51
[W]		
Wan Zailah Wan Said	OS19-2	28/89

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Wang po-ting	OS11-7	23/74
	OS11-8	23/74
Wataru Mizushina	GS3-1	34/97
Watcharin Tangsuksant	OS1-2	21/49
Way Soong Lim	OS1-3	21/49
Wei Xiao	OS20-5	28/93
Wei-Xiang Li	OS2-1	25/52
	OS2-2	25/52
Wei-Xiang Lin	OS2-4	25/53
Weizheng Pan	OS1-1	21/49
Wen-Hua Li	GS8-1	-/105
Wen-Shyang Hwang	OS2-4	25/53
Wenjunliang Zhang	OS18-3	40/88
	OS18-4	40/88
Wisanu Jitviriya	OS1-2	21/49
	OS1-7	22/50
Wong Wei Herng	OS19-1	28/88
[X]		
Xingyu Zhao	OS20-5	28/93
Xinlin Wang	OS20-5	28/93
Xinyu Chen	OS20-5	28/93
Xuancheng You	OS13-3	-/79
Xuewen Zhang	OS13-2	-/78
[Y]		
Ya-Chen Li	OS2-4	25/53
Yamato Fukuiri	OS1-9	22/51
Yan-Hua Chen	OS10-9	24/72
Yang Liu	OS13-1	-/78
	OS13-2	-/78
Yang Tang	OS20-5	28/93
Yao Wang	OS13-5	-/79
Yao-Tien Chen	POS	25/106
Yasir Mehmood	OS4-10	43/57
Yasuhiro Suzuki	OS14-1	34/80
	OS14-2	34/80
	OS14-3	34/80
Yi-Feng Tsou	OS10-9	24/72
Yi-Ting Liu	OS10-1	23/70
Yide Yang	GS7-1	35/103
Yingmin Jia	OS13-2	-/78
Yiqian Ge	GS7-3	35/104
Yohei Kamikawa	GS4-1	27/98
Yoji Kawamura	OS16-1	32/82
Yoshihiro Kita	OS8-2	46/68
	OS8-3	46/68
Yoshihiro Ueda	OS9-1	47/68
	OS9-2	47/69
	OS9-3	47/69
	OS9-4	47/69
Yoshikazu Hirayama	GS4-5	27/99
Yoshiki Hori	OS1-6	22/50
Young-Im Cho	PS1	21/48
Youyang Ye	OS20-5	28/93
Yu Oshikawa	OS12-1	37/75
	OS12-2	37/75
	OS12-3	37/75
Yu-Chi Li	OS2-4	25/53
Yu-En Tien	OS10-4	24/71
Yu-Ming Li	OS11-2	23/73
Yudai Yamaguchi	OS12-10	38/78
Yue He	OS13-3	-/79
Yue Ma	OS13-4	-/79
Yui Tanjo	GS1-2	36/94
	GS2-4	32/96
	GS2-5	32/96
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	GS4-7	27/100
	GS6-1	34/101
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Yuichiro Tanaka	OS7-3	44/65
	OS7-4	44/66
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Yuka Okayama	OS16-7	33/84

Yuki Fukumoto	OS5-10	31/60
	OS5-13	31/61
Yuki Tomoda	GS1-1	36/94
Yukiko Furuya	OS16-4	32/83
Yukito Yoshidai	GS4-1	27/98
Yulin Duan	OS13-1	-/78
Yuma Yoshimoto	OS7-6	44/66
	OS7-7	44/66
Yunzhong Song	OS20-1	28/92
Yutaka Yamaguti	GS1-1	36/94
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Yuting Hsiao	OS10-7	24/72
Yuya Doi	OS9-6	47/70
Yuya Nishida	OS5-8	31/60
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Zaris Izzati Mohd Yassin	OS18-2	40/87
Zhao-Sheng Chen	OS11-6	23/74
Zhaorui Hao	OS20-4	28/92
Zhi-Yuan Su	OS2-1	25/52
Zhongxi Zhang	GS6-2	34/102
Zi-Jie Xu	OS10-7	24/72
Zitong Zhou	OS5-9	31/60
Zong-Sheng Li	OS3-1	25/53