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IEEE
IEEE 11TH INTERNATIONAL CONFERENCE ON UNDERWATER SYSTEM TECHNOLOGY: THEORY AND APPLICATIONS
16th to 18th October 2026, Shanghai, China

USYS 2026

- Organizing Committee
- Submission Procedure
- Program

Conference Hosts

Co-organizer

IEEE Oceanic Engineering Society Malaysia Chapter

上海理工大学 水下机器人系统与智能系统研究所

Contact Us

Secretariat of USYS'26:

University of Shanghai for Science and Technology
No. 516, Gongjun Road, Yangpu District, Shanghai

Email:
USYS2026@163.com

Welcome to IEEE USYS 2026 !

Welcome to the 2026 IEEE 11th International Conference on Underwater System Technology: Theory and Applications (USYS 2026). The conference will be held in collaboration with IEEE Oceanic Engineering Society Malaysia Chapter and University of Shanghai for Science and Technology from October 16th to 18th, 2026.

USYS 2026 aims to provide a platform for researchers, scientists, engineers, academicians, and industrial professionals from around the world to share, discuss, and disseminate their current R&D activities and experiences in the field of underwater system technology, covering both fundamental theories and practical applications.

The conference focuses on advancing underwater vehicle technology, intelligent subsea systems, control and simulation methods, and ocean engineering applications. It also seeks to explore new technologies and strategies for marine resource utilization, ocean ecosystem preservation, and the future development of underwater system technology.

Conference Date: 16th to 18th October 2026
Conference Location: Shanghai, China

Submission

Registration

Hotel

Important Dates

Deadline for Full-paper: **8th June, 2026**
Notification of Acceptance: **20th August, 2026**
Camera Ready Submission: **16th September, 2026**

Submission Guidelines

Conference Service Company

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IEEE USYS 2026

2026 IEEE 11th International Conference on Underwater System Technology: Theory and Applications

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IEEE USYS 2026

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Welcome to the IEEE USYS 2026! Please have your papers submitted by the deadline. Papers must be written in English and should describe original work, which has not been published or being reviewed for other conferences. Please submit the full-paper in .doc or .pdf format limited to six pages. Accepted paper will be sent to IEEE Xplore for indexing (subject to fulfilling the IEEE regulation).

TITLE AND ABSTRACT

* Title

* Abstract

846

AUTHORS*

You may add your coauthors.

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<input checked="" type="radio"/>	dongyinchu02@163.com	Yinchu	Dong	上海理工大学	China <input type="button" value="x"/> <input type="button" value="↑"/> <input type="button" value="↓"/>

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SUBJECT AREAS*

- Marine technology
- Ocean structure
- Software Engineering and Simulation
- Seabed mapping techniques
- Virtual collaborative simulation software
- Virtual environment

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<input type="checkbox"/> Advanced underwater object ranging & tracking	<input type="checkbox"/> Renewable energy sources
<input type="checkbox"/> Intelligent navigation guidance, Obstacle avoidance	<input type="checkbox"/> Underwater communication system
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Step3: Delivery Confirmation

Submission Summary

Conference Name	2026 IEEE 11th International Conference on Underwater System Technology: Theory and Applications
Paper ID	6
Paper Title	Simulation Research on Tension-Balanced Multi-AUV Cooperative Hoisting
Abstract	To address the critical challenges of path planning, formation maintenance, and load tension balancing in multi-autonomous underwater vehicle (AUV) cooperative lifting operations, this paper presents an integrated planning frame work that synergizes an enhanced three-dimensional Artificial Potential Field (APF) approach, a formation control scheme based on relative positional relationships, and a tension

2026 IEEE 11th International Conference on Underwater System Technology: Theory and Applications : Submission (6) has been created. 



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Track Name: USYS2026

Paper ID: 6

Paper Title: Simulation Research on Tension-Balanced Multi-AUV Cooperative Hoisting

Abstract:

To address the critical challenges of path planning, formation maintenance, and load tension balancing in multi-autonomous

Confirm the paper id