

YUNZHI LIN

✉ yunzhi.lin@gatech.edu ☎ +1 (470)351-9500 🌐 <https://yunzhi.netlify.com>

🎓 Google Scholar 📍 TSRB 440, 85 5th ST NW, Atlanta, GA, 30308, United States

SUMMARY

I am an ECE Ph.D. candidate at Georgia Tech, specializing in integrating computer vision with robotics to address real-world challenges. My expertise includes 6-DoF object pose estimation, object grasping, and human-robot interaction, enriched by collaborations with NVIDIA Research and Meta FAIR.

RESEARCH INTEREST

- Computer Vision: Object Pose Estimation, Object Pose Tracking, Keypoint Tracking, Neural Radiance Field
- Robotics: Object Grasping, Robot Manipulation, Robot Simulation, Human-Robot Interaction

ACADEMIC EXPERIENCE

- **Georgia Institute of Technology** *Atlanta, USA 08/2018 - Present*
Ph.D. Candidate & M.S. in ECE
- **University of Alberta** *Edmonton, Canada 09/2017 - 12/2017*
Research Intern in Applied Nonlinear Control Lab
- **Southeast University** *Nanjing, China 09/2014 - 06/2018*
B.E. in Automation, Overall GPA: 3.86/4.0 (Rank: 3/104)

INDUSTRY EXPERIENCE

- **Meta AI** *Menlo Park, USA 05/2023 - 11/2023*
Research Intern, Advisor: Kevin Liang, Yipu Zhao, Fu-Jen Chu, Matt Feiszli
Ego-HowTo Team, FAIR Accel
 - ◇ **Generalized Object Pose Tracking**
 - Developed a streamlined pipeline combining video segmentation, uncertainty-aware keypoint refinement, and structure from motion, effectively tracking 6-DoF poses from short-term monocular RGB video
 - Generated a large-scale photo-realistic synthetic dataset of 40K clips (4M frames) using BlenderProc2, including RGB/depth/mask/normal/pose annotations, facilitating object pose tracking in dynamic settings
- **NVIDIA Research** *Atlanta, USA 05/2022 - 12/2022*
Research Intern, Advisor: Thomas Müller, Jonathan Tremblay, Stan Birchfield
Learning and Perception Research Group
 - ◇ **Neural Radiance Fields for Robust Pose Estimation (ICRA 2023)**
 - Developed a parallelized, momentum-based optimization method using NeRF models to estimate 6-DoF poses from monocular RGB input
 - Achieved improved generalization and robustness on both synthetic and real-world benchmarks, improving the percentage of pose error less than 5 degrees or 0.05 units threshold over 40%
- **NVIDIA Research** *Atlanta, USA 05/2020 - 05/2021*
Research Intern, Advisor: Jonathan Tremblay, Stephen Tyree, Stan Birchfield
Learning and Perception Research Group
 - ◇ **Category-level Object Pose Estimation (ICRA 2022 & Patent US20220277472A1)**

- Developed a keypoint-based RGB-only 6-DoF and size pose estimator for category-level objects
- Integrated into [NVIDIA Isaac Robot Operating System (ROS)]
- ◇ **Category-level Object Pose Tracking (ICRA 2022 & Patent US20240005547A1)**
 - Extended to support robust object pose tracking with uncertainty estimation
 - SOTA results on the Objectron benchmark, improving average precision at 0.5 3D IoU from 72% to 80%
- ◇ **Multi-level Scene Understanding (IROS 2021 & Patent US20220068024A1)**
 - Proposed a multi-level robotic scene understanding system, including dense 3D reconstruction, shape estimation and fitting of objects with primitive shapes, and full 6-DoF pose estimation of known object instances

RESEARCH EXPERIENCE

- **Georgia Institute of Technology** *Atlanta, USA 06/2021 - 12/2022 & 02/2019 - 05/2020*
Research Assistant, Advisor: Patricio A. Vela
Intelligent Vision and Automation Laboratory
 - ◇ **Human-Robot Interaction: Playing Jigsaw Puzzles with A Robot (NSF Funding [#2026611])**
 - Developed a human-robot system that allows a robot to interact and play jigsaw puzzles with human players
 - Created a cost-effective robot platform (\$1K) with RealSense D415 and Dynamixel servomotor
 - ◇ **Object Grasping via Primitive Shapes (ICRA 2020)**
 - Developed an automated strategy to generate primitive shape data in the V-REP simulation
 - Designed a grasping pipeline that segments objects from depth input, identifies optimal shape parameters through shape fitting, and selects and executes the most feasible grasp
 - Achieved over 93% success rate on static grasping task using a 7-DoF robotic arm

HONORS AND AWARDS

- NVIDIA Patent Award (3x), NVIDIA Corp. *04/2021-03/2022*
- Outstanding Graduates (top 5%), Southeast University *06/2018*
- National Undergraduate Exchange Scholarship, China Scholarship Council *06/2017*
- National Scholarship (top 3%), Southeast University *09/2015*

SKILLS

- **Programming Languages:** C/C++, Python, Matlab
- **Softwares & Tools:** OpenCV, V-REP, ROS, Caffe, TensorFlow, PyTorch