

YUNZHI LIN

✉ yunzhi.lin@gatech.edu ☎ +1 (470)351-9500 🌐 <https://yunzhi.netlify.app>
🎓 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 in FAIR Accel
- **NVIDIA Research** *Remote, USA 05/2022 - 12/2022*
Research Intern in Learning and Perception Research Group
- **NVIDIA Research** *Remote, USA 05/2020 - 05/2021*
Research Intern in Learning and Perception Research Group

RESEARCH EXPERIENCE

- **Generalized Object Pose Tracking** *05/2023 - 11/2023*
Advisor: Kevin Liang, Fu-Jen Chu, Yipu Zhao, Xingyu Chen, Weiyao Wang, Hao Tang, Patricio A. Vela, Matt Feiszli
Ego-HowTo Team, Meta FAIR Accel
 - 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
- **Neural Radiance Fields for Robust Pose Estimation** *05/2022 - 09/2022*
Advisor: Thomas Müller, Jonathan Tremblay, Bowen Wen, Stephen Tyree, Alex Evans, Patricio A. Vela, Stan Birchfield
Learning and Perception Research Group, NVIDIA Research

- 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

- **Human-Robot Interaction: Playing Jigsaw Puzzles with A Robot** 06/2021 - 12/2022

Advisor: Patricio A. Vela

Intelligent Vision and Automation Laboratory, Georgia Institute of Technology

- 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
- Funded by National Science Foundation (NSF) for research and development [#2026611]

- **Category-level Object Pose Estimation and Tracking** 11/2020 - 09/2021

Advisor: Jonathan Tremblay, Stephen Tyree, Patricio A. Vela, Stan Birchfield

Learning and Perception Research Group, NVIDIA Research

- Developed a keypoint-based RGB-only 6-DoF and size pose estimator for category-level objects
- 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%
- Integrated into [NVIDIA Isaac Robot Operating System (ROS)]

- **Multi-level Scene Understanding** 05/2020 - 10/2020

Advisor: Jonathan Tremblay, Stephen Tyree, Patricio A. Vela, Stan Birchfield

Learning and Perception Research Group, NVIDIA Research

- 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

- **Object Grasping via Primitive Shapes** 02/2019 - 05/2020

Advisor: Patricio A. Vela

Intelligent Vision and Automation Laboratory, Georgia Institute of Technology

- 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

PATENTS

- **Object pose tracking from video images**
Yunzhi Lin, Jonathan Tremblay, Stephen Tyree, Stan Birchfield
Number: US20240005547A1
- **Single-stage category-level object pose estimation**
Stan Birchfield, Jonathan Tremblay, Yunzhi Lin, Stephen Tyree
Number: US20220277472A1
- **Determining a three-dimensional representation of a scene**
Yunzhi Lin, Jonathan Tremblay, Stephen Tyree, Stan Birchfield
Number: US20220068024A1

SELECTED PUBLICATIONS [Google Scholar]

Preprints

- [P1]. **Primitive Shapes Recognition for Object Grasping**
Yunzhi Lin, Chao Tang, Fujen Chu, Ruinian Xu, Patricio A. Vela
arXiv:2201.00956
- [P2]. **OmniPose6D: Towards Short-Term Object Pose Tracking in Dynamic Scenes from Monocular RGB Input**
Yunzhi Lin, Kevin Liang, Fu-Jen Chu, Yipu Zhao, Xingyu Chen, Weiyao Wang, Hao Tang, Patricio A. Vela, Matt Feiszli
In Submission

Conferences

- [C1]. **WDiscOOD: Out-of-Distribution Detection via Whitened Linear Discriminative Analysis**
Yiye Chen, Yunzhi Lin, Ruinian Xu, Patricio A. Vela
International Conference on Computer Vision (ICCV 2023)
- [C2]. **KGNv2: Separating Scale and Pose Prediction for Keypoint-based 6-DoF Grasp Pose Synthesis on RGB-D input**
Yiye Chen, Ruinian Xu, Yunzhi Lin, Patricio A. Vela
IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS 2023)
- [C3]. **Parallel Inversion of Neural Radiance Fields for Robust Pose Estimation**
Yunzhi Lin, Thomas Müller, Jonathan Tremblay, Bowen Wen, Stephen Tyree, Alex Evans, Patricio A. Vela, Stan Birchfield
IEEE International Conference on Robotics and Automation (ICRA 2023)
- [C4]. **Keypoint-GraspNet: Keypoint-based 6-DoF Grasp Generation from the Monocular RGB-D input**
Yiye Chen, Yunzhi Lin, Patricio A. Vela
IEEE International Conference on Robotics and Automation (ICRA 2023)
- [C5]. **Keypoint-based Category-level Object Pose Tracking from an RGB Sequence with Uncertainty Estimation**
Yunzhi Lin, Jonathan Tremblay, Stephen Tyree, Patricio A. Vela, Stan Birchfield
IEEE International Conference on Robotics and Automation (ICRA 2022)
- [C6]. **Single-Stage Keypoint-based Category-level Object Pose Estimation from an RGB Image**
Yunzhi Lin, Jonathan Tremblay, Stephen Tyree, Patricio A. Vela, Stan Birchfield
IEEE International Conference on Robotics and Automation (ICRA 2022)
- [C7]. **Multi-view Fusion for Multi-level Robotic Scene Understanding**
Yunzhi Lin, Jonathan Tremblay, Stephen Tyree, Patricio A. Vela, Stan Birchfield
IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS 2021)
- [C8]. **A Joint Network for Grasp Detection Conditioned on Natural Language Commands**
Yiye Chen, Ruinian Xu, Yunzhi Lin, Patricio A. Vela
IEEE International Conference on Robotics and Automation (ICRA 2021)
- [C9]. **Using Synthetic Data and Deep Networks to Recognize Primitive Shapes for Object Grasping**

Yunzhi Lin*, Chao Tang*, Fujen Chu, Patricio A. Vela
IEEE International Conference on Robotics and Automation (ICRA 2020)

- [C10]. **Blind Deblurring Using Discriminative Image Smoothing**
Wenze Shao, **Yunzhi Lin**, Bingkun Bao, Liqian Wang, Qi Ge, Haibo Li
Pattern Recognition and Computer Vision (PRCV 2018)

Journals

- [J1]. **SGL: Symbolic Goal Learning in a Hybrid, Modular Framework for Human Instruction Following**
Ruinian Xu, Hongyi Chen, **Yunzhi Lin**, Patricio A. Vela
IEEE Robotics and Automation letters
- [J2]. **Gradient-based discriminative modeling for blind image deblurring**
Wenze Shao, **Yunzhi Lin**, Yuanyuan Liu, Liqian Wang, Qi Ge, Bingkun Bao, Haibo Li
Nerocomputing
Journal of Mathematical Imaging and Vision

Workshops

- [W1]. **NViSII: A Scriptable Tool for Photorealistic Image Generation**
Nathan Morrical, Jonathan Tremblay, **Yunzhi Lin**, Stephen Tyree, Stan Birchfield, Valerio Pascucci, Ingo Wald
International Conference on Learning Representations Workshop (ICLR workshop 2021)

TEACHING EXPERIENCE

- Teaching Assistant, ECE 3005 Professional and Technical Communications, Gatech *Spring 2023*
- Teaching Assistant, ECE 4560 Introduction to Automation & Robotics, Gatech *Fall 2022*

ACADEMIC SERVICE

- Conference reviewer for CoRL'19, ICRA'21-24, IROS'21-24, ECCV'22
- Journal reviewer: Neurocomputing, IEEE Robotics and Automation Letters, IEEE/ASME Transactions on Mechatronics, IEEE/CAA Journal of Automatica Sinica, IEEE Computer Graphics and Applications, IEEE Transactions on Circuits and Systems for Video Technology, IEEE Transactions on Automation Science and Engineering

HONORS AND AWARDS

- NVIDIA Patent Award (3x), NIVIDA 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