NING BI

E C Stoner Building 6.01• Leeds, United Kingdom, LS2 9JT
(+44) 07432578740 • scnb@leeds.ac.uk • https://github.com/mrtriskin

EDUCATION

University of Leeds **Leeds UK**
School of Computing, Ph.D candidate(full scholarship) in Computer Science *Sept. 2019 - Present*
Advisor: Prof. Ali Gooya, Prof. Alejandro F Frangi
Proposed area of research: Bayesian Deep Atlases for Cardiac Motion Abnormality Detection from Imaging and Metadata.

ShanghaiTech University **Shanghai China**
School of Information Science and Technology, B.S. in Computer Science *Sept. 2015 - July. 2019*
Advisor: Prof. Shenghua Gao, Major in Computer Vision

SKILLS

Research Interests: Segmentation, Object Tracking, Abnormality Detection, Image Synthesis.
Programming: Python(Pytorch), C++, MATLAB, C#, JS, LaTex.
Knowledge: IELTS(7/9), Nodejs, Docker, Git.
Softwars: Maya, SolidWorks, Photoshop, Adobe Premiere, Microsoft Office.

AWARDS AND HONORS

The **2nd Prize** in INESA i-Lab Hackathon, Shanghai *July. 2017*
The **Top 10 Prize** in TechCrunch Hackathon, Shanghai *Nov. 2017*
The **3rd Prize** in Robomaster Central Division, Hangzhou *June. 2018*
Reviewer of IEEE Transactions on Circuits and Systems for Video Technology *Aug. 2020 - Present*
Honored Student Volunteer in IEEE Joint Conferences IEEE SOSE 2020 *Aug. 2020*

WORK EXPERIENCE

SVIP Lab *ShanghaiTech University* **Shanghai China**
· Research internship on Deep Learning based **Object Detection** projects. *Mar. 2018 - Jun. 2019*
YOKE Intelligence *R&D department* **Shanghai China**
· Computer vision algorithm internship on **Multi-view Object Tracking & Re-identification**. *Sept. 2018 - July. 2019*
ShanghaiTech University *School of Information Science and Technology* **Shanghai China**
· Teaching Assistant of CS172 Computer Vision. *Sept. 2018 - Dec. 2018*
University of Leeds *School of Computing* **Leeds UK**
· Teaching Assistant of COMP2611 Artificial Intelligence *Mar. 2020 - June. 2020*
University of Leeds *School of Computing* **Leeds UK**
· Teaching Assistant of COMP5712M Programming for Data Science *Sept. 2020 - Present*

PUBLICATIONS

PPGNet: Learning Point-Pair Graph for Line Segment Detection *Mar. 2019*
Ziheng Zhang, Zhengxin Li, ***Ning Bi****, Shenghua Gao*

Accepted by **CVPR** 2019

Multiview Vehicle Tracking by Graph Matching Model *Jun. 2019*
Minye Wu, Guli Zhang, ***Ning Bi****, Zhiru Shi*

Accepted by **CVPR** 2019 **AICity Challenge**

Visual Tracking With Multiview Trajectory Prediction *Aug. 2020*
Minye Wu, Haibin Ling, ***Ning Bi****, Shenghua Gao, Qiang Hu, Hao Sheng, Jingyi Yu*

Accepted by **IEEE Transactions on Image Processing**

DragNet: learning-based deformable registration for realistic cardiac MR sequencegeneration from a single frame *Jul. 2022*

Arezoo Zakeri, Alireza Hokmabadi, ***Ning Bi****, Isuru Wijesinghe, Michael G. Nix, Steffen E. Petersen, Alejandro F.Frangi, Zeike A. Taylor, Ali Gooya*

Accepted by **Medical Image Analysis**

SegMorph: Concurrent Segmentation and Motion Estimation on CMR Sequences *Oct. 2022*

Ning Bi*, Arezoo Zakeri, Yan Xia, Alejandro F.Frangi, Ali Gooya*

Under review by **IEEE Transactions on Medical Imaging**

RESEARCH EXPERIENCES

Bayesian deep atlases for cardiac motion abnormality detection from imaging and metadata *Sept. 2020*

Ph.D. Project, University of Leeds

Investigates the role of metadata (age, gender, etc.) in determining cardiac motion and abnormalities.

Weakly Supervised Cardiac Segmentation via Recurrent VAE *Sept. 2019*

Provisional PhD Project, University of Leeds

Exploited temporal and spatial recurrent feature to reach a self-supervised cardiac segmentation approach.

Reinforcement Learning based Path Planning Robot *Jun. 2018*

Course Project(CS285 Mechatronics), ShanghaiTech University

Proposed an end-to-end framework, PPGNet, to extract wire-frame structure in man-made space.

Reinforcement Learning based Path Planning Robot *Jun. 2018*

Course Project(CS285 Mechatronics), ShanghaiTech University

Proposed an end-to-end framework, PPGNet, to extract wire-frame structure in man-made space.

SIST Rambler Robot *Nov. 2017*

Course Project(CS283/CS284 Robotics/SLAM), ShanghaiTech University

Propose a key-frame based SLAM algorithm and extend it to a robot with two oriented Velodyne LIDARs.