Yuhai Wang

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Education

University of Southern California — Los Angeles, CA
M.S. in Analytics; ***GPA: 3.8/4.0*** — *Jan. 2023 – Present*
Related Courses: Robotics; Optimization; Deep Learning

Tiangong University — Tianjin, China
B.E. in Internet of Things; ***GPA: 3.7/4.0 (top 5%)*** — *Aug. 2018 – May. 2022*
Related Courses: Advanced Mathematics; Data Structure; Operating System

Research Interest

My research experience spans legged robots, robotic arms, multi-phase reinforcement learning, and computer vision (including re-identification and Neural Radiance Fields), and I am eager to keep this momentum going in my PhD studies. I am particularly interested in the intersection of (i) robotic manipulation, (ii) object detection and 3D reconstruction, (iii) reinforcement learning, and (iv) large language models. Currently, I am leading a research project on using whole-body control (WBC) to enable a quadruped robot to maintain balance while reaching a target position in highly dynamic environments.

Selected Publications

1. **Wang, Yuhai**; Maryam Pishgar. Dynamic Token Selective Transformer for Aerial-Ground Person Re-Identification. *IEEE International Conference on Multimedia & Expo (ICME), under review, 2025.* [pdf], [project page].

2. Jiang, Hao; **Wang, Yuhai***; Zhou, Hanyang*; Seita, Daniel. Learning to Singulate Objects in Packed Environments Using a Dexterous Hand. *International Symposium of Robotics Research (ISRR), 2024.* [pdf], [project page].

3. Ye, Baijun; Liu, Caiyun; Ye, Xiaoyu; Chen, Yuantao; **Wang, Yuhai**; Yan, Zike; Shi, Yongliang; Zhao, Hao; Zhou, Guyue. Blending Distributed NeRFs with Tri-stage Robust Pose Optimization. *International Conference on Intelligent Robots and Systems (IROS), 2024.* [pdf]

4. Xue, Yongjiang; Yuan, Xichen; **Wang, Yuhai(speaker)**; Yang, Yang; Lu, Siyu; Zhang, Bo; Lai, Juezhu; Wang, Jianming; Xiao, Xuan. Lywal: A Leg-Wheel Transformable Quadruped Robot with Picking Up and Transport Functions. *International Conference on Robotics and Automation (ICRA), 2021.* [pdf] [Video page].

Research Experience

Sensing, Learning, and Understanding for Robotic Manipulation (SLURM) Lab — Los Angeles, CA
Research Assistant, advised by Prof. Daniel Seita — *Sep. 2023 – present*

- Developed a framework for object separation in crowded environments using Isaac Gym for simulation, incorporating displacement-based state representation and multi-phase reinforcement learning. Conducted physical experiments with Allegro and Franka robots, using Realsense D435i and D405 for the vision system, based on the DROID Robot Platform.(ISRR 2024)
- Proposed a Top-k Token Selective Transformer for aerial-ground camera networks(AGPReID), to better model identity representation spatially(ICME 2025 Under Review)

Institute of AI Industry Research(AIR), Tsinghua University Remote

Research Assistant, advised by Prof. Guyue Zhou & Prof. Yongliang Shi *April. 2023 – Sep. 2023*

- Developed a distributed NeRF system with three-stage pose optimization, utilizing Mip-NeRF360 to obtain precise image poses and enhancing robustness through inverted Mip-NeRF360 and truncated dynamic low-pass filters.(IROS 2024)
- Achieved NeRF fusion by calculating coarse transformations between NeRFs in different coordinate systems, demonstrating strong performance in both real-world and simulated environments.

Institute of AI Industry Research(AIR), Tsinghua University Beijing, China

Research Engineer, advised by Prof. Guyue Zhou & Prof. Xinliang Zhang *Aug. 2021 – Feb. 2022*

- Exported the URDF models of the ARX5 robot arm from SolidWorks and completed its simulation and physical control using MoveIt and ROS. Utilized a RealSense D435i camera to acquire ArUco marker positions, integrating them into ROS to enable the ARX5's end effector to track the position of the ArUco marker.
- Participated in building the simulation environment for the IEEE ICRA2022 RoboMaster University Sim2Real Challenge.

Robotics Research Lab, Tiangong University Tianjin, China

Research Assistant, advised by Prof. Xuan Xiao *Oct. 2019 – Aug. 2021*

- Designed and developed a quadruped robot featuring a novel leg mechanism based on a four-bar linkage, and completed kinematic calculations using C language.
- Utilized Webots for robot simulation to achieve two motion postures, and employed MATLAB for controlling the physical robot, successfully conducting experimental tests.(ICRA 2021)

Service

SLURM Lab, USC Los Angelegs, CA

Graduate Research Assistant *Sep. 2023 – now*

WBCD Competition@ICRA 2025 Atlanta, GA

Hardware Sponsor *May. 2025*

ISE 534: Data Analytics Consulting, USC Los Angelegs, CA

Graduate Teaching Assistant *Jan. 2024 – May. 2024*

Agile Robotics workshop@ICRA 2024 Remote

Reviewer *April. 2024*

School of Computer Science and Technology, Tiangong University Tianjin, China

Academic Representative *Aug. 2018 – May. 2022*

Honors & Awards

President's Scholarship *2019, 2020*

Social Activities Scholarship *2020*

Outstanding Student Leader Award *2019, 2021*

Off-campus competition scholarship *2020*

First Prize in the National Challenge Cup Competition *2021*

Honorable Mention of the Mathematical Contest in Modeling *2020*

Skills

Programming Languages: Python, C, Matlab, R, SPSS, SQL

Robotics: ROS, Motion Planning, Mobile Manipulation

Robot Learning: RL (DDPG, PPO), IL (BC), Inverse RL, Hierarchical Learning

Robot Hardwares: Franka, Allegro Hand, ARX5 Arm, Go2 Dog, Leap Hand, Lywal(undergraduate project)

Computer Vision: Re-identification, Diffusion Models, GANs

Libraries: PyTorch, OpenCV, Issac Gym, Mujoco