



Eungchang Mason Lee

ROBOTICS RESEARCHER · UAVs EXPERT

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📄 engchang | 🎓 Google Scholar | 🏠 engchang.github.io

About Me

I am a well-organized, fast-learning, and hard-working person. My research interests are laid on UAVs, Exploration, Path planning, SLAM, and Active SLAM.

I recommend to look over my 📄 Github and 📺 Youtube

Education

KAIST (Korea Advanced Institute of Science and Technology)

PH. D. **CANDIDATE** IN ELECTRICAL ENGINEERING, URBAN ROBOTICS LAB

- GPA: 3.63/4.3

Daejeon, Rep. of Korea

Mar. 2021 - Current

KAIST (Korea Advanced Institute of Science and Technology)

MASTER IN ELECTRICAL ENGINEERING, URBAN ROBOTICS LAB

- GPA: 3.58/4.3

Daejeon, Rep. of Korea

Mar. 2019 - Feb. 2021

KyungPook National University

BACHELOR IN SCHOOL OF ELECTRONICS ENGINEERING

- Graduation with top honors, **GPA: 4.23/4.3, rank: 2/354**
- Two-year leave for military service
- One-year leave for Working Holiday in Canada

Daegu, Rep. of Korea

Mar. 2012 - Feb. 2019

Skills

Tools MATLAB, Solidworks, Blender, Sketchup, Gazebo, Unity

Programming ROS, C/C++, Python, MATLAB, Markdown, LaTeX, HTML

Languages Korean, English

Honors & Awards

2022. 10 **Only one team that finished the course:** Autonomous Flight Competition in Battlefield Situations

Rep. of Korea

2019. 12 **3rd Prize/424:** AIRR AlphaPilot (LockheedMartin & The Drone Racing League)

U.S.A

2019. 02 **Grand Prize:** The right person of University (SmartKey-KyungPook National University)

Rep. of Korea

2019. 02 **2nd Prize/354:** Best Graduates of The Year (KyungPook National University)

Rep. of Korea

2018. 11 **MathWorks Korea Special Prize:** R-BIZ Challenge Turtlebot3 Autorace (ROBOTIS & MathWorks Korea)

Rep. of Korea

Activities

1. **2022 UVS Symposium:** Invited talk - "How we won Autonomous Flight Competition in Battlefield Situations", 2022. 12., *Daejeon, Rep. of Korea*

2. **KBS JungGyeon-ManLi Season 3** - "Ep 6. Coexistence with Robots", Co-operation with Meere Company, 2021. 11., *Video*

Experiences & Projects

Development of Drone System for Diagnosis of Porcelain Insulators in Overhead Transmission Lines

Rep. of Korea

SUPPORTED BY KEPSCO AND KEPRI

Apr. 2023 - Current

CONDUCTED AT URBAN ROBOTICS LAB IN KAIST

- In this project, we develop a autonomous drone manipulation framework for diagnosis of porcelain insulators in transmission lines. We are developing a robust multi-LiDAR SLAM, real-time obstacle avoidance path planner, and adaptive attitude / trajectory tracking controllers.
- I am mainly developing the multi-LiDAR SLAM and path planner.
- Relative video - video

Research of Coverage Path Planner for 3D Reconstruction with UAVs

Rep. of Korea

SUPPORTED BY CONFIDENTIAL

in 2022

CONDUCTED AT URBAN ROBOTICS LAB IN KAIST

- In this project, we developed a energy-efficient and obstacle-aware coverage path planner for UAVs to accurately reconstruct the target structures with high-resolution. The detailed information is confidential.
- I developed the main coverage path planner.
- Relative video - video
- Relative paper - doi.org/10.1007/978-3-031-26889-2_3

Autonomous Flight Competition in Battlefield Situations

Rep. of Korea

HOSTED BY ADD

May. 2022 - Oct. 2022

CONDUCTED AT URBAN ROBOTICS LAB IN KAIST

- The competition aims to develop an autonomous drone to pass through complex and dangerous outdoor obstacles, infiltrate an unknown two-story building, detect hidden targets, create precise 3D maps including target types and coordinates, and return to the starting point safely.
- I developed main framework including exploration, local/global path planners, 3D map logger with the detected target positions, and a decision-making system.
- Relative video - video

KHNP Virtual Robot Challenge 2022 (as a developer and a maintainer)

Rep. of Korea

HOSTED BY KHNP

Sep. 2022 - Dec. 2022

- The goals of the competition was to develop a autonomous navigation algorithm and a robust controller for a quadrotor UAV to complete diverse and challenging tasks including obstacle avoidance, exploration, and enduring the wind disturbances.
- I made Gazebo maps for the competition and coded scoring GUI. Additionally, I coded sample controllers for the the quadrotor UAV.
- Relative video - video

Palm Tree Field Exploration and Tree Identification with UAV / UGV

Rep. of Korea

CONDUCTED AT AKA-AI ROBOTICS

Nov. 2021 - May. 2022

- The final goal of this research project is to develop an exploration system for monitoring unknown palm tree orchard environments while avoiding collisions and figuring out appearances of trees (phenotyping).
- I developed the whole system including pointcloud data processing, path planning, and controller. A state-of-the-art open-sourced SLAM algorithm is utilized.
- Relative videos - video1, video2

IEEE UAV Competition

U.S.A

HOSTED BY LPCV

Jan. 2022 - Feb. 2022

CONDUCTED AT URBAN ROBOTICS LAB IN KAIST

- The goals of the competition was to track the non-uniform motion vehicle at constant distance away with a quadrotor UAV, while avoiding obstacles.
- We estimated the trajectory of the moving vehicle in the form of 5th order polynomial using the detected center point with YOLO network. Then, Adaptive weight Model Predictive Controller (AMPC) is designed to track the target effectively.
- I mainly developed state estimator and MPC controller.
- Relative video - video

KHNP Virtual Robot Challenge 2021 (as a developer and a maintainer)

Rep. of Korea

HOSTED BY KHNP

Sep. 2021 - Dec. 2021

- The goals of the competition was to develop a autonomous navigation algorithm and a robust controller for a quadraped robot to complete diverse and challenging tasks including obstacle avoidance, manipulation for grasping a cube, climbing stairs, and enduring the disturbances.
- I made Gazebo maps for the competition and coded scoring GUI. Additionally, I coded sample controllers for the manipulator and the quadraped robot.
- Relative video - video

Unmanned Swarm CPS Research Lab

Rep. of Korea

SUPPORTED BY ADD

Jan. 2021 - Dec. 2021

CONDUCTED AT URBAN ROBOTICS LAB IN KAIST

- In this project, we developed adaptive multi robot localization method. With the high fidelity networking, artificial intelligent cooperative control, and mobile ground control station, unmanned swarm system has been researched to operate cyber-physical systems.
- As my lab was in charge of managing all 10 labs and developing multi robot localization, as a person in charge, I mainly managed all members in the project, validated whole system for the demonstration, and developed localization algorithm.
- Relative video - video
- Relative paper - DOI: 10.23919/ICCAS52745.2021.9649888

Autonomous Drone Navigation for Power Line Inspection in Underground

Rep. of Korea

SUPPORTED BY KEPCO AND KEPRI

Aug. 2020 - Dec. 2022

CONDUCTED AT URBAN ROBOTICS LAB IN KAIST

- In this project, we developed indoor SLAM, navigation, and exploration method to operate an UAV exploring the underground power line tunnel safely. In addition, the robust and autonomous landing framework of the UAV on moving mobile robot was developed to charge battery during operation.
- I mainly developed path planner, exploration, landing framework, and navigation system. In consideration with the limited payload and computational resource of the UAV, the precomputed and lightweight local exploration planner was developed.
- Relative videos - video1, video2, video3, video4
- Relative publications - DOI: 10.1007/978-981-16-4803-8_16, DOI: 10.1109/IROS51168.2021.9636611, DOI: 10.23919/ICCAS52745.2021.9649920

A Study on the Visual-Inertial Navigation System of Artificial Intelligent Unmanned Aerial Vehicle for Reconnaissance and Exploration

Rep. of Korea

HOSTED BY ROND

May. 2020 - Nov. 2020

CONDUCTED AT URBAN ROBOTICS LAB IN KAIST

- The main goal of this project is to develop an UAV system with Visual-Inertial Navigation System for 3D mapping of unknown environments adopting single RGB-D camera.
- I mainly implemented whole system including VIO, YOLO object detection, mapping system, and controller.
- Relative video - video

AIIR AlphaPilot (Artificial Intelligence Robotic Racing)

U.S.A

HOSTED BY LOCKHEED MARTIN AND THE DRONE RACING LEAGUE

Mar. 2019 - Dec. 2019

CONDUCTED AT UNMANNED SYSTEMS RESEARCH GROUP IN KAIST

- AlphaPilot is the first large-scale open innovation challenge of its kind focused on advancing artificial intelligence (AI) and autonomy. The main goal of this competition is to finish the drone racing track as soon as possible autonomously.
- I mainly implemented a VIO (Visual-Inertial Odometry) and Kalman filter-based state estimator and basic controller.
- Our team won the 3rd prize among 424 teams over 81 countries.
- Relative videos - Youtube playlist

R-BIZ Challenge Turtlebot3 Autorace

Rep. of Korea

HOSTED BY ROBOTIS, MATHWORKS KOREA, KIRIA, AND MOTIE

Jun. 2018 - Nov. 2018

CONDUCTED AT PHYSICAL INTELLIGENCE LAB IN KYUNGPOOK NATL. UNIV.

- ROS based autonomous driving system for a mobile robot (Turtlebot3) is developed for completing the racing track with diverse missions.
- I mainly developed Lyapunov functional to control the robot, HOG-based object detector, and decision-making mission planner.
- Our team won the MathWorks Korea Special Prize.

Research on Multi-Rate Sensor Fusion based Mobile Robot Model Predictive Control System

Rep. of Korea

SUPPORTED BY THE ELECTRONICS AND TELECOMMUNICATIONS RESEARCH INSTITUTE (ETRI)

Apr. 2018 - Dec. 2018

CONDUCTED AT PHYSICAL INTELLIGENCE LAB IN KYUNGPOOK NATL. UNIV.

- The final goal of this research project is to design multi-rate State Estimator that can assume exact state using asynchronized data from a vehicle's multi sensor system.
- I mainly developed ROS based data processing system, LiDAR based path planning for the mobile robot.
- Relative publication - DOI: 10.1109/ICCE.2019.8661985

Military service

Rep. of Korea

REPUBLIC OF KOREA ARMY

Mar. 2013 - Dec. 2014

- Served as a Signaller in Combat Support Company
- Discharged as Sergeant

Technology Transfer

1. Hyun Myung, **Eunchang Lee**, and Hyungtae Lim, "Adaptive and robust 3D SLAM method that adjusts parameters depending on the environments, and Application of SLAM method for unmanned aerial vehicle flight in GNSS-denied environments", 2023.05.01, [Rep. of Korea](#)

Patents & SW

APPLIED PATENTS

1. Hyung Myung, **Eunchang Lee**, Seungwon Song, Nahrendra I Made Aswin, Junho Choi, Duckyu Choi, and Seunghyun Lee, "Drone Unit for Unmanned Exploration and Reconnaissance, Autonomous Flight System and The Method Thereof," Application Number: 10-2023-0099161, 2023.07.28, [Rep. of Korea](#)
2. Hyun Myung, Minho Oh, Wonho Song, Hyungtae Lim, **Eunchang Lee**, Euigon Jung, Sumin Hu, Jung-Hee Park, Chae Hyun Lee, and Jae Kyung Kim, "Method and Apparatus for Recognizing a Moving Environment Based on Sensor Data," Application Number: 10-2023-0075575,

3. Hyun Myung, Nahrendra I Made Aswin, Byeongho Yu, Tirtawardhana Christian, and **Eungchang Lee**, "METHOD AND APPARATUS FOR CONTROL OF DRONE PERFORMING NOMINAL CONTROL REINFORCEMENT BASED ON DEEP REINFORCEMENT LEARNING," Application Number: 10-2023-0054096, 2023.04.25, [Rep. of Korea](#)
 4. Hyun Myung, Sungjae Shin, Kwangyik Jung, **Eungchang Lee**, and Junho Choi, "Tightly Coupled UWB-Visual-Inertial Odometry for Robust Localization," Application Number: 10-2021-0154973, 2021.11.11, [Rep. of Korea](#)
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REGISTERED SW

1. Hyung Myung, Sungjae Shin, Sungwon Hwang, **Eungchang Lee**, Junho Choi, and Kwangyik Jung, "Multi-robot relative pose estimation algorithm using polar histogram matching," Registration Number: C-2021-043064, 2021.05.19, [Rep. of Korea](#)

Featured Publications

(†: Co-first author)

1. **E. M. Lee**, I. M. A. Nahrendra, J. Choi, S. Lee, and H. Myung, "Autonomous Flying Drone for Unmanned Reconnaissance in Battlefield Situations," *Korea Robotics Society Annual Conference (KRoC) RED Show*, **Best work Awarded**, 2023, [Pyeongchang, Rep. of Korea](#)
2. **E. M. Lee**, J. Choi, H. Lim, and H. Myung, "REAL: Rapid Exploration with Active Loop-Closing toward Large-Scale 3D Mapping using UAVs," in *Proc. IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, 2021, [Prague, Czech Rep.](#)
3. **E. M. Lee**, D. Choi, and H. Myung, "Peacock Exploration: A Lightweight Exploration for UAV using Control-Efficient Trajectory," in *Proc. International Conference on Robot Intelligence Technology and Applications (RITA)*, **Best paper Awarded**, 2020, [Rep. of Korea](#)
4. **E. M. Lee et al.**, "Development of a 3D Mapping System including Object Position for UAV with a RGB-D camera in an Unknown and GNSS-denied Environment," in *Proc. Institute of Embedded Engineering of Korea 2020 Fall Conference (IEMEK)*, **Best paper Awarded**, 2020, [Rep. of Korea](#)

Other Publications

(†: Co-first author)

INTERNATIONAL JOURNAL PAPERS

1. I. M. A. Nahrendra, C. Tirtawardhana, B. Yu, **E. M. Lee**, and H. Myung, "Retro-RL: Reinforcing Nominal Controller with Deep Reinforcement Learning for Tilting-Rotor Drones," *IEEE Robotics and Automation Letters (RA-L)*, 2022
 2. M. Oh, E. Jung, H. Lim, W. Song, S. Hu, **E. M. Lee**, J. Park, J. Kim, J. Lee, and H. Myung, "TRAVEL: Traversable Ground and Above-Ground Object Segmentation Using Graph Representation of 3D LiDAR Scans," *IEEE Robotics and Automation Letters (RA-L)*, **2022 RA-L Best Paper Awarded**, 2022
 3. Y. Kim, B. Yu, **E. M. Lee**, J. Kim, H. Park, and H. Myung, "STEP: State estimator for legged robots using a preintegrated foot velocity factor," *IEEE Robotics and Automation Letters (RA-L)*, 2022
 4. J. Jeon, S. Jung, **E. M. Lee**, D. Choi, and H. Myung, "Run Your Visual-Inertial Odometry on NVIDIA Jetson: Benchmark Tests on a Micro Aerial Vehicle," *IEEE Robotics and Automation Letters (RA-L)*, 2021
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INTERNATIONAL CONFERENCE PAPERS

1. D.-U. Seo, H. Lim, **E. M. Lee**, H. Lim, and H. Myung, "Enhancing Robustness of Line Tracking Through Semi-Dense Epipolar Search in Line-based SLAM," in *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, 2023, [Detroit, U.S.A](#)
2. **E. M. Lee**, D. Youn, and H. Myung, "THE-Planner: Topological and Hierarchical Exploration Path Planner for Fast 3D Mapping of Outdoor Structures with UAVs," in *Proc. IEEE International Conference on Ubiquitous Robots (UR)*, 2023, [Honolulu, U.S.A](#)
3. J. Choi, M. Jeong, **E. M. Lee**, D. Choi, and H. Myung, "NLOS-Avoiding and Obstacle-Adaptive Formation Control by Sharing Obstacle Information of a Leader UAV in Multi-UAV System," in *Proc. IEEE International Conference on Ubiquitous Robots (UR)*, 2023, [Honolulu, U.S.A](#)
4. J. Choi, **E. M. Lee**, M. Jeong, D. Choi, and H. Myung, "Range-only Relative Position Estimation for Multi-UAV," in *Proc. IEEE International Conference on Control, Automation and Systems (ICCAS)*, 2022, [Busan, Rep. of Korea](#)

5. **E. M. Lee**, et al., “CEO-MLCPP: Control-Efficient and Obstacle-Aware Multi-Layer Coverage Path Planner for 3D Reconstruction with UAVs,” in *Proc. International Conference on Robot Intelligence Technology and Applications (RiTA)*, 2022, [Gold Coast, Australia](#)
6. D. Lee, **E. M. Lee**, H. Lim, S. Song, and H. Myung, “FARO-Tracker: Fast and Robust Target Tracking System for UAVs in Urban Environment,” in *Proc. International Conference on Robot Intelligence Technology and Applications (RiTA)*, 2022, [Gold Coast, Australia](#)
7. D. Lee, **E. M. Lee**, D. Choi, J. Choi, C. Tirtawardhana, and H. Myung, “M-BRIC: Design of Mass-driven Bi-Rotor with RL-based Intelligent Controller,” in *Proc. IEEE International Conference on Ubiquitous Robots (UR)*, 2022, [Jeju, Rep. of Korea](#)
8. **E. M. Lee**, J. Jeon, and H. Myung, “TROT-Q: Traversability and Obstacle Aware Target Tracking System for Quadruped Robots,” in *Proc. Asian Control Conference (ASCC)*, 2022, [Jeju, Rep. of Korea](#)
9. S. Shin, **E. M. Lee**, J. Choi, and H. Myung, “MIR-VIO: Mutual Information Residual-based Visual Inertial Odometry with UWB Fusion for Robust Localization,” in *Proc. IEEE International Conference on Control, Automation and Systems (ICCAS)*, **Best paper Awarded**, 2021, [Jeju, Rep. of Korea](#)
10. S. Lee, S. Chang, **E. M. Lee**, J. Choi, J. Jeon, S. Kim, and H. Myung, “TPL: Trajectory Planner for Target Tracking in Low-Light Environments,” in *Proc. International Conference on Robot Intelligence Technology and Applications (RiTA)*, 2021, [Daejeon, Rep. of Korea](#)
11. C. Kim[†], **E. M. Lee**[†], J. Choi, J. Jeon, S. Kim, and H. Myung, “ROLAND: Robust Landing of UAV on Moving Platform using Object Detection and UWB based Extended Kalman Filter,” in *Proc. IEEE International Conference on Control, Automation and Systems (ICCAS)*, 2021, [Jeju, Rep. of Korea](#)
12. **E. M. Lee**, D. Seo, J. Jeon, and H. Myung, “QR-SCAN: Traversable Region Scan for Quadruped Robot Exploration using Lightweight Pre-computed Trajectory,” in *Proc. IEEE International Conference on Control, Automation and Systems (ICCAS)*, 2021, [Jeju, Rep. of Korea](#)
13. J. Choi, **E. M. Lee**, S. Shin, and H. Myung, “Solving Geometric Constraints for Relative Position Estimation using UWB Sensors in Multi-Robot System,” in *Proc. World Congress on Advances in Nano, Bio, Robotics and Energy (ANBRE21)*, 2021, [Seoul, Rep. of Korea](#)
14. D. Choi, **E. M. Lee**, and H. Myung, “Online 3D Coverage Path Planning Using Surface Vector,” in *Proc. IEEE International Conference on Ubiquitous Robots (UR)*, 2021, [Gangneung, Rep. of Korea](#)
15. **E. M. Lee**, and H. Myung, “Analysis on the performance of VIO according to Trajectory Planning of UAV,” in *Proc. IEEE International Conference on Control, Automation and Systems (ICCAS)*, 2020, [Jeju, Rep. of Korea](#)
16. **E. M. Lee**, I. Wee, T. Kim, and D. H. Shim, “Comparison of Visual Inertial Odometry using FlightGoggles Simulator for UAV,” in *Proc. IEEE International Conference on Control, Automation and Systems (ICCAS)*, 2019, [Jeju, Rep. of Korea](#)
17. Y. Jin, S. Han, **E. M. Lee**, S. M. Lee, C. Shin, and J. Yun, “Development of Autonomous Driving Systems Using State Estimator with Multi-rate Sampled-data,” in *Proc. IEEE International Conference on Consumer Electronics (ICCE)*, 2019, [Las Vegas, U.S.A](#)

DOMESTIC PAPERS

1. **E. M. Lee** and H. Myung, “Two-Stage Optimization-Based Energy-Efficient Coverage Path Planner for 3D Reconstruction,” in *Proc. Korea Robotics Society Annual Conference (KRoC)*, 2023, [Pyeongchang, Rep. of Korea](#)
2. **E. M. Lee**, D. Lee, H. Lim, S. Song, and H. Myung, “Non-uniform motion target tracking system for UAVs,” in *Proc. Korea Robotics Society Annual Conference (KRoC)*, 2022, [Pyeongchang, Rep. of Korea](#)
3. S. Jung, J. Choi, **E. M. Lee**, D. Choi, and H. Myung, “Multi-sensor based 3D Mapping for Autonomous Bridge Inspection Using Unmanned Aerial Vehicle,” in *Proc. Korea Institute of Structural Maintenance and Inspection 2020 Fall Conference (KSMI)*, 2020, [Seoul, Rep. of Korea](#)
4. **E. M. Lee**, I. Wee, T. Kim, S. Moon, and D. H. Shim, “Analysis on Visual-Inertial State Estimation(VINS-Mono) for Drone using FlightGoggles Simulator,” in *Proc. The Korean Society for Aeronautical and Space Sciences 2019 Spring Conference (KSAS)*, 2019, [Byeonsan, Rep. of Korea](#)
5. I. Wee, **E. M. Lee**, T. Kim, and D. H. Shim, “Dynamic Model Analysis of Flight Goggles Simulator and Autonomous Flight using Moving Virtual Target,” in *Proc. The Korean Society for Aeronautical and Space Sciences 2019 Spring Conference (KSAS)*, 2019, [Byeonsan, Rep. of Korea](#)
6. T. Kim, I. Wee, **E. M. Lee**, and D. H. Shim, “Vision based Gate Detection Algorithm for Autonomous Drone Racing,” in *Proc. The Korean Society for Aeronautical and Space Sciences 2019 Spring Conference (KSAS)*, 2019, [Byeonsan, Rep. of Korea](#)
7. W. Kim, **E. M. Lee**, W. Eom, S. Han, Y. Jin, and S. M. Lee, “Sampled-data control for visual servoing of 6 DOF system using TP model transformation,” in *Proc. IEMEK Symposium on Embedded Technology (ISET)*, 2018, [Jeju, Rep. of Korea](#)
8. **E. M. Lee**, S. Han, Y. Jin, W. Shin, J. Yun, and S. M. Lee, “Image based visual servoing for tracking control of a mobile robot,” in *Proc. IEMEK Symposium on Embedded Technology (ISET)*, 2018, [Jeju, Rep. of Korea](#)