



## DINH-CUONG HOANG

Nationality: Vietnamese

Gender: Male

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[ResearchGate](#)

[Google Scholar](#)

### Academic Career:

Dec 2021 – Now

Lecturer & Researcher at FPT University (Full Time)

**Teaching courses:** Programming Fundamentals (C Language); Object Oriented Programming (Java); Data Structures and Algorithms; Digital Image Processing; Advanced Computer Vision; Programming for Robotics; Robotics: Perception; Introduction of Deep Learning.

**Research Areas:** Computer vision, deep learning, robotics.

Jan 2018 – Dec 2021

Ph.D in Computer Science, Örebro University, Sweden.

[website](#)

Centre for Applied Autonomous Sensor Systems ([AASS](#)).

**Thesis:** *Vision-based Perception For Autonomous Robotic Manipulation.* [web](#) [PDF](#)

**Research interests:** My research interests lie at the intersection of computer vision, robotics, and machine learning. I am particularly interested in topics involving autonomy for robots, with a focus on perception algorithms.

**ILIAD Project:** a key member of the EU-funded research project Iliad. [website](#) [code](#) [video](#) [video](#) [video](#)

2016 – 1, 2017

Research Assistant at National Taiwan University (NTU)

**Project 1:** Automated 3D pick & place and key dimension inspection on randomly stacked workpieces. [video](#) [video](#)

**Project 2:** 3D surface reconstruction and automated robotic inspection system. [video](#)

2014 – 2015

Master of Science in Automation Technology from National Taipei University of Technology (NTUT).

**Thesis:** Multi-View 3-D surface digitization using Automated robot scanning and image registration. [video](#) [video](#)

2009 – 2014

5-year Engineering Program, Control and Automation Engineering, Hanoi University of Science and Technology.

## Research Skills:

- Practical experience in C/C++, python, ROS, Gazebo.
- Strong familiarity with 2D image and 3D point cloud processing algorithms.
- Research experience in deep learning, familiarity with Pytorch.
- Solid theoretical background of the basic concepts in robotics, computer vision, and deep learning.

## Awards and Honors:

- Fully Funded PhD Program in Computer Science, Orebro University, Sweden.
- National Taiwan University Regulations Governing Academic Research Fellowship for Outstanding International Graduate Students 2016.
- 2016 CTCI Scholarship for Oversea Graduate Students in Taiwan.
- Award for being ranked 1st among the master students graduated at the Institute of Automation Technology (2016), National Taipei University of Technology.
- The second place of Intelligent Automation Equipment Invention Award 6th 2016, Taiwan.
- Best Poster Award at International Conference on Inventions (ICI) 2015.
- The honorable award of 2015 Robot Competition for innovative smart application on industrial robot, Taiwan.
- National Taipei University of Technology Scholarship for Outstanding International Master's Students (2014-2015).

## Recent Publications

### Conference Rank A\*:

**1. Hoang, D. C.,** Stork, J. A., & Stoyanov, T. (2022). Voting and Attention-based Pose Relation Learning for Object Pose Estimation from 3D Point Clouds. *The 2022 IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS 2022)*, Kyoto, Japan, October 23-27, 2022. [PDF](#)

**2. Hoang, D. C.,** Stork, J. A., & Stoyanov, T. (2022). Context-Aware Grasp Generation in Cluttered Scenes. *IEEE International Conference on Robotics and Automation (ICRA 2022)*, Philadelphia, USA, May 23-27, 2022. [PDF](#)

**3. Hoang, D. C.,** Lilienthal, A. J., & Stoyanov, T. (2020). Panoptic 3D Mapping and Object Pose Estimation Using Adaptively Weighted Semantic Information. *IEEE International Conference on Robotics and Automation (ICRA 2020)*, Paris, France, May 31-Jun 4, 2020. [PDF](#) [code](#) [video](#)

### ISI/SCOPUS Q1:

**4. Hoang, D.C.,** Stork, J.A. and Stoyanov, T., 2022. Voting and Attention-Based Pose Relation Learning for Object Pose Estimation From 3D Point Clouds. *IEEE Robotics and Automation Letters*, 7(4), pp.8980-8987. [PDF](#)

**5. Hoang, D. C.,** Lilienthal, A. J., & Stoyanov, T. (2020). Object-RPE: Dense 3D reconstruction and pose estimation with convolutional neural networks. *Robotics and Autonomous Systems (RAS)*, 133, 103632. [PDF](#) [code](#) [video](#)

**6. Hoang, D. C.,** Lilienthal, A. J., & Stoyanov, T. (2020). Panoptic 3D Mapping and Object Pose Estimation Using Adaptively Weighted Semantic Information. *IEEE Robotics and Automation Letters (RAL)*, 5(2), 1962-19. [PDF](#) [code](#) [video](#)

**7. Hoang, D. C.,** Chen, L. C., & Nguyen, T. H. (2016). Sub-OBB based object recognition and localization algorithm using range images. *Measurement Science and Technology*, 28(2), 025401. [PDF](#) [code](#) [video](#)

*ICRA, RAL, and RAS* are top conferences and journals in robotics and artificial intelligence. Sources: [google scholar](#) and [scimagojr](#).

***Please find my full publication list on [research gate](#) or [google scholar](#).***