

Dian Wang

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EDUCATION

Northeastern University

Ph.D. in Computer Science

M.S. in Computer Science; GPA: 4.00/4.00

Sichuan University

B.Eng. in Computer Science and Engineering; GPA: 3.56/4.00

Boston, MA, USA

Jan. 2020 – Present

Sept. 2017 – Dec. 2019

Chengdu, China

Sept. 2013 – June 2017

EXPERIENCE

Boston Dynamics AI Institute

Research Intern

Cambridge, MA, USA

May. 2023 – Present

- Conduct research in solving long-horizon robotic manipulation tasks using geometric deep learning.

The Helping Hands Lab, Northeastern University

Research Assistant

Boston, MA, USA

Jan. 2018 – Present

Equivariant reinforcement learning in robotic manipulation

- Defined the symmetric properties of reinforcement learning in robotic manipulation.
- Proposed neural network architectures for improving training efficiency in robotic manipulation tasks.

BulletArm reinforcement learning environments

- Implemented an open-sourced robotic reinforcement learning environment library using PyBullet.
- Built a real-world experimental platform using a UR5 arm.

Policy learning in SE(3) action spaces

- Designed a reinforcement learning framework for robotic manipulation tasks.
- Proposed an imitation learning algorithm for large action spaces.

Assistive robotic pick-and-place system

- Built an assistive robotic system to assist people with disabilities in household manipulation tasks.
- Conducted pick-and-place experiments in an open world environment.

Institute of Computing Technology, Chinese Academy of Sciences

Research Intern

Beijing, China

July. 2016 – Aug. 2026

- Led team of 4 interns to implement a user dynamic detection app based on data from gravity sensor.

PUBLICATIONS

- 18 **Dian Wang**, Xupeng Zhu, Jung Yeon Park, Robert Platt, and Robin Walters. A general theory of correct, incorrect, and extrinsic equivariance. Under review. [Link](#)
- 17 Hai Huu Nguyen, David Klee, Andrea Baisero, **Dian Wang**, Robert Platt, and Christopher Amato. Equivariant reinforcement learning under partial observability. Under review
- 16 Haojie Huang, **Dian Wang**, Arsh Tangri, Robin Walters, and Robert Platt. Leveraging pick and place symmetries. Under review
- 15 Xupeng Zhu, **Dian Wang**, Guanang Su, Ondrej Biza, Robin Walters, and Robert Platt. On robot grasp learning using equivariant models. *Autonomous Robots*, 2023. [Link](#)
- 14 **Dian Wang**, Jung Yeon Park, Neel Sortur, Lawson L.S. Wong, Robin Walters, and Robert Platt. The surprising effectiveness of equivariant models in domains with latent symmetry. In *International Conference on Learning Representations (ICLR)*, 2023. **Spotlight**. Acceptance Rate 8%. [Link](#)
- 13 Mingxi Jia*, **Dian Wang***, Guanang Su, David Klee, Xupeng Zhu, Robin Walters, and Robert Platt. Seil: Simulation-augmented equivariant imitation learning. In *International Conference on Robotics and Automation (ICRA)*, 2023. *Equal contribution. Acceptance Rate: 43%. [Link](#)
- 12 Haojie Huang, **Dian Wang**, Xupeng Zhu, Robin Walters, and Robert Platt. Edge grasp network: A graph-based SE(3)-invariant approach to grasp detection. In *International Conference on Robotics and Automation (ICRA)*, 2023. Acceptance Rate: 43%. [Link](#)
- 11 **Dian Wang**, Mingxi Jia, Xupeng Zhu, Robin Walters, and Robert Platt. On-robot learning with equivariant models. In *Conference on Robot Learning (CoRL)*, 2022. Acceptance Rate: 39%. [Link](#)

- 10 Hai Huu Nguyen, Andrea Baisero, **Dian Wang**, Christopher Amato, and Robert Platt. Leveraging fully observable policies for learning under partial observability. In *Conference on Robot Learning (CoRL)*, 2022. Acceptance Rate: 39%. [Link](#)
- 9 **Dian Wang***, Colin Kohler*, Xupeng Zhu, Mingxi Jia, and Robert Platt. Bulletarm: An open-source robotic manipulation benchmark and learning framework. In *The International Symposium on Robotics Research (ISRR)*, 2022. *Equal contribution. Acceptance Rate 49%. [Link](#)
- 8 Haojie Huang, **Dian Wang**, Robin Walters, and Robert Platt. Equivariant transporter network. In *Robotics: Science and Systems (RSS)*, 2022. Acceptance Rate 32%. [Link](#)
- 7 Xupeng Zhu, **Dian Wang**, Ondrej Biza, Guanang Su, Robin Walters, and Robert Platt. Sample efficient grasp learning using equivariant models. In *Robotics: Science and Systems (RSS)*, 2022. Acceptance Rate 32%. [Link](#)
- 6 **Dian Wang**, Robin Walters, and Robert Platt. SO(2)-equivariant reinforcement learning. In *International Conference on Learning Representations (ICLR)*, 2022. **Spotlight**. Acceptance Rate 5%. [Link](#)
- 5 **Dian Wang**, Robin Walters, Xupeng Zhu, and Robert Platt. Equivariant Q learning in spatial action spaces. In *Conference on Robot Learning (CoRL)*, 2021. Acceptance Rate: 34%. [Link](#)
- 4 Alexander Wilkinson, Michael Gonzales, Patrick Hoey, David Kontak, **Dian Wang**, Noah Tormane, Amelia Sinclair, Zhao Han, Jordan Allspaw, Robert Platt, and Holly Yanco. Design guidelines for human-robot interaction with assistive robot manipulation systems. *Paladyn, Journal of Behavioral Robotics*, 2021. [Link](#)
- 3 Ondrej Biza, **Dian Wang**, Robert Platt, Jan-Willem van de Meent, and Lawson LS Wong. Action priors for large action spaces in robotics. In *International Conference on Autonomous Agents and Multiagent Systems (AAMAS)*, 2021. Acceptance Rate: 25%. [Link](#)
- 2 **Dian Wang**, Colin Kohler, and Robert Platt. Policy learning in SE(3) action spaces. In *Conference on Robot Learning (CoRL)*, 2020. Acceptance Rate: 34.7%. [Link](#)
- 1 **Dian Wang**, Colin Kohler, Andreas ten Pas, Alexander Wilkinson, Maozhi Liu, Holly Yanco, and Robert Platt. Towards assistive robotic pick and place in open world environments. In *The International Symposium on Robotics Research (ISRR)*, 2019. [Link](#)

PRESENTATIONS

The Surprising Effectiveness of Equivariant Models in Domains with Latent Symmetry	Kigali, Rwanda
<i>International Conference on Learning Representations (ICLR) 2023</i>	May 2023
Equivariant Learning for Robotic Manipulation	Providence, RI, USA
<i>Department of Computer Science, Brown University</i>	Apr. 2023
Equivariant Learning for Robotic Manipulation	Boston, MA, USA
<i>Boston Robotics Speaker Series, presented by Universal Robots</i>	Mar. 2023
On-Robot Learning with Equivariant Models	Auckland, New Zealand
<i>Conference on Robot Learning (CoRL) 2022</i>	Dec. 2022
Graph-Based SE(3)-invariant Approach to Grasp Detection	Auckland, New Zealand
<i>CoRL 2022 Workshop on Sim-to-Real Robot Learning</i>	Dec. 2022
SEIL: Simulation-augmented Equivariant Imitation Learning	Auckland, New Zealand
<i>CoRL 2022 Workshop on Sim-to-Real Robot Learning</i>	Dec. 2022
Equivariant Reinforcement Learning for Robotic Manipulation	Providence, RI, USA
<i>The Multi-disciplinary Conference on Reinforcement Learning and Decision Making 2022</i>	June 2022
Equivariant Q Learning in Spatial Action Spaces	New York City, NY, USA
<i>RSS 2022 Workshop on Scaling Robot Learning</i>	June 2022
SO(2)-Equivariant Reinforcement Learning for Robotic Manipulation	Philadelphia, PA, USA
<i>ICRA 2022 Workshop on Scaling Robot Learning</i>	May 2022
SO(2)-Equivariant Reinforcement Learning	Online
<i>International Conference on Learning Representations (ICLR) 2022</i>	Apr. 2022
Equivariant Q Learning in Spatial Action Spaces	Online
<i>Conference on Robot Learning (CoRL) 2021</i>	Nov. 2021
Policy Learning in SE(3) Action Spaces	Online
<i>Conference on Robot Learning (CoRL) 2020</i>	Nov. 2020

Imitation Learning with Pixel-Wise Action Parametrization*M.S. Thesis Defense, Khoury College of Computer Sciences, Northeastern University*

Boston, MA, USA

*Dec. 2019***Towards Assistive Robotic Pick and Place in Open World Environments***The International Symposium on Robotics Research (ISRR) 2019*

Hanoi, Vietnam

*Dec. 2019***TEACHING****Guest Lecture on Leveraging SE(2) Symmetries in Robot Learning***Robotics Science and Systems (Northeastern CS5335), Prof. Robert Platt**Mar. 2022***Guest Lecture on Equivariant Learning for Robotic Manipulation***Geometric Deep Learning (Northeastern CS7180), Prof. Robin Walters**Apr. 2023***MENTORING**

Mingxi Jia	M.S. at Northeastern	Now Ph.D. Student at Brown	<i>Dec. 2021 - Present</i>
Guanang Su	M.S. at Northeastern	Now Ph.D. Student at Univ. of Minnesota	<i>Dec. 2021 - Present</i>
Neel Sortur	Undergrad. at Northeastern		<i>May 2021 - Oct. 2022</i>
Zhengyi Ou	M.S. at Northeastern	Now Software Engineer at Medtronic	<i>Sept. 2020 - Dec. 2021</i>
Yida Niu	M.S. at Northeastern		<i>Sept. 2020 - Aug. 2021</i>

PROFESSIONAL SERVICE**Lead Organizer**, RSS 2023 Workshop on Symmetries in Robot Learning**Reviewer**: NeurIPS 2023. ICRA 2023, 2022, 2019. CoRL 2023, 2022. IROS 2023, 2021. RAL 2022. T-RO 2022.**HONERS & AWARDS**

2023 JP Morgan Chase PhD Fellowship	JP Morgan Chase	<i>June 2023</i>
Best Paper Award Finalist	ICRA 2022 Workshop on Scaling Robot Learning	<i>May 2022</i>
Khoury College Graduate Research Fellowship	Northeastern University	<i>Aug. 2019</i>
First Place of Outstanding Bachelor's Thesis	Sichuan University	<i>June 2017</i>

SKILLS**Programming**: Python, Java, C++**Tools**: PyCharm, IntelliJ IDEA, Git, LaTeX, Final Cut Pro**Robotics**: UR5, Baxter, Robotic Operating System (ROS), PyBullet, OpenRave**Machine Learning**: PyTorch, NumPy