Jinghuan Shang

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Education

Stony Brook University, NY, USA **2018 – Present**
Ph.D. Candidate in Computer Science, GPA: 3.98/4, Advisor: Prof. Michael S. Ryoo

Shanghai Jiao Tong University, Shanghai, China **2014 – 2018**
B.S. in Computer Science, IEEE Pilot Class

Research Interest

I am interested in creating autonomous system via imitation learning and reinforcement learning. My current research focuses on visual and sequence representation learning for robotics, with a concentration on leaning from multiple viewpoints and multiple visual modalities.

Selected Publications

1. **Shang**, **J.**, Das, S. & Ryoo, M. S. *Learning Viewpoint-Agnostic Visual Representations by Recovering Tokens in 3D Space* in *Proceedings of Conference on Neural Information Processing Systems (NeurIPS)* (2022).
2. Li, X., **Shang**, **J.**, Das, S. & Ryoo, M. S. *Does Self-supervised Learning Really Improve Reinforcement Learning from Pixels?* in *Proceedings of Conference on Neural Information Processing Systems (NeurIPS)* (2022).
3. Burgert, R., **Shang**, **J.**, Li, X. & Ryoo, M. S. *Neural Neural Textures Make Sim2Real Consistent* in *Conference on Robot Learning (CoRL)* (2022).
4. **Shang**, **J.**, Li Xiang annd Kahatapitiya, K., Lee, Y.-C. & Ryoo, M. S. StARformer: Transformer with State-Action-Reward Representations for Robot Learning. *IEEE Transactions on Pattern Analysis and Machine Intelligence* (2022).
5. **Shang**, **J.**, Kahatapitiya, K., Li, X. & Ryoo, M. S. *StARformer: Transformer with State-Action-Reward Representations for Visual Reinforcement Learning* in *European Conference on Computer Vision (ECCV)* (2022).
6. **Shang**, **J.** & Ryoo, M. S. *Self-Supervised Disentangled Representation Learning for Third-Person Imitation Learning* in *IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)* (2021).

Research Experience

Research Intern, Motional AD Inc **Aug 2022 – Present**
Trajectory Prediction

Research Assistant, Stony Brook University **May 2020 – Present**
Visual and Sequence Representation Learning for Robotics

- Viewpoint-agnostic representation learning using Transformer [1][Visual][Viewpoint][Transformer]

    - Proposed 3DTRL, a learnable, differentiable layer that learns viewpoint-agnostic representations from monocular 2D image input.
    - It improves tasks including image recognition, multi-view video alignment and action recognition.
    - It is a light-weighted, plug-and-play module that achieves improvements with minimal (2% computation and 4% parameters) overhead than Transformer backbone.
- Transformer for visual reinforcement learning and imitation learning [5] [Visual][Sequence][Transformer]
    - Adopted Transformers architecture for reinforcement learning tasks under a sequence modeling formulation.
    - Proposed StARformer, which models local representations explicitly from strongly related state, action, and reward tokens, and uses local representations for sequence prediction.
    - Results showed performance improvements over the existed Transformer-based method by over 70%, in both offline-RL and imitation learning.
    - StARformer is also highlighted for better modeling longer trajectories than the existed method.
    - StARformer outperforms the baseline by $10\% - 30\%$ in offline evaluations and $\sim 100\%$ in real-world evaluation on a human-following task.
- Third-person imitation learning for egocentric tasks [6] [Visual][Viewpoint]
    - Developed customized egocentric task environments in Minecraft (navigation) and in PyBullet (manipulation).
    - Introduced dual auto-encoders for learning joint FPV-TPV visual representation.
    - Explicitly split vector representations for disentangling agent state and third-person viewpoint representations.
    - Introduced representation permutation loss to train representations to be disentangled.
    - Results show the learned representations lead to better policies for both TPV and FPV imitation.

Professional Activities

Reviewer: CVPR2022, ECCV2022
Guest Talk: Google Inc. (2022, Transformer for Robot Learning), CSE527 Introduction to Computer Vision (Fall 2021, graduate level), CSE525 Introduction to Robotics (Spring 2022, 2021, graduate level)
Teaching Assistant: CSE548 Analysis of Algorithms (Spring 2019, graduate level), CSE564 Visualization (Spring 2020, graduate level), CSE101 Computer Science Principles (Fall 2018)

Honors and Awards

- NeurIPS 2022 Scholar Award 2022
- Merit Scholarship, Stony Brook University 2018-2019
- Outstanding Graduate of Colleges and Universities in Shanghai, China (Top 5%) 2018
- 1st Prize in China Undergraduate Mathematical Contest in Modeling 2017
- Academic Excellence Scholarship of SJTU (Top 20%) 2015, 2016, 2017

Technical Skills

Competitive Programming:[My LeetCode] Ranked 9/54 in SBU ACM ICBC Selection Contest, 2020
Programming Languages: [My Github] Python, Java, C/C++, Go, JavaScript
Technologies/Frameworks: PyTorch, Linux, Git, Tensorflow, Unity3D