

Yulun Tian

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Research Interests

I am passionate about developing **scalable and trustworthy multi-agent systems** that operate robustly over long periods of time without human intervention. My current research applies tools from nonlinear and distributed optimization, graph theory, and machine learning to develop principled **algorithms with theoretical guarantees** and **real-world systems** for multi-agent perception and navigation.

Education

- 2019 – 2023 **Ph.D. Aeronautics and Astronautics**, *Massachusetts Institute of Technology*.
- Thesis: *Algorithms and Systems for Scalable Multi-Agent Geometric Estimation*.
 - Minor concentration: Optimization Methods.
 - Cumulative GPA: 5.0/5.0.
- 2017 – 2019 **S.M. Aeronautics and Astronautics**, *Massachusetts Institute of Technology*.
- Cumulative GPA: 5.0/5.0.
- 2013 – 2017 **B.A. Computer Science**, *University of California, Berkeley*.
- Cumulative GPA: 3.94/4.0 (*High Distinction*).

Awards and Recognitions

- 2022 **King-Sun Fu Memorial Best Paper Award**, *IEEE Transactions on Robotics (T-RO)*
- 2023 **Outstanding Reviewer**, *IEEE Robotics and Automation Letter (RA-L)*
- 2021 **Honorable Mention for King-Sun Fu Memorial Best Paper Award**, *IEEE Transactions on Robotics (T-RO)*
- 2020 **Honorable Mention for Best Paper**, *IEEE Robotics and Automation Letter (RA-L)*
- 2020 **AUVSI XCELLENCE Humanitarian Award**, *Association for Uncrewed Vehicle Systems International (AUVSI)*

Experience

- Sep 2023– Present **Postdoctoral Associate**, *MIT LIDS & AeroAstro*.
My current work focuses on developing *algorithms with performance guarantees* and *real-world systems* to enable scalable and trustworthy multi-agent perception.
- Sep 2017– Aug 2023 **Graduate Research Assistant**, *MIT LIDS & AeroAstro*.
- Developed fully distributed algorithms for multi-agent SLAM with guaranteed convergence under asynchronous communication and global optimality certificates.
 - Developed distributed and outlier-robust system for multi-agent metric-semantic SLAM.
- Summer 2020 **Research Intern**, *Meta Reality Labs*.
- Researched rotation/translation averaging algorithms for global structure-from-motion.
 - Benchmarked algorithm performance using large-scale internet photo datasets.

Invited Talks

- Aug 2023 “**Multi-Agent Geometric Estimation: Algorithms and Systems**”, *NEURAL Lab, Northeastern University*.
- July 2023 “**Rotation Averaging via Fast Laplacian Solvers**”, *Spectral Graph Theoretic Methods (SGTM) Workshop, RSS 2023, [Video](#)*.
- July 2022 “**Kimera-Multi: Robust, Distributed, Dense Metric-Semantic SLAM for Multi-Robot Systems**”, *UC Berkeley Semiautonomous Seminar*.

Publications

Journal Articles

- [1] **Yulun Tian**, Yun Chang, Fernando Herrera Arias, Carlos Nieto-Granda, Jonathan P How, and Luca Carlone. “Kimera-Multi: Robust, Distributed, Dense Metric-Semantic SLAM for Multi-Robot Systems”. In: *IEEE Transactions on Robotics (T-RO)* (2022). **King-Sun Fu Memorial Best Paper Award**.
- [2] **Yulun Tian**, Ksra Khosoussi, David M Rosen, and Jonathan P How. “Distributed Certifiably Correct Pose-Graph Optimization”. In: *IEEE Transactions on Robotics (T-RO)* (2021). **Honorable Mention for King-Sun Fu Memorial Best Paper Award**.
- [3] **Yulun Tian**, Ksra Khosoussi, and Jonathan P How. “A Resource-Aware Approach to Collaborative Loop-Closure Detection with Provable Performance Guarantees”. In: *International Journal of Robotics Research (IJRR)* (2021). **Invited paper**.
- [4] **Yulun Tian**, Alec Koppel, Amrit Singh Bedi, and Jonathan P How. “Asynchronous and Parallel Distributed Pose Graph Optimization”. In: *IEEE Robotics and Automation Letters (RA-L)* (2020). **Honorable Mention for Best Paper Award**.
- [5] **Yulun Tian**, Katherine Liu, Kyel Ok, Loc Tran, Danette Allen, Nicholas Roy, and Jonathan P. How. “Search and Rescue under the Forest Canopy using Multiple UAVs”. In: *International Journal of Robotics Research (IJRR)* (2020). **Invited paper**.
- [6] Kaveh Fathian, Ksra Khosoussi, **Yulun Tian**, Parker Lusk, and Jonathan P How. “CLEAR: A Consistent Lifting, Embedding, and Alignment Rectification Algorithm for Multiview Data Association”. In: *IEEE Transactions on Robotics (T-RO)* (2020).

Conference Proceedings

- [7] **Yulun Tian**, Yun Chang, Long Quang, Arthur Schang, Carlos Nieto-Granda, Jonathan P How, and Luca Carlone. “Resilient and Distributed Multi-Robot Visual SLAM: Datasets, Experiments, and Lessons Learned”. In: *IEEE/RSJ Intl. Conf. on Intelligent Robots and Systems (IROS)*. 2023.
- [8] **Yulun Tian**, Amrit Singh Bedi, Alec Koppel, Miguel Calvo-Fullana, David M Rosen, and Jonathan P How. “Distributed Riemannian Optimization with Lazy Communication for Collaborative Geometric Estimation”. In: *IEEE/RSJ Intl. Conf. on Intelligent Robots and Systems (IROS)*. 2022.
- [9] Yun Chang, **Yulun Tian**, Jonathan P. How, and Luca Carlone. “Kimera-Multi: a System for Distributed Multi-Robot Metric-Semantic Simultaneous Localization and Mapping”. In: *IEEE Intl. Conf. on Robotics and Automation (ICRA)*. 2021.

- [10] **Yulun Tian**, Katherine Liu, Kyel Ok, Loc Tran, Danette Allen, Nicholas Roy, and Jonathan P. How. "Search and Rescue Under the Forest Canopy Using Multiple UAS". In: *Intl. Sym. on Experimental Robotics (ISER)*. 2018.
- [11] **Yulun Tian**, Kasra Khosoussi, and Jonathan P How. "Resource-Aware Algorithms for Distributed Loop Closure Detection with Provable Performance Guarantees". In: *Intl. Workshop on the Algorithmic Foundations of Robotics (WAFR)*. 2018.
- [12] **Yulun Tian**, Kasra Khosoussi, Matthew Giamou, Jonathan P How, and Jonathan Kelly. "Near-Optimal Budgeted Data Exchange for Distributed Loop Closure Detection". In: *Robotics: Science and Systems (RSS)*. 2018.
- [13] Ming Jin, Shichao Liu, **Yulun Tian**, Mingjian Lu, Stefano Schiavon, and Costas Spanos. "Indoor Environmental Quality Monitoring by Autonomous Mobile Sensing". In: *4th ACM International Conference on Systems for Energy-Efficient Built Environments*. 2017.

Preprints

- [14] **Yulun Tian** and Jonathan P. How. *Spectral Sparsification for Communication-Efficient Collaborative Rotation and Translation Estimation*. <https://arxiv.org/pdf/2210.05020.pdf>. 2022.
- [15] **Yulun Tian**, Kasra Khosoussi, and Jonathan P. How. *Block-Coordinate Minimization for Large SDPs with Block-Diagonal Constraints*. <https://arxiv.org/pdf/1903.00597.pdf>. 2019.

Theses

- [16] **Yulun Tian**. "Algorithms and Systems for Scalable Multi-Agent Geometric Estimation". PhD thesis. Massachusetts Institute of Technology, 2023.
- [17] **Yulun Tian**. "Reliable and resource-aware collaborative slam for multi-robot search and rescue". S.M. thesis. Massachusetts Institute of Technology, 2019.

Professional Activities

Journal	T-RO : IEEE Transactions on Robotics (2020–2023)
Reviewer	IJRR : International Journal of Robotics Research (2023) RA-L : IEEE Robotics and Automation Letters (2018–2023) Field Robotics (2021–2022) AIJ : Artificial Intelligence Journal (2022) AURO : Autonomous Robots (2022)
Conference	ICRA : IEEE International Conf. on Robotics and Automation (2020–2023)
Reviewer	IROS : IEEE/RSJ International Conf. on Intelligent Robots and Systems (2020–2023)
Membership	IEEE : Institute of Electrical and Electronics Engineers (2020–2023)

Skills

- Software **Languages:** C, C++, Python, MATLAB.
Robotics: ROS, Eigen, OpenCV, OpenGV, PCL.
Optimization: GTSAM, Ceres Solver, g2o, Manopt, ROPTLIB, cvx, YALMIP.
Learning: PyTorch.
- Hardware **Sensors:** RealSense, Velodyne, Ouster.
Platforms: Intel NUC, Jetson Xavier.

Software

- Kimera-Multi A complete system for *distributed* and *robust* multi-robot metric-semantic SLAM, featuring distributed loop closure, pose graph optimization, and onboard metric-semantic mapping. Implemented in C++ and ROS ([code](#)).
- dpgo A suite of distributed pose graph optimization (PGO) algorithms based on Riemannian optimization. Additional features include asynchronous communication and outlier-robust optimization. Implemented in C++ with ROS wrapper ([code](#)).

References available upon request.