

Benjamin Eisner

Curriculum Vitae

CONTACT INFORMATION	Carnegie Mellon University Pittsburgh, PA 15232	<i>Email:</i> ben.a.eisner@gmail.com <i>Site:</i> www.beisner.me
RESEARCH INTERESTS	Learning for manipulation, 3D perception, policy learning	
EDUCATION	Carnegie Mellon University , Pittsburgh, Pennsylvania USA Aug. 2020 - Aug. 2025 Ph.D. in Robotics, Robotics Institute - School of Computer Science Advisor: David Held Dissertation: <i>Deep 3D Geometric Reasoning for Robot Manipulation</i>	
	Princeton University , Princeton, New Jersey USA Sep. 2013 - Jun. 2017 Bachelor of Science in Engineering, Computer Science High Honors GPA: 3.51 Departmental GPA: 3.64	
	University College London , London UK Jan. 2016 - Jun. 2016 Affiliate Student in Computer Science	
EXPERIENCE	Tesla , Palo Alto, CA Jun. 2024 - Sep. 2024 <i>ML/Robotics Intern - Optimus</i> Manager: Julian Ibarz • Worked on a high-velocity, cross-functional ML team building Optimus's brain. • Specialized in deep learning models for visual intelligence.	
	DeepMind , London, UK Jul. 2022 - Nov. 2022 <i>Research Scientist Intern - Visual Learning for Manipulation</i> Collaborators: Jon Scholz, Yi Yang, Todor Davchev, Mel Vecerik • Researched ways to incorporate 3D visual inductive biases into large-scale robot learning systems. • Developed a provably SE(3)-Equivariant architecture for learning relative object placement tasks from demonstrations, resulting in a publication at ICLR 2024.	
	Samsung AI Center , New York, New York USA Nov. 2018 - Aug. 2020 <i>Machine Learning Research Engineer</i> Advisors: Daniel Lee, Sebastian Seung, Larry Jackel • Developed novel deep reinforcement learning algorithms for exploration in sparse environments and improved training stability, leading to a conference paper (IJCAI-PRICAI 2020) and a workshop paper (ICML 2019). • Collaborated on a project that fused traditional planning with deep learning to learn diverse manipulation behaviors, resulting two publications (including IROS 2019).	

Google, New York, New York USA **Sep. 2017 - Nov. 2018**
Software Engineer (L3 & L4) - Geo Data

- Led an organization-wide effort to test how massive data changes affected the Google Maps API.
- Developed a workflow management system for simulating world-scale launches for Google Maps and Knowledge Graph.
- Consistently managed tens of simultaneous experiments that processed petabytes of data across thousands of nodes, enabling major org-wide launches.

Princeton University, Princeton, New Jersey USA **Jan. 2015 - May 2017**
Lab Teaching Assistant

Machine Reading Lab @ UCL, London UK **Jan. 2016 - Nov. 2016**
Research Intern

Advisors: Sebastian Riedel, Tim Rocktaschel

- Researched ways to learn embeddings for new tokens based only on short, natural language descriptions, leading to a workshop publication at EMNLP 2016.
- Demonstrated quantitative improvements on downstream NLP tasks (i.e. Twitter Sentiment Classification) using learned Emoji embeddings.

Google, Kirkland, Washington USA **Jun. 2016 - Sep. 2016**
Software Engineering Intern

Microsoft, Redmond, Washington USA **Jun. 2015 - Sep. 2015**
Software Engineering Intern

Contactive, New York, New York USA **Jun. 2014 - Dec. 2014**
Software Engineering Intern

Konica Minolta Medical Imaging, Wayne, New Jersey USA **Jul. 2013 - Aug. 2013**
Software Development Intern

HONORS AND AWARDS	Best Paper Finalist, RSS 2022	2022
	NSF Graduate Research Fellowship	2020 - 2025
	High Honors, Department of Computer Science, Princeton University	2017
	Elected to Sigma Xi	2017
	Best Paper, SocialNLP Workshop at EMNLP 2016	2016
	National Merit Scholar	2013

PUBLICATIONS

2025	Saha, K., Li, A., Rodriguez-Izquierdo, Á., Yu, L., Eisner, B. , Likachev, M., Held, D. (2025). Planning from Point Clouds over Continuous Actions for Multi-object Rearrangement. CoRL 2025 - Oral (5.7%) . https://openreview.net/forum?id=XF691tY1MU
	Li, Y., Mao, X., Yuan, Y., Sim, K., Eisner, B. , Held, D. (2025). Learn from What We HAVE: History-Aware VErifier that Reasons about Past Interactions Online. CoRL 2025 . https://openreview.net/forum?id=iWMM4oxMBu

- 2024 **Eisner, B.**, Cai, E., Donca, O., Vitchutripop, T., Held, D. (2024). Sequential Object-Centric Relative Placement Prediction for Long-horizon Imitation Learning. **Learning Effective Abstractions for Planning (LEAP) Workshop @ CoRL 2024**. <https://openreview.net/forum?id=4CLiGBQV3U>
- Cai, E., Donca, O., **Eisner, B.**, Held, D. (2024). Non-rigid Relative Placement through 3D Dense Diffusion. **CoRL 2024**. <https://openreview.net/forum?id=rvKWxIvj0>
- Li, Y., Leng, W., Fang, Y., **Eisner, B.**, Held, D. (2024). FlowBotHD: History-Aware Diffuser Handling Ambiguities in Articulated Objects Manipulation. **CoRL 2024**. <https://openreview.net/forum?id=3ZAgXBRv1a>
- Eisner, B.**, Yang, Y., Davchev, T., Vecerik, M., Scholz, J., & Held, D. (2024). Deep SE(3)-Equivariant Geometric Reasoning for Precise Placement Tasks. **ICLR 2024**. <https://openreview.net/forum?id=2inBuWtyL2>
- 2023 Zhang, H., **Eisner, B.**, Held, D. (2023). FlowBot++: Learning Generalized Articulated Objects Manipulation via Articulation Projection. **CoRL 2023**. <https://sites.google.com/view/flowbotpp/home>
- Qureshi, M. N., **Eisner, B.**, Held, D. (2023). On Time-Indexing as Inductive Bias in Deep RL for Sequential Manipulation Tasks. **LmMbmG Workshop @ IROS 2023** .
- 2022 Pan, C.*, Okorn, B.*, Zhang, H.*, **Eisner, B.***, Held, D. (2022). TAX-Pose: Task-Specific Cross-Pose Estimation for Robot Manipulation. **CoRL 2022**. <https://sites.google.com/view/tax-pose/home>
- Eisner, B.***, Zhang, H.*, Held, D. (2022). FlowBot3D: Learning 3D Articulation Flow to Manipulate Articulated Objects. **Best Paper Finalist, RSS 2022**. <https://sites.google.com/view/articulated-flowbot-3d>
- Qureshi, M. N., **Eisner, B.**, Held, D. (2022). Deep Sequenced Linear Dynamical Systems for Manipulation Policy Learning. **NeurIPS 2022 Workshop**. <https://sites.google.com/view/deep-sequenced-lds>
- Narasimhan, G., Zhang, K., **Eisner, B.**, Lin, X., & Held, D. (2022) Self-supervised Transparent Liquid Segmentation for Robotic Pouring. **ICRA 2022**. <https://sites.google.com/view/transparentliquidpouring>
- 2021 Yang, D., Tosun, T., **Eisner, B.**, Isler, V., & Lee, D. (2021). Robotic Grasping through Combined image-Based Grasp Proposal and 3D Reconstruction. **ICRA 2021**. <https://arxiv.org/abs/2003.01649>
- 2020 Simmons-Edler, R., **Eisner, B.**, Yang, D., Bisulco, A., Mitchell, E., Seung, S., & Lee, D. (2020). Reward Prediction Error as an Exploration Objective in Deep RL. **International Joint Conference on Artificial Intelligence 2020 (IJCAI-PRICAI2020)**. <https://arxiv.org/abs/1906.08189>

2019	Tosun, T., Mitchell, E., Eisner, B. , Huh, J., Lee, B., Lee, D., ... & Lee, D. (2019). Pixels to Plans: Learning Non-Prehensile Manipulation by Imitating a Planner. IROS 2019 . https://arxiv.org/abs/1904.03260	
	Simmons-Edler, R.*, Eisner, B.* , Mitchell, E.*, Seung, S., & Lee, D. (2019). Q-Learning for Continuous Actions with Cross-Entropy Guided Policies. RL4RealLife Workshop, ICML 2019 . https://arxiv.org/abs/1903.10605	
2016	Eisner, B. , Rocktäschel, T., Augenstein, I., Bošnjak, M., & Riedel, S. (2016). emoji2vec: Learning emoji representations from their description. Best Paper, SocialNLP Workshop, EMNLP 2016 . https://arxiv.org/abs/1609.08359	
PRESENTATIONS	FlowBot3D: Learning 3D Articulation Flow to Manipulate Articulated Objects <i>Long Oral, Best Paper Finalist, RSS 2022</i>	2022
	Mapping Your Brain with Deep Learning <i>Internal talk at Google NYC</i>	2017
	emoji2vec: Learning emoji representations from their description. <i>SocialNLP Workshop at EMNLP 2016</i>	2016