

## EDUCATION

---

**Stanford University** 2021 – Present

**Doctor of Philosophy in Computer Science**

Advisors: Prof. Jeannette Bohg, Prof. Marco Pavone

Co-founder & President, Canadian Student Association at Stanford. Lead Organizer, Stanford AI Salon

**University of Toronto** 2016 – 2019, 2020 – 2021

**Bachelor of Applied Science in Engineering Science, Robotics**

Advisor: Prof. Florian Shkurti. Graduation with Honors, Dean's Honor List 2018 – 2021

## SELECTED RESEARCH EXPERIENCES

---

**Autonomous Systems Lab**, Stanford University Stanford, CA, USA

Graduate Researcher advised by Prof. Marco Pavone 2022-03 – Present

*Topics: (focus) reliability for generative robot policies [Site] foundation models for robot safety [Site, Site]; (involved) uncertainty quantification, out-of-distribution detection, deep offline reinforcement learning*

**Interactive Perception and Robot Learning Lab**, Stanford University Stanford, CA, USA

Graduate Researcher advised by Prof. Jeannette Bohg 2022-01 – Present

*Topics: (focus) task and motion planning with learned skills [Site] and large language models [Site, Site, Site]; (involved) imitation learning, deep reinforcement learning, constrained optimization*

## ADDITIONAL RESEARCH EXPERIENCES

---

**NASA Jet Propulsion Laboratory**, California Institute of Technology Pasadena, CA, USA

Visiting Researcher advised by Dr. Issa Nesnas and Dr. Saptarshi Bandyopadhyay 2023-06 – 2023-09

*Topics: autonomy for deep space exploration [Site]; Section 347: mobility and robotic systems*

**Stanford Vision and Learning Lab**, Stanford University Stanford, CA, USA

Graduate Researcher advised by Prof. Jiajun Wu 2021-09 – 2022-02

*Topics: neuro-symbolic models for AI task planning*

**Robot Vision and Learning Lab**, Vector Institute & University of Toronto Toronto, Canada

Undergraduate Researcher advised by Prof. Florian Shkurti 2020-05 – 2021-05

*Topics: robot task planning in structured world models with graph neural networks [Site]*

**Mobile Robotics Lab**, MILA & McGill University Montreal, QC, Canada

Research Intern co-supervised by Prof. Gregory Dudek and Prof. David Meger 2020-01 – 2020-05

*Topics: learning for visual SLAM [Paper], visual representations for reinforcement learning [Paper]*

**Noah's Ark Lab**, Huawei Research Canada Markham, ON, Canada

Deep Learning Research Intern, perception and localization with Dr. Bingbing Liu 2019-05 – 2020-05

*Topics: 3D semantic scene reconstruction [Paper], segmentation and semantic SLAM [Paper]*

**Autonomous Systems and Biomech. Lab**, University of Toronto Toronto, ON, Canada

Research Intern supervised by Prof. Goldie Nejat 2018-05 – 2018-08

*Topics: sim2real transfer for robot reinforcement learning [Paper]*

## INDUSTRY EXPERIENCES

---

**Mixed Reality and Robotics, Microsoft** Redmond, WA, USA

Software Engineering Intern on the Scene Understanding and Data Teams (HoloLens) 2021-05 – 2021-08

*Topics: bridging multi-agent reinforcement learning and mixed reality environments*

**Cloud, Google** San Francisco, CA, USA

Software Engineering Intern building ABI simulators with the Istio Networking Team 2020-05 – 2020-08

## HONORS AND AWARDS

---

<b>Clear Ventures DeepTech Fellowship</b> Awarded to promising PhD candidates and post-docs that aspire to build deep tech companies	2023
<b>Stanford School of Engineering Fellowship, Computer Science</b> Awarded to outstanding students pursuing doctoral degrees in computer science and engineering	2021
<b>Ontario Engineering Competition</b> Awarded first prize at Toronto’s district and Ontario’s provincial programming competitions	2019
<b>NSERC Undergraduate Student Research Award</b> Awarded to undergraduate science and engineering students on the basis of research aptitude	2018
<b>President’s Scholarship Program</b> Awarded to top engineering candidates pursuing studies at the University of Toronto	2016

## PUBLICATIONS

---

### REFEREED CONFERENCE PAPERS

- [1] Y. Huang, C. Agia, J. Wu, T. Hermans, and J. Bohg, “Points2plans: From point clouds to long-horizon plans with composable relational dynamics,” *2025 IEEE International Conference on Robotics and Automation (ICRA)*, 2025. [Online]. Available: <https://arxiv.org/abs/2408.14769>.
- [2] C. Agia, R. Sinha, J. Yang, Z. Cao, R. Antonova, M. Pavone, and J. Bohg, “Unpacking failure modes of generative policies: Runtime monitoring of consistency and progress,” in *8th Annual Conference on Robot Learning*, 2024. [Online]. Available: <https://arxiv.org/abs/2410.04640>.
- [3] J. Thumm, C. Agia, M. Pavone, and M. Althoff, “Text2interaction: Establishing safe and preferable human-robot interaction,” in *8th Annual Conference on Robot Learning*, 2024. [Online]. Available: <https://arxiv.org/abs/2408.06105>.
- [4] M. Bazzi, A. Shahid, C. Agia, J. Alora, M. Forgione, D. Piga, F. Braghin, M. Pavone, and L. Roveda, “Robomorph: In-context meta-learning for robot dynamics modeling,” in *International Conference on Informatics in Control, Automation and Robotics*, 2024. [Online]. Available: <https://arxiv.org/abs/2409.11815>.
- [5] R. Sinha, A. Elhafsi, C. Agia, M. Foutter, E. Schmerling, and M. Pavone, “Real-time anomaly detection and reactive planning with large language models,” in *Robotics: Science and Systems*, Outstanding Paper Award, 2024. [Online]. Available: <https://arxiv.org/abs/2407.08735>.
- [6] DROID Dataset Team, “Droid: A large-scale in-the-wild robot manipulation dataset,” in *Robotics: Science and Systems*, 2024. [Online]. Available: <https://arxiv.org/abs/2403.12945>.
- [7] Open X-Embodiment Collaboration, “Open X-Embodiment: Robotic learning datasets and RT-X models,” in *2024 IEEE International Conference on Robotics and Automation (ICRA)*, Best Paper Award, 2024. [Online]. Available: <https://arxiv.org/abs/2310.08864>.
- [8] C. Agia, G. C. Vila, S. Bandyopadhyay, D. S. Bayard, K. Cheung, C. H. Lee, E. Wood, I. Aenishanslin, S. Ardito, L. Fesq, M. Pavone, and I. A. D. Nesnas, “Modeling considerations for developing deep space autonomous spacecraft and simulators,” in *IEEE Aerospace Conference (AeroConf)*, 2024. [Online]. Available: <https://arxiv.org/abs/2401.11371>.
- [9] C. Agia, T. Migimatsu, J. Wu, and J. Bohg, “Stap: Sequencing task-agnostic policies,” in *2023 IEEE International Conference on Robotics and Automation (ICRA)*, 2023, pp. 7951–7958. DOI: 10.1109/ICRA48891.2023.10160220. [Online]. Available: <https://arxiv.org/abs/2210.12250>.
- [10] C. Agia, K. M. Jatavallabhula, M. Khodeir, O. Miksik, V. Vineet, M. Mukadam, L. Paull, and F. Shkurti, “Taskography: Evaluating robot task planning over large 3d scene graphs,” in *Proceedings of the 5th Conference on Robot Learning (CoRL)*, ser. Proceedings of Machine Learning Research, vol. 164, PMLR, 2022, pp. 46–58. [Online]. Available: <https://arxiv.org/abs/2207.05006>.
- [11] R. Cheng, C. Agia, F. Shkurti, D. Meger, and G. Dudek, “Latent attention augmentation for robust autonomous driving policies,” in *2021 IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, 2021, pp. 130–136. DOI: 10.1109/IROS51168.2021.9636449.

- [12] R. Cheng, C. Agia, Y. Ren, X. Li, and L. Bingbing, “S3cnet: A sparse semantic scene completion network for lidar point clouds,” in *Proceedings of the 2020 Conference on Robot Learning (CoRL)*, ser. Proceedings of Machine Learning Research, vol. 155, PMLR, 2021, pp. 2148–2161. [Online]. Available: <https://arxiv.org/abs/2012.09242>.
- [13] R. Cheng, C. Agia, D. Meger, and G. Dudek, “Depth prediction for monocular direct visual odometry,” in *2020 17th Conference on Computer and Robot Vision (CRV)*, IEEE Computer Society, 2020, pp. 70–77.

#### REFEREED JOURNAL PAPERS

- [1] K. Lin, C. Agia, T. Migimatsu, M. Pavone, and J. Bohg, “Text2motion: From natural language instructions to feasible plans,” *Autonomous Robots, Special Issue: Large Language Models in Robotics*, 2023. DOI: 10.1007/s10514-023-10131-7. [Online]. Available: <https://arxiv.org/abs/2303.12153>.
- [2] A. Elhafsi, R. Sinha, C. Agia, E. Schmerling, I. A. D. Nesnas, and M. Pavone, “Semantic anomaly detection with large language models,” *Autonomous Robots, Special Issue: Large Language Models in Robotics*, 2023. DOI: 10.1007/s10514-023-10132-6. [Online]. Available: <https://arxiv.org/abs/2305.11307>.
- [3] Y. Ren, B. Liu, R. Cheng, and C. Agia, “Lightweight semantic-aided localization with spinning lidar sensor,” *IEEE Transactions on Intelligent Vehicles*, vol. 8, no. 1, pp. 605–615, 2021. DOI: 10.1109/TIV.2021.3099022.
- [4] H. Hu, K. Zhang, A. H. Tan, M. Ruan, C. Agia, and G. Nejat, “A sim-to-real pipeline for deep reinforcement learning for autonomous robot navigation in cluttered rough terrain,” *IEEE Robotics and Automation Letters*, vol. 6, no. 4, pp. 6569–6576, 2021. DOI: 10.1109/LRA.2021.3093551.

#### THESIS PAPERS

- [1] C. Agia and F. Shkurti, “Contextual graph representations for task-driven 3d perception and planning,” Undergraduate Dissertation, University of Toronto, Toronto, ON, 2021. [Online]. Available: [https://drive.google.com/file/d/1LjTdgwuiJa-gIiVbbqj9vh-qoEZgqkb\\_/view?usp=sharing](https://drive.google.com/file/d/1LjTdgwuiJa-gIiVbbqj9vh-qoEZgqkb_/view?usp=sharing).

#### INVITED TALKS

---

<b>SystemX Conference, Stanford University.</b> Learning to solve long-horizon tasks	2023-11
<b>Facebook AI Research.</b> Taskography: Evaluating robot task planning over large 3d scene graphs	2021-07
<b>Microsoft Research.</b> Robot task planning in structured world models	2021-07

#### PROFESSIONAL SERVICE AND TEACHING

Journal Service: Reviewer for IJRR, RA-L

Conference Service: Reviewer for RSS, CoRL, CVPR, ICRA, IROS, ISER, AeroConf

2 x Teaching assistant for Stanford AA174A/CS137A/EE160A (2023, 2024): Principles of Robot Autonomy 1

1 x Teaching assistant for Stanford AA274B/CS237B/EE260B/ME274B (2025): Principles of Robot Autonomy 2

#### PATENTS

- Agia, C.G., Cheng, R., Ren, Y., Liu, B. (2022). *Systems and Methods for Generating a Road Surface Semantic Segmentation Map from a Sequence of Point Clouds* (U.S. Application No. 17/676,131, U.S. Patent No. 12,008,762). U.S. Patent and Trademark Office. [Google Patents link](#).
- Cheng, R., Agia, C.G., Ren, Y., Liu, B. (2022). *Methods and Systems for Semantic Scene Completion for Sparse 3D Data* (U.S. Application No. 17/492,261, U.S. Patent No. 12,079,970). U.S. Patent and Trademark Office. [Google Patents link](#).

#### COMMUNITY SERVICE AND LEADERSHIP

---

<b>Canadian Student Association</b> , Stanford University	2024-01 – Present
Co-founder and President of Stanford’s Canadian Student Association	

<b>Stanford AI Salon</b> , Stanford University	2021-10 – Present
Lead Organizer of Stanford’s AI Salon, a platform facilitating open-ended discussion between graduate students, industry, and academic leaders on contemporary ML & AI topics and their societal implications	

<b>Stanford CS Mentorship Program</b> , Stanford University	2021-10 – Present
Advising students from underrepresented and minority groups to lead fruitful careers in computer science research	

<b>Frosh Scholars Mentorship Program</b> , Stanford University	2021-10 – 2022-07
Mentoring first generation college students towards balanced progress in academics, career, and well-being	
<b>Pro Bono Research Mentoring</b>	2021-01 – Present
Guided many undergraduate research students through applications at top graduate engineering schools	
<b>NSight Student Mentorship Program</b> , University of Toronto	2018-09 – 2019-05
Provided academic, social, and personal support to first and second year Engineering Science students	

## SKILLS

---

Languages: (*Proficient*) Python, C/C#/C++, MATLAB, Rust, L<sup>A</sup>T<sub>E</sub>X, Bash - (*Working*) Java, Assembly  
 Tools: Git, Linux/Unix, Unity, Docker, Wasmtime (WebAssembly), Kubernetes  
 Libraries: PyTorch, TensorFlow, ROS, NumPy, ml-agents, PCL, OpenCV, SciPy, scikit-learn, Pandas, Jupyter