

# Aryaman Gupta

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## RESEARCH OBJECTIVE

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My research focuses on developing efficient generalist robot policies through failure-guided, closed-loop learning, and delivering safety guarantees via lightweight, context-aware guardrails at runtime. Building on my prior work in unsupervised LLM-driven robot failure analysis and safety monitoring for high-speed perception-driven systems, I now aim to develop advanced safety-assuring models that generalize across embodiments and strengthen the safety alignment of large policies, including Vision-Language-Action (VLA) models.

## EDUCATION

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- **Stanford University** Stanford, CA  
*Ph.D. in Aeronautics and Astronautics; Advisor: Somil Bansal; GPA: 4.00/4.00* *Jan 2025 – Present*
- **Stanford University** Stanford, CA  
*M.S. in Aeronautics and Astronautics; GPA: 4.00/4.00* *Jan 2025 – Dec 2026 (exp.)*
- **Indian Institute of Technology (BHU)** Varanasi, India  
*B.Tech. in Electronics Engineering; Advisor: Om Jee Pandey; GPA: 9.42/10.00* *Nov 2020 – May 2024*

## PUBLICATIONS

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- [1] **Aryaman Gupta\***, Yusuf Umut Ciftci\*, Somil Bansal, “From Perception Logs to Failure Modes: Language-Driven Semantic Clustering of Failures for Robot Safety”, *Under Review*
- [2] **Aryaman Gupta\***, Kaustav Chakraborty\*, Somil Bansal, “Detecting and Mitigating System-Level Anomalies of Vision-Based Controllers”, *ICRA ’24*
- [3] Kaustav Chakraborty, **Aryaman Gupta**, Somil Bansal, “Enhancing Safety and Robustness of Vision-Based Controllers via Reachability Analysis”, *Under Review*
- [4] A.M. Ali, **Aryaman Gupta**, H.A. Hashim, “Deep Reinforcement Learning for Sim-to-Real Policy Transfer of VTOL-UAVs Offshore Docking Operations”, *Applied Soft Computing Journal*
- [5] Neha Sharma, **Aryaman Gupta**, Sivala Deepak, Om Jee Pandey, “Node Fault Prediction Assisted Small-World IoT Networks Using ML Frameworks”, *IEEE ANTS’24* [Best Paper Award]

\*Equal Contribution

## EXPERIENCE

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- **Safe and Intelligent Autonomy Lab** Stanford, CA  
*Graduate Student | Prof. Somil Bansal* *Aug 2024 - Present*
  - **Research Area:** Safe and efficient generalist robot policies through failure-guided closed-loop learning.
  - Developed multimodal LLM-based unsupervised methods to identify and interpret robot failure modes from deployment data, enabling continual policy improvement and enhanced runtime safety monitoring.
  - Worked on safeguarding high-speed systems, such as F1-Tenth cars and drones operating under visuomotor policies, solely through perception inputs (LiDAR/camera) and no privileged information.
- **University of Southern California** Los Angeles, CA  
*Research Internship | Prof. Somil Bansal* *May 2023 - August 2024*
  - **Goal:** Provide safety guarantees on vision-based controllers leveraging knowledge of their failures.
  - Mined failure modes of an aircraft taxiing system by computing Neural Reachable Tubes (NRTs).
  - Developed a runtime vision-based failure monitor and fallback mechanisms, reducing failures by 42%.
  - Fine-tuned policy on augmented failure dataset, reducing failures by 20% and prediction error by 10%.
  - Applied Conformal Prediction for probabilistic safety guarantees enabling deployment under uncertainty.

- Carleton University** Ottawa, Canada  
*Research Internship | Prof. Hashim Mohamed* *January 2023 - December 2023*
  - **Goal:** Develop docking mechanism for VTOL-UAVs on offshore charging platforms using Deep-RL.
  - Built a custom environment for UAV landing with JONSWAP model-based hydrodynamic disturbances (waves) acting on the docking station, making it oscillate on the water surface.
  - Implemented DQN and PPO algorithms to compare performance among value and policy-based agents.
  - Agents successfully learnt to land precisely and safely through a carefully designed reward function.
- Indian Institute of Science** Bengaluru, India  
*Research Internship | Prof. Bharadwaj Amrutur* *May 2022 - July 2022*
  - **Goal:** Develop centralized multi-agent exploration and vision-aided dynamic collision avoidance systems.
  - Implemented RRT-exploration algorithm and map merging on a multi-robot fleet for collective SLAM.
  - Performed real-time map updates, detecting obstacles with 3D Object Detection through infrastructure cameras and using Gradient Descent to optimize obstacles' 3D real-world position for avoidance.
  - Developed ROS packages that can be configured and implemented on custom hardware testbeds.
- Changwon National University** Changwon, South Korea  
*Research Internship | Prof. Oh-Seol Kwon* *March 2022 - July 2022*
  - **Goal:** Develop a deep learning architecture for efficient object detection in low-resolution aerial images.
  - Combined Faster R-CNN, Edge Enhanced Network, and SRGAN architectures for the joint task.
  - Performed End-to-End Training of the entire pipeline, feeding detector's loss to SRGAN network.
  - Obtained testing accuracies of 95.5% on COWC and 83.2% on OGST datasets.

## SELECTED ACHIEVEMENTS

• Annenberg Scholarship, USC	2024
• Best Paper Award – IEEE Advanced Networks and Telecommunication Systems	2024
• Best Undergraduate Thesis – among 146 students in ECE IIT BHU	2024
• IUSSTF-Viterbi Scholarship – among top 15 students selected across India	2023
• DAAD-WISE Scholarship	2023
• Mitacs GRI Scholarship	2023
• Honourable Mention by IIT BHU for technical achievements, leadership, and student mentorship	2023
• 2nd Position – All IITs Robotics Association Challenge	2021

## SELECTED PROJECTS

- Multi-Agent Warehouse Cleaning**
  - **Goal:** Develop a Multi-Agent Coverage and Cleaning system for unknown terrains using ground robots. [\[Link\]](#)
  - Built a swarm of Omnidrive Robots and mapped the terrains using RRT-based Multi-Aobot Exploration.
  - Distributed terrain among multiple agents by computing Voronoi Cells using Fortune's Algorithm.
  - Used Polygon Planners for computing Boustrophedon Paths for each agent for complete coverage.
- UAV Swarming**
  - **Goal:** Develop PID Position Control for a swarm of multiple drones. [\[Link\]](#)
  - Used ArUco marker and Time of Flight (TOF) Lidar sensor for pose estimation with Kalman Filter for correction.
  - Implemented Cascaded PID for 3D position control and Python-based socket communication.
  - Used Flocking Algorithm for implementing swarm motion of drones in PyBullet simulation software.
- Multi-Purpose Household Robot (Supervised by Prof. Shyam Kamal, IIT BHU)**
  - **Goal:** Design a Compact Ground Robot that can perform household tasks like Cleaning and Child-Care. [\[Link\]](#)
  - Designed a CAD model and integrated ROS autonomy packages for Exploration, Navigation, and Coverage.
  - Used Computer Vision for tasks like threat detection and child tracking for child care in households.
  - Developed prototype with Jetson Nano and STM Microcontroller and using Intel Realsense for perception.

## RELEVANT COURSEWORK

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- **Graduate Courses:** AA-276 (Principles of Safety-Critical Autonomy), AA-228V (Validation of Safety-Critical Systems), AA-203 (Optimal and Learning Based Control), AA-228 (Decision Making Under Uncertainty), ENGR-205 (Introduction to Control Design Techniques), AA-242A (Classical Dynamics)
- **Undergraduate Courses:** MA-101 (Real Analysis), MA-102 (Linear Algebra), MA-202 (Probability and Statistics), CSO-102 (Data Structures and Algorithms), CSO-332 (Ubiquitous Computing), CSO-458 (Soft Computing)

## SKILLS AND INTERESTS

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- **Languages and Libraries:** Python, C++, MATLAB, Julia, JAX, Hugging Face, PyTorch, TensorFlow, Keras, scikit-learn, OpenCV, OpenAI Gym, X-Plane, CARLA
- **Technologies and Tools:** ROS, ROS2, Flightmare, AutowareAI, Open3D, Linux, Git, Docker, L<sup>A</sup>T<sub>E</sub>X

## COMMUNITY SERVICES AND INVOLVEMENTS

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- Reviewer – CoRL (2025), T-RO (2025), RA-L (2025)
- Working Group Member – Stanford Center for AI Safety
- Technical Lead – RoboReG, a student-led robotics research group at IIT BHU

## STUDENT MENTORSHIP

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- Joyce Yang (Cornell BS CS), Tito Rosas (UCLA BS ME)