

EDUCATION

- **Stanford University** Stanford, CA
Doctor of Philosophy in Aeronautics and Astronautics; GPA: 4.00/4.00 January 2025 – Present
- **Indian Institute of Technology (BHU)** Varanasi, India
Bachelor of Technology in Electronics Engineering; GPA: 9.42/10.00 November 2020 – May 2024

PUBLICATIONS

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* [\[Link\]](#)
2. **Aryaman Gupta***, Kaustav Chakraborty*, Somil Bansal, “Detecting and Mitigating System-Level Anomalies of Vision-Based Controllers”, *ICRA ’24* [\[Link\]](#)
3. Kaustav Chakraborty, **Aryaman Gupta**, Somil Bansal, “Enhancing Safety and Robustness of Vision-Based Controllers via Reachability Analysis”, *Under Review* [\[Link\]](#)
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* [\[Link\]](#)
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] [\[Link\]](#)

*Equal Contribution

EXPERIENCE

- **University of Southern California** Los Angeles, CA
Research Internship | Prof. Somil Bansal May 2023 - August 2024
 - **Goal:** Provide safety guarantees of vision-based controllers leveraging knowledge of their failure cases.
 - Prepared datasets containing failure samples labelled using Backward Reachable Tubes (BRTs).
 - Trained an Anomaly Detector to detect system failures and trigger Fallback Controller for safety.
 - BRT failure volume reduced by 40% on testing environments unseen during anomaly detector training.
 - Implemented Conformal Prediction to provide confidence guarantees on the anomaly detector.
- **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 initially accelerate downwards and then decelerate to land safely.
- **Indian Institute of Science** Bengaluru, India
Summer Research Internship | Prof. Bharadwaj Amrutur May 2022 - July 2022
 - **Goal:** Develop centralized multi-agent exploration and vision-aided dynamic obstacle avoidance systems.
 - Implemented RRT-Exploration and Map Merge on multiple ground robots in unseen environments.
 - Performed real-time map updates using 3D Object Detection with multiple infrastructure cameras and used First-Order Gradient Descent for optimizing obstacle’s 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

- Awarded the **Best Paper Award** in the IEEE Advanced Networks and Telecommunication Systems.
- Awarded the **Best Undergraduate Thesis Title** among 146 students in ECE department at IIT BHU.
- Among **Top-15** students selected across India for the **IUSSTF-Viterbi Scholarship 2023** to pursue a fully-funded summer research internship at the USC Viterbi School of Engineering.
- Awarded **DAAD-WISE Scholarship 2023** to pursue Research Internship in German Public Institutes.
- Awarded **Mitacs GRI Scholarship 2023** to pursue Research Internship in Canadian Institutes.
- Awarded **Honourable Mention** for my technical achievements and contribution in organizing competitions and workshops and mentoring students by the Science and Technology Council of IIT BHU.
- Stood **Second** in **All Indian Institutes of Technology Robotics Association 2021 Challenge** among all prestigious institutions in India for maximum coverage of warehouse using multiple agents.

RELEVANT COURSEWORK

- **Graduate Courses:** AA-276(Principles of Safety-Critical Autonomy), AA-228V(Validation of Safety-Critical Systems), AA-203(Optimal and Learning Based Control), ENGR-205(Introduction to Control Design Techniques)
- **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

- **Areas of Interest:** Safety Critical Control, Robotics, Self Driving, Reinforcement Learning, Computer Vision
- **Languages and Libraries:** Python, C++, MATLAB, OpenAI Gym, PyTorch, Tensorflow, X-Plane, Carla
- **Technologies:** ROS, ROS2, Deep Learning, Machine Learning, AutowareAI, Linux, Git, \LaTeX

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-Robot Exploration.
 - Distributed terrain among multiple agents by computing Voronoi Cells using Fortune's Algorithm.
 - Used a polygon planner for computing Boustrophedon Paths for each agent for complete coverage.
- **UAV Swarming**
 - **Goal:** Develop UAV Position Control using PID controller and implement Swarm Motion 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 for manual control.
 - Used Flocking Algorithm for a 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 packages for Exploration, Navigation, and Coverage.
 - Used Computer Vision for tasks like threat detection and child following for child care in households.
 - Developed prototype with Jetson Nano and STM Microcontroller and using Intel Realsense for perception.

COMMUNITY SERVICES AND INVOLVEMENTS

- Reviewer for CoRL, T-RO, RA-L
- Member of Stanford Center for AI Safety's Working Group
- Technical Lead of RoboReG, a student robotics research group at IIT-BHU

STUDENT MENTORSHIP

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