

Mustafa Shaikh

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Robotics and machine learning practitioner focusing on object tracking with experience in control and motion planning. I have 5 years of industry experience working closely with business stakeholders. I can dive deep into the details, and I have lead projects end to end, from identifying a problem and designing a solution, to implementation and delivery.

EDUCATION

M.S. Electrical and Computer Engineering

UNIVERSITY OF CALIFORNIA, SAN DIEGO

Specialization: Robotics and Intelligent Systems

San Diego, CA | 2022 - 2024

B.A.Sc. Engineering Science

UNIVERSITY OF TORONTO

Toronto, ON | 2013 - 2017

WORK EXPERIENCE

RESEARCH ENGINEER | SALK INSTITUTE FOR BIOLOGICAL STUDIES

San Diego, CA | 2024 -

Key Skills: Multi-object tracking, deep learning, transformers, ResNet, rotary embeddings, segmentation, Kalman filters, optical flow, Hungarian matching, camera distortion, video encoding, ffmpeg, parallel video loading

- Developed a transformer-based **multiple object tracking** system for microscopy and animal videos, achieving **>98%** tracking accuracy
- Acquired and processed public cell tracking video datasets 50x larger than in-house data
- Created a **pretrained microscopy model** that **improves key metrics** by **>40%**, and beats state of the art by **>8%**
- Implemented features to boost learning capacity and usability of the model, including: **rotary embeddings**, support for **sparsely annotated** training data, mixed dataset training, customizable **feature extractor factory**
- Optimized tracker code to reduce **GPU memory** usage by **50%** and reduce **runtime** by **30%** during inference
- Developed new **global tracking accuracy** metric to address gaps in existing multi-object tracking metrics

GRADUATE RESEARCH ASSISTANT | EXISTENTIAL ROBOTICS LAB, UC SAN DIEGO San Diego, CA | 2023 - 2024

Key Skills: Model predictive control, control barrier functions (CBF), casADi, CVX, JAX, QP, Extended Kalman Filter, RRT*, collision avoidance, ROS, Jackal robot, LiDAR, depth camera, HectorSLAM

Publication: "Control Strategies for Pursuit-Evasion Under Occlusion Using Visibility and Safety Barrier Functions" accepted at the *IEEE International Conference on Robotics and Automation (ICRA) 2025*

Preprint: <https://arxiv.org/abs/2411.01321>

- Implemented a **model predictive controller** with control barrier constraints for a robot to track a moving target
- Demonstrated **>95% tracking** in **real world experiments** with Jackal wheeled robot in a cluttered environment
- Achieved **50Hz control frequency** on the robot, including SLAM and target detection
- Implemented **Extended Kalman Filter** to estimate target's position and velocity using camera detections

DATA SCIENTIST, SR. DATA SCIENTIST | WALMART CANADA

Toronto, ON | 2019 - 2022

Key Skills: Natural Language Processing - Spacy, Named Entity Recognition, BERT, human-in-the-loop systems, AutoML, PySpark, SQL, MLOps, Python, Pandas, Numpy, Keras, Google Cloud Platform, Airflow

Project lead - Automated Attribute Assignment (Jul 2021 to Jun 2022). **Goal:** Extract product features from item descriptions to populate missing data for products on walmart.ca to improve search quality for customers

- Developed **named entity recognition pipeline** to learn **context-aware** features from product descriptions; led to **>\$1MM CAD revenue increase** annually by populating features for over 500,000 items

- Recognized need for **high quality custom annotated data**; pitched, acquired and integrated a **human-in-the-loop** annotation tool (Prodigy) with active labelling
- **Coordinated Jr. Data Scientist**, and guided the implementation of an **asynchronous orchestration layer**
- Worked closely with business stakeholders to guide problem framing, roadmap, execution and production support

Other Projects (Apr. 2019 to Jun. 2021)

- Developed and deployed **hierarchical model factory** to categorize 3rd party vendor items on walmart.ca; increased **categorization rate from 90% to 97%** which increased product views for previously 'unfindable' items
- Lead developer for data-driven, rules based online **grocery substitutions recommendation** engine; **300bps improvement in customer satisfaction**
- Created and maintained **fulfillment centre forecast** to optimize labour; >90% accuracy up from 75% previously, **>\$1MM annual labour savings** by achieving high accuracy during holiday period

PROJECTS

ROBOTICS, DEEP LEARNING AND SOFTWARE

UC SAN DIEGO, 2023-2024

Key Skills: Extended Kalman Filter (EKF), Particle Filter, IMU, LiDAR, encoder, stereo camera features, intrinsics, sensor fusion, odometry, disparity, occupancy grid, texture map, SIFT, point cloud registration, PyTorch, C++, RAI, smart pointers, design patterns, templates, variants, STL

- **Visual-Inertial SLAM** for a car with an Extended Kalman Filter using **IMU** and **stereo camera** data
- Created a color texture map of an indoor environment using **particle filter SLAM** on a robot's sensor data
- Approached the **point cloud registration** problem using **PointNet**, and achieved performance close to Iterative Closest Point, on synthetic data
- (C++) **String library** with underlying buffer manager. **Achieved 25% lower memory usage than C++ std::string** for common string operations: append, replace, insert, erase, search
- (C++) Graph-based **in-memory JSON datastore** with query capability
- (C++) **Compressing archive tool** with add, extract, retrieve capability

SKILLS

Python, C++, SQL, PyTorch, JAX, Numpy, Pandas, Keras, CVX, CasADi OpenCV, GCP, PySpark, Hadoop, Airflow, ROS, ROS2