**Sneh Acharya**

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**Education**

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| **Bachelor of Science in**    **Software Skills** | **Computer Science** | The *University of Texas at Arlington* Expected May 2025   * UTA Academic Scholarship (All 4 years) * Freshman Honor Roll (Fall 2021) |
| **Languages:** | C/C++, C#, Java, JavaScript, Python, HTML, CSS, PLC, Visual Basic, PHP, MySQL, Dart, Flutter |
| **Frameworks/Other:** | Git, Netlify, Firebase, OpenCV, NumPy, PANDAS, Cypress, Selenium, Bootstrap, WordPress |
| **Operating System:** | macOS, Windows, Ubuntu |
| **Certification:**  **Skills:**  **Language:**  **Work Experience** | Additive Manufacturing, Mechanical Design, Robotics, and Automation  Microsoft Office, SolidWorks, AutoCAD, ROS, Unity, Adobe Photoshop, Adobe Premiere, Adobe Illustrator  Fluent in English, Hindi, and Nepali |

# HERACLEIA HUMAN-CENTERED COMPUTING LAB (UTA) (http://heracleia.uta.edu)

*UNDERGRADUATE RESEARCHER March 2022 – Present*

* Making a platform for data collecting using ROS and the Summit XL robot to collect and process sensor data for autonomous navigation
* Building virtual settings with the Unity game engine to simulate investigations involving human-robot interaction
* Working on Smartphone-Based IoT-Controller Framework for Assisting the Blind in Human-Robot Interaction
* Working with Human-Robot Interactive System using Hand Gestures and Smartphone-based IoT-Controller Framework.

# MSV SERVICE SOLUTIONS (<https://www.moonlightsvc.com>)

*WEB DEVELOPER June 2021 – Present*

* Conducted preliminary discussions with clients regarding the design and functionality of the website.
* Reviewed designs and features as presented by the team.
* Leads off testing of all websites.
* Evaluated the state of readiness of websites before turning over the project to the client.

**DFW SHREE KRISHNA PRANAMI HINDU SAMAJ TEXAS (**[**https://dfwskpm.org**](https://dfwskpm.org)**)**

*WEB DEVELOPER April 2019 – August 2021*

# made code fixes and customized the corporate website, I used a variety of technologies, including JavaScript.

# Prior to going online, I tested websites and conducted user testing and troubleshooting.

# Requirements were analyzed, and software applications were planned, created, and implemented.

# Projects

* **Capital One – Budgeting App | Flutter Flow (UI Design), Flutter, Dart, and Google Firebase |**

**HackUTD IX |** [**https://github.com/sneh-ach/Capital-One-Budgeting-App**](https://github.com/sneh-ach/Capital-One-Budgeting-App)

* Designed, implemented, and tested Flutter and Dart code using BLoC pattern for IOS, Android and Web.
* ﻿﻿Designed and created custom -form features including scrolling selectors and data entries.
* Used Visual Studio Code and android studio as the primary IDE to develop, test and deploy the Android

application and Dart as programming language.

* ﻿﻿Used GitHub to manage Git repositories and versioning control.
* **Towards a Teleoperated Multimodal Human Robot Interactive SLAM using Smartphone based IoT-Controller Framework** **| Research Paper | Heracleia Human-Centered Computing Lab (**[**http://heracleia.uta.edu**](http://heracleia.uta.edu))

Through this system, humans are added in the loop to build SLAM map where they send commands through IoT-Controller

Framework to add and change locations, creating a Human Robot Interactive (HRI) SLAM map on top of 2D SLAM map. The

HRI SLAM can be used by robot to navigate to locations, when users issue navigation command. Preliminary experiments

conducted in lab environment showed that the HRI SLAM can be built and updated, using user voice and text commands.

Adding or changing a location in SLAM map took an average time of 9.7 seconds while the robotic system took an average

time of 40.96 seconds to complete a navigation task using SLAM map with an average distance error of 10.4 cm.

* **Smartphone-Based IoT Framework for Assisting the Blind in Human-Robot Interaction | Research Paper |**

**Heracleia Human-Centered Computing Lab (**[**http://heracleia.uta.edu**](http://heracleia.uta.edu))

Smartphone-based IoT-controller framework is proposed to assist visually impaired users with effective interaction with robots in a human-robot interaction scenario. The user can access a smartphone application through speech, give commands for a pick and place task, and the robot performs the task based on the user’s speech command. This preliminary work aims to implement the general controller framework and test the integration with the robotic system.

* **Indoors Traversability Estimation with Less Labels for Mobile Robots | Research Paper |  
  Heracleia Human-Centered Computing Lab (**[**http://heracleia.uta.edu**](http://heracleia.uta.edu))  
    
   This project aims to determine indoor traversability estimation using only RGB images through the prism of binary image   
   classification. Our proposed method exploits the power of a pre- trained Vision Transformer (ViT) which we fine-tune on   
   our own collected small dataset. Through experimentation, we show that the performance of our fine-tuning method achieves   
   high levels of accuracy and generalization and outruns well-established state-of-the-art deep architecture for image classification   
   such as ResNet.

# Assessment of Cognitive Fatigue from Gait Cycle Analysis Robots | Research Paper | Heracleia Human-Centered Computing Lab (<http://heracleia.uta.edu>)

# The proposed system in this paper takes two asynchronous videos of the gait of individuals to classify if they are cognitively

# fatigued or not. We leverage the pose estimation library OpenPose, to extract the body keypoints from the frames in the videos.

# To capture the spatial and temporal information of the gait cycle, a CNN-based model is used in the system to extract the embedded

# Features which are then used to classify the cognitive fatigue level of individuals. To train and test the model, a gait dataset is built

# from 21 participants by collecting walking data before and after inducing cognitive fatigue using clinically used games. The proposed

# model can classify cognitive fatigue from the gait data of an individual with an accuracy of 81

* **A Shared Control Teleoperation Framework for Mobile Robots in In-doors Environments Utilizing Control**   
  **Barrier Functions in Virtual Reality | Research Paper |  
  Heracleia Human-Centered Computing Lab (**[**http://heracleia.uta.edu**](http://heracleia.uta.edu))

This paper describes a novel shared control teleoperation frame- work for mobile robots that utilizes Control Barrier Functions   
 (CBFs) as filtering mechanism to prevent a human operator from making dangerous actions. The proposed framework demonstrates   
 the potential to create a CBF controller that enables users with no prior knowledge of robotics to safely tele-navigate mobile robots   
 with limited situational awareness. As formal methods, we utilize a hand-crafted CBF, which acts as a repulsive field to describe  
 unsafe regions withing the robot’s vicinity. The implementation of the application was deemed possible by creating a Virtual Reality  
 (VR)simulation in the Unity Engine with the SUMMIT-XL STEEL mobile base as an experimental platform. Preliminary experimental  
 results show the ability of the framework to enable safe teleoperation.

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