Neel P. **Bhatt**

POSTDOCTORAL FELLOW · CENTER FOR AUTONOMY · ODEN INSTITUTE

The University of Texas at Austin, Texas, USA

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Research Interests

Neuro-symbolic AI, Assured Active Perception & Prediction, Computer Vision, Autonomous Systems, State Estimation, Sequential Decision-Making.

Education

University of Waterloo
Sept 2018 - May 2023

Doctor of Philosophy (PhD) - Mechatronics Engineering (Advisors: A Khajepour and E Hashemi)   *Waterloo, ON - Canada*

- Research focus: Spatially-aware multi-agent object motion prediction for autonomous driving using RL and potential fields
- Project Lead: WATonoBus: First Canadian all weather autonomous shuttle in operation on public roads
- Head Course TA for ME780: Autonomous Driving
- **Courses:** ML, RL, DL, Robotics, Autonomous Driving, Adaptive Control, Tools for Software Eng., Mechatronics System Integration

University of Toronto
Sept 2014 - June 2018

Bachelor of Applied Science (BASc) with High Honours - Mechanical Eng. - Robotics Minor - GPA: 3.97/4   *Toronto, ON - Canada*

- Among the **top 3** winners for the capstone design project competition across the department
- Ranked in the **top 5%** of all students in the department
- **Courses:** Robotics, Mechatronics Principles, Mechatronics Systems: Design and Integration, Control Systems

Experience

The University of Texas at Austin
Sept 2023 - Present

Postdoctoral Research Fellow, Center for Autonomy, Oden Institute   *Austin, TX - USA*

- Working with Professor Atlas Wang and Ufuk Topcu as a part of the Autonomous Systems Group and the VITA Research Group at the University of Texas at Austin.
- Research centered at developing neuro-symbolic architectures for generative AI, trustworthy sequential decision-making using multi-modal foundational models, and assured active perception for autonomous systems.
- Developing neuro-symbolic perception and planning architectures for DARPA Assured Neuro Symbolic Learning and Reasoning (ANSR) project.

University of Waterloo
Sept 2018 - Sept 2023

Lead Research Scientist, WATonoBus Autonomous Shuttle   *Waterloo, ON - Canada*

- Developed and implemented hardware and software architecture for perception, prediction, and decision-making including auto startup launch scripts, custom packages and drivers (Python/C++), multi-sensor fusion, system integration (ROS), and visualization.
- Led a team of several graduate students achieving permit for daily operation and testing on public roads as part of ministry's pilot program.

University of Alberta
Jan 2021 - Present

Visiting Research Scholar, NODE Lab   *Edmonton, AB - Canada*

- Worked with Professor Ehsan Hashemi on several research projects covering RL-based decision making for human-autonomous system handover, visual and interial odometry, SLAM, object detection, cooperative perception, and supervised several graduate students.
- Developed and implemented hardware and software architecture for NODE Lab's autonomous vehicle.

General Motors R&D
May 2019 - Sept 2019

AV Software Engineering Intern, GM Global R&D Tech Center   *Detroit, MI - USA*

- Designed and implemented a novel real-time supervisory DL framework for vehicle velocity estimation consisting of a LSTM-based network architecture achieving > 95% accuracy on a large test set (Python, PyTorch) – ROI for patent submitted.
- Automated data generation and augmentation to ensure class balance and generalizability.

WATonomous Self-Driving Vehicle
May 2018 - Aug 2019

Perception Team Core Member, GM AutoDrive Challenge   *Waterloo, ON - Canada*

- Worked on the WATonomous self-driving vehicle, training TensorFlow based object detection models with data augmentation to classify traffic lights and achieved higher accuracy on test images specific to application.

Clearpath Robotics
May 2017 - Sept 2017

Applications Engineering Intern, Research and Development Center   *Waterloo, ON - Canada*

- Conducted robot simulations with Gazebo and ROS for line/person following demos presented at IROS 2017.
- Design focused on addressing needs of robot autonomy team for effective image processing, recognition, and control.

University of Toronto   *May 2016 - Sept 2016*

Research Intern, Robotics Institute (NSERC USRA)   *Toronto, ON - Canada*

- Worked with Professor Yu Sun at the Robotics Institute, specifically at the Advanced Micro and Nanosystems Lab.
- Designed and fabricated an easy to use and maintain system for vibration and acoustic isolation of one of a kind Atomic Force Microscope (AFM) with resolution better than 0.05 nm.

University of Toronto   *May 2015 - Sept 2015*

Research Intern   *Toronto, ON - Canada*

- Worked with Professor Chul B. Park and analyzed discrete event procedures and algorithms, studied mathematical structures behind, and designed experiments toward parametric study and simulation of relevant parameters that govern the geometry of cellular plastic structures.

Publications

* Denotes equal contribution and co-first authorship

Journal Articles

[J1] **DynaNav-SVO: Dynamic Stereo Visual Odometry With Semantic-Aware Perception for Autonomous Navigation**
Marcelo Cabrera, **Neel P. Bhatt**, Ehsan Hashemi
IEEE Transactions on Intelligent Vehicles (T-IV), 2024

[J2] **A Survey on 3D Object Detection in Real-time for Autonomous Driving**
Marcelo Cabrera, Aayush Jain, **Neel P. Bhatt**, Arunava Banerjee, Ehsan Hashemi
Frontiers in Robotics and Artificial Intelligence, 2024

[J3] **Consensus-Based Information Filtering in Distributed LiDAR Sensor Network for Tracking Mobile Robots**
Isabella Luppi, **Neel P. Bhatt**, Ehsan Hashemi
Sensors, 2024

[J4] **Object Reconstruction and Localization in Indoor Environments Using Infrastructure Sensor Node**
Soham Dasgupta, Venkata Devarakonda, Yifeng Cao, Minghao Ning, **Neel P. Bhatt**, Yufeng Yang, Ehsan Hashemi, Amir Khajepour
IEEE Sensors Journal, 2024

[J5] **MPC-PF: Socially and Spatially Aware Object Trajectory Prediction for Autonomous Driving Systems Using Potential Fields**
Neel P. Bhatt, Amir Khajepour, Ehsan Hashemi
IEEE Transactions on Intelligent Transportation Systems (T-ITS), 2023

[J6] **Integrated Inertial-LIDAR based Map Matching Localization for Varying Environments**
Xin Xia, **Neel P. Bhatt**, Amir Khajepour, Ehsan Hashemi
IEEE Transactions on Intelligent Vehicles (T-IV), 2023

[J7] **Infrastructure-Aided Localization and State Estimation for Autonomous Mobile Robots**
Daniel Flögel, **Neel P. Bhatt**, Ehsan Hashemi
Robotics, 2022

Conference Papers

[C1] **Fine-Tuning Language Models Using Formal Methods Feedback: A Use Case in Autonomous Systems**
Yunhao Yang*, **Neel P. Bhatt***, Tyler Ingebrand*, William Ward, Steven Carr, Zhangyang Wang, Ufuk Topcu
Conference on Machine Learning and Systems (MLSys), 2024, Santa Clara, USA

[C2] **MM3DGS SLAM: Multi-modal 3D Gaussian Splatting for SLAM Using Vision, Depth, and Inertial Measurements**
Lisong C. Sun*, **Neel P. Bhatt***, Jonathan C. Liu, Zhiwen Fan, Zhangyang Wang, Todd E. Humphreys, Ufuk Topcu
IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), 2024, Abu Dhabi, UAE

[C3] **Fine-Tuning Language Models Using Formal Methods Feedback**
Yunhao Yang*, **Neel P. Bhatt***, Tyler Ingebrand*, William Ward, Steven Carr, Zhangyang Wang, Ufuk Topcu
Neuro-Symbolic Learning and Reasoning in the Era of Large Language Models (NucLeaR) @ AAAI, 2024, Vancouver, Canada

[C4] **A Stereo Visual Odometry Framework with Augmented Perception for Dynamic Urban Environments**
Marcelo Cabrera, **Neel P. Bhatt**, Ehsan Hashemi
IEEE Intelligent Transportation Systems Conference (ITSC), 2023, Bizkaia, Spain

[C5] **MPC-PF: Social Interaction Aware Trajectory Prediction of Dynamic Objects for Autonomous Driving Using Potential Fields**
Neel P. Bhatt, Amir Khajepour, Ehsan Hashemi
IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), 2022, Kyoto, Japan

[C6] **Augmented Visual Localization Using a Monocular Camera for Autonomous Mobile Robots**
Ali Salimzadeh, **Neel P. Bhatt**, Ehsan Hashemi
IEEE International Conference on Automation Science and Engineering (CASE), 2022, Mexico City, Mexico

[C7] **Real-time Pedestrian Localization and State Estimation Using Moving Horizon Estimation**
Ehsan Mohammadbagher*, **Neel P. Bhatt***, Ehsan Hashemi, Baris Fidan, Amir Khajepour
IEEE Intelligent Transportation Systems Conference (ITSC), 2020, Rhodes, Greece

Preprints

[P1] **Comp4D: LLM-Guided Compositional 4D Scene Generation**
Dejia Xu, Hanwen Liang, **Neel P. Bhatt**, Hezhen Hu, Hanxue Liang, Konstantinos N Plataniotis, Zhangyang Wang

Under submission, 2024

[P2] WATonoBus: An All Weather Autonomous Shuttle
Neel P. Bhatt, Ruihe Zhang, Minghao Ning, Alghooneh Ahmad, Chen Sun, Pouya Panahandeh, Ehsan Mohammadbagher, Ted Ecclestone, Ben MacCallum, Ehsan Hashemi, Amir Khajepour
Under submission, 2024

[P3] Monocular Vision-based State Estimation for Autonomous Navigation using Gaussian Processes
Yunchen Ge, **Neel P. Bhatt**, Ehsan Hashemi
Under submission, 2024

[P4] RNDT: LiDAR-based Navigation using Normal Distributions Transform Filter
Ali Shafiezadeh, **Neel P. Bhatt**, Ehsan Hashemi
Under submission, 2024

[P5] Soft Constrained Autonomous Vehicle Navigation using Gaussian Processes and Instance Segmentation
Bruno H. Groenner Barbosa, **Neel P. Bhatt**, Amir Khajepour, Ehsan Hashemi
arXiv preprint - arXiv:2101.06901

Thesis

[T1] Socially and Spatially Aware Motion Prediction of Dynamic Objects for Autonomous Driving
Neel P. Bhatt
University of Waterloo, 2023

Invited Talks

Fine-tuning Language Models Using Formal Methods Feedback
Invited Talk at Hewlett Packard AI Labs, 2024
Invited Talk at DESTION Workshop, 2024
Industry Talk for Lockheed Martin Artificial Intelligence Center - Assured Autonomy Systems, 2024
Invited Talk at Autonomous Mobile Robotics Lab, 2023

MM3DGS SLAM: Multi-modal 3D Gaussian Splatting for SLAM Using Vision, Depth, and Inertial Measurements
Poster Presentation at National AI Institute for Foundations of Machine Learning (IFML), 2024
Industry Talk at NXP Innovation Lab, 2024
Poster Presentation at Machine Learning Lab Symposium, 2024
Poster Presentation at 6G@UT Fourm, 2024 and 2023

DARPA Assured Neuro Symbolic Learning and Reasoning (ANSR) PI Meetings
Research Talk at CMU, 2024
Research Talk at UC Berkeley, 2023

Reliable State Estimation and Distributed Controls in Intelligent Vehicular Networks
Tutorial Presenter and Organizer for IEEE Intelligent Vehicles (IV), 2023

WATonoBus - Algorithms and Software Structure for an All Weather Shuttle
Guest Lecture for ECE495 at University of Waterloo, 2023

Object Detection with ROS and OpenCV, Multi-Modal Data Acquisition, and Visualization
Guest Lecture for MECE788 at University of Alberta, 2023

An Overview of the WATonoBus - Canada's First Autonomous 5G Shuttle
Guest Lecture at University of Waterloo, 2022

Awards

Queen Elizabeth II Graduate Scholarship in Science and Technology (QEII-GSST)   *2022 - 2023 & 2019 - 2020*
Government of Ontario   *Waterloo, ON - Canada*
QEII-GSST is a merit-based scholarship program based on academic excellence, research ability and potential in program of study, and communication and leadership abilities targeted specifically towards students in a research-based graduate program in STEM disciplines.

Ontario Graduate Scholarship (OGS)   *2021 - 2022 & 2020 - 2021*
Government of Ontario   *Waterloo, ON - Canada*
OGS is a merit-based scholarship program for Ontario's best graduate students in all disciplines of academic study.

Engineering Excellence Doctoral Fellowship (EEDF)   *2020 - 2021*
University of Waterloo   *Waterloo, ON - Canada*
EEDF is awarded to student researchers who were admitted directly to the PhD program from a Bachelor's degree.

NSERC Industrial Experience Award   *May 2017 - Sept 2017*
National Sciences and Engineering Research Council (NSERC)   *Waterloo, ON - Canada*
Received for conducting R&D at Clearpath Robotics as part of an internship.

NSERC Undergraduate Research Award *May 2016 - Sept 2016*
National Sciences and Engineering Research Council (NSERC) *Toronto, ON - Canada*
Received for conducting research with Professor Yu Sun during undergradute studies.

President's Scholar Award *2014 - 2015*
University of Toronto *Toronto, ON - Canada*
Received for being one of the top 150 highly qualified students applying to first year of direct-entry undergraduate studies.

Service

Reviewing	**CoRL** (2024), **ECCV** (2024), **CVPR** (2024), **T-ITS** (2020,2021,2022,2023,2024), **IROS** (2022,2023,2024), **ICRA** (2021,2022,2023) **ITSC** (2020,2023,2024), **IV** (2020,2021,2023,2024), **ICORR** (2022), **SMCS** (2022,2023), **MSSP** (2023)
Committee	Associate Editor, Awards Committee, and Publicity Chair **ITSC** (2024)
Fellowships	MITACS Accelerate (2021-2022)
Tutorials	Reliable State Estimation and Distributed Controls in Intelligent Vehicular Networks (ITSC 2023)

Patents

Monocular Camera System Performing Depth Estimation of Objects Surrounding a Vehicle
US Patent Application No.: P104140-PRI-NP-US01, Filing Date: March 29, 2023

Deep Learning Supervisory Framework for Vehicle State Estimation
Patent Application Pending, ROI Filing Date: September 1, 2019

Skills

Machine Learning	Pytorch, TensorFlow, Keras, OpenCV, scikit-learn.
Programming	Python, C++, ROS, CUDA, Linux, Shell (Bash/Zsh), LaTeX, Markdown, Firebase, Git.
Simulation and Design	OpenAI Gym, CARLA, AirSim, Unreal, Gazebo, Simulink, SolidWorks, MasterCAM.
Hardware Interfacing	LIDARs, Cameras, RADARs, GNSS, IMU, Embedded Computing (NVIDIA Jetsons), Time Sync., CAN Bus, Arduino.