Ragib Arnab

U.S. Citizen

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ragibarnab.com | github.com/ragibarnab

Research Interests

Interested in researching AI that is more efficient and robust while requiring little supervision. Areas of interest: self-supervised learning, video understanding, energy-based models, neuromorphic computing

| Education | |
|---|----------------------|
| The University of Texas at Dallas – Bachelor of Science in Computer Science | May 2024 |
| Relevant Coursework: Machine Learning, Intelligent Systems | GPA: 3.77 |
| Experience | |
| Post Bachelors Student, Information Sciences (CCS-3) | Oct 2024 – Present |
| Los Alamos National Laboratory | Los Alamos, NM |
| • Conducting research on spatio-temporal learning to develop foundational models for | scientific computing |
| Mentors: <u>Dr. Garrett Kenyon</u> , <u>Dr. Michal Kucer</u> | |
| Technical Intern, AI and Data Analytics | May 2023 – Aug 2023 |
| Pacific Northwest National Laboratory | Seattle, WA |
| • Developed an object detection pipeline for aerial drones equipped with event camera | S |
| Mentor: <u>Dr. Yijing Watkins</u> | |
| Undergraduate Student, Information Sciences (CCS-3) | Jun 2022 – May 2023 |
| Los Alamos National Laboratory | Los Alamos, NM |
| • Applied sparse coding on the task of lidar depth completion for autonomous driving | |
| Mentor: <u>Dr. Garrett Kenyon</u> | |
| Publications | |

- D. Hannan, R. Arnab, G. Parpart, G. Kenyon, E. Kim, and Y. Watkins, "Event-to-video conversion for overhead object detection," IEEE Southwest Symposium on Image Analysis and Interpretation (SSIAI) 2024. Available: <u>https://arxiv.org/abs/2402.06805</u>
- **R. Arnab**, G. Kenyon, "Sparse Coding for Depth Completion on Autonomous Vehicles [Slides]," 2022. Available: <u>https://doi.org/10.2172/1985006</u>

Projects

Nova, Applied Systems Lab at UT Dallas

- Worked as a software developer on an open-source self-driving project
- Developed lidar mapping, localization, and SLAM systems
- Integrated 3D object detection and tracking software
- Advisor: Prof. Justin Ruths

Visual SLAM

- Built a monocular visual SLAM system to map unknown environments using video footage
- Utilized OpenCV functions for visual odometry
- Applied g2o graph optimization library for bundle adjustment

Skills

ProgrammingPython, C++, C, Java, MATLAB, SQLSoftwarePyTorch, NumPy, pandas, Matplotlib, OpenCV, g2o, ROS 2, Git, Linux, MySQL, AWS EC2/S3/RDS