

**THE UNIVERSITY OF TEXAS AT AUSTIN**  
**Cockrell School of Engineering**  
**Resume**

**FULL NAME:** David Fridovich-Keil      **TITLE:** Assistant Professor

**DEPARTMENT:** Aerospace Engineering and Engineering Mechanics

**EDUCATION**

Princeton University	Electrical Engineering	B.S.E.	2015
University of California, Berkeley	Electrical Engineering & Computer Sciences	Ph.D.	2020

**CURRENT AND PREVIOUS ACADEMIC POSITIONS**

Assistant Professor, The University of Texas at Austin      August 2021 - present  
 Department of Aerospace Engineering and Engineering Mechanics  
 Director of the Control and Learning for Autonomous Robotics (CLeAR) Lab

Post-Doctoral Researcher, Stanford University      September 2020 - June 2021

Post-Doctoral Researcher, University of California, Berkeley      June 2020 - August 2020

Graduate Research Assistant, University of California, Berkeley      August 2017 - May 2020

**OTHER PROFESSIONAL EXPERIENCE**

Software Engineer, Nuro Inc.      Summer 2018  
 Motion planning and prediction algorithm development for autonomous vehicles.

Software Engineer, Applied Science & Technology Research Institute      Summer 2014  
 Image processing for consumer electronics.

Embedded Systems Engineer, Sentinel Photonics      Summer 2013  
 Signal processing for lightweight, high-precision gas sensing.

**MEMBERSHIPS IN PROFESSIONAL AND HONORARY SOCIETIES**

Member, Institute of Electrical and Electronics Engineers (IEEE)

**PROFESSIONAL SOCIETY AND MAJOR GOVERNMENTAL COMMITTEES,  
 EDITORIAL BOARDS, AND CONFERENCES ORGANIZED/CHAired**

**Conference Activities: Organizer**

Organizer, Workshop on Robust Autonomy: Tools for Safety in Real-World Uncertain Environments,  
 Robotics: Science & Systems, 2019-2021

**OTHER PROFESSIONAL HIGHLIGHTS**

**Current Review Activities**

IEEE Transactions on Automatic Control

IEEE Transactions on Robotics

IEEE Transactions on Intelligent Vehicles  
 Optimization Methods and Software  
 Robotics: Science & Systems  
 IEEE Robotics and Automation Letters  
 IEEE International Conference on Robotics and Automation  
 IEEE Conference on Decision and Control  
 IEEE Conference on Control Technology and Applications  
 Learning for Dynamics and Control  
 American Control Conference  
 Advances in Neural Information Systems  
 International Conference on Learning Representations

## UNIVERSITY COMMITTEES/ADMINISTRATIVE ASSIGNMENTS

### Texas Robotics

Core Robotics Faculty Committee, 2021-present

## HONORS AND AWARDS

Demetri Angelakos Memorial Achievement Award, 2020  
 Robotics: Science & Systems Pioneer, 2019  
 Top Reviewer at NeurIPS, 2019  
 Outstanding Graduate Student Instructor, 2018  
 Charles Ira Young Memorial Prize, 2015  
 G. David Forney Jr. Prize, 2015  
 James Hayes-Edger Palmer Prize, 2015  
 NSF Graduate Research Fellowship, 2015

## PUBLICATIONS

### Refereed Journal Publications in Rank as Assistant Professor and Earlier

- J1 D. R. Anthony, D. Fridovich-Keil, and J. F. Fisac, “Back to the future: Efficient, time-consistent solutions in reach-avoid games,” *Robotics and Automation Letters* (under review), 2022 [pdf](#)
- J2 F. Laine, D. Fridovich-Keil, C.-Y. Chiu, and C. Tomlin, “The computation of approximate generalized feedback nash equilibria,” *SIAM Journal on Optimization* (under review), 2022 [pdf](#)
- J3 E. Rolf\*, D. Fridovich-Keil\*, M. Simchowitz, B. Recht, and C. J. Tomlin, “A successive-elimination approach to adaptive robotic sensing,” *IEEE Transactions on Robotics*, 2020 [pdf](#)
- J4 D. Fridovich-Keil\*, A. Bajcsy\*, J. F. Fisac, S. L. Herbert, S. Wang, A. D. Dragan, and C. J. Tomlin, “Confidence-aware motion prediction for real-time collision avoidance,” *International Journal of Robotics Research*, 2019 [pdf](#)
- J5 R. Dobbe, O. Sondermeijer, D. Fridovich-Keil, D. Arnold, D. Callaway, and C. J. Tomlin, “Towards distributed energy services: Decentralizing optimal power flow with machine learning,” *IEEE Transactions on Smart Grid*, 2019 [pdf](#)

### Refereed Conference Proceedings

- C1 J. Li, D. Fridovich-Keil, S. Sojoudi, and C. Tomlin, “Augmented lagrangian method for instantaneously constrained reinforcement learning problems,” in *IEEE Conference on Decision and Control (CDC)*, 2021

- C2 L. Peters, D. Fridovich-Keil, V. Rubies-Royo, C. Tomlin, and C. Stachniss, “Inferring objectives in continuous dynamic games from noise-corrupted partial state observations,” in *Robotics: Science and Systems*, 2021 [pdf](#)
- C3 D. Fridovich-Keil and C. J. Tomlin, “Approximate solutions to a class of reachability games,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2021 [pdf](#)
- C4 C.-Y. Chiu\*, D. Fridovich-Keil\*, and C. J. Tomlin, “Encoding defensive driving as a dynamic nash game,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2021 [pdf](#)
- C5 F. Laine, D. Fridovich-Keil, C.-Y. Chiu, and C. J. Tomlin, “Multi-hypothesis interactions in game-theoretic motion planning,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2021 [pdf](#)
- C6 T. Westenbroek, E. Mazumdar, D. Fridovich-Keil, V. Prabhu, C. J. Tomlin, and S. S. Sastry, “Adaptive control for linearizable systems using on-policy reinforcement learning,” in *IEEE Conference on Decision and Control (CDC)*, 2020 [pdf](#)
- C7 D. Fridovich-Keil\*, V. Rubies-Royo\*, and C. J. Tomlin, “An iterative quadratic method for general-sum differential games with feedback linearizable dynamics,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2020 [pdf](#)
- C8 D. Fridovich-Keil, E. Ratner, L. Peters, A. D. Dragan, and C. J. Tomlin, “Efficient iterative linear-quadratic approximations for nonlinear multi-player general-sum differential games,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2020 [pdf](#)
- C9 L. Peters, D. Fridovich-Keil, C. J. Tomlin, and Z. Sunberg, “Inference-based strategy alignment for general-sum differential games,” in *International Conference on Autonomous Agents and Multiagent Systems (AAMAS)*, 2020 [pdf](#)
- C10 T. Westenbroek\*, D. Fridovich-Keil\*, E. Mazumdar\*, S. Arora, V. Prabhu, S. S. Sastry, and C. J. Tomlin, “Feedback linearization for unknown systems via reinforcement learning,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2020 [pdf](#)
- C11 V. Rubies-Royo, D. Fridovich-Keil, S. L. Herbert, and C. J. Tomlin, “A classification-based approach for approximate reachability,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2019 [pdf](#)
- C12 S. L. Herbert\*, A. Bajcsy\*, D. Fridovich-Keil, J. F. Fisac, S. Deglurkar, A. D. Dragan, and C. J. Tomlin, “A scalable framework for real-time multi-robot, multi-human collision avoidance,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2019 [pdf](#)
- C13 D. Fridovich-Keil\*, J. F. Fisac\*, and C. J. Tomlin, “Safely probabilistically complete real-time planning and exploration in unknown environments,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2019 [pdf](#)
- C14 J. F. Fisac\*, A. Bajcsy\*, S. L. Herbert, D. Fridovich-Keil, S. Wang, C. J. Tomlin, and A. D. Dragan, “Probabilistically safe robot planning with confidence-based human predictions,” in *Robotics: Science and Systems*, 2018 [pdf](#)
- C15 D. Fridovich-Keil\*, S. L. Herbert\*, J. F. Fisac, S. Deglurkar, and C. J. Tomlin, “Planning, fast and slow: A framework for adaptive real-time safe trajectory planning,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2018 [pdf](#)
- C16 R. Dobbe\*, D. Fridovich-Keil\*, and C. J. Tomlin, “Fully decentralized policies for multi-agent systems: An information theoretic approach,” in *Advances in Neural Information Processing Systems (NeurIPS)*, pp. 2941–2950, 2017 [pdf](#)
- C17 D. Fridovich-Keil, N. Hanford, M. P. Chapman, C. J. Tomlin, M. K. Farrens, and D. Ghosal, “A model predictive control approach to flow pacing for TCP,” in *Allerton Conference on Communication, Control, and Computation*, pp. 988–994, 2017 [pdf](#)
- C18 D. Fridovich-Keil, E. Nelson, and A. Zakhori, “AtomMap: A probabilistic amorphous 3D map representation for robotics and surface reconstruction,” in *IEEE International Conference on Robotics and Automation (ICRA)*, pp. 3110–3117, 2017 [pdf](#)

**ORAL PRESENTATIONS**

- O1 July 2021, “A Brief Tour of Dynamic Games for Multi-Agent Modeling,” Workshop on Perception and Control for Autonomous Navigation in Crowded, Dynamic Environments, Robotics: Science & Systems [video](#)
- O2 July 2021, “A Brief Tour of Dynamic Games for Multi-Agent Modeling,” Semiautonomous Seminar, UC Berkeley.
- O3 July 2021, Robotics Research Debate, Robotics: Science & Systems Pioneers Workshop.
- O4 April 2021, “Parallelizable Methods for Multimodal Stochastic Optimal Control,” NASA ULI Joint Meeting, Stanford.
- O5 2019, “A Scalable Framework for Real-Time Multi-Robot, Multi-Human Collision Avoidance,” Connected and Automated Vehicles, University of Michigan.
- O6 2019, “Iterative Linear Quadratic Approximations for Nonlinear Differential Games,” Robotic Manipulation and Interaction, UC Berkeley.
- O7 2019, “Iterative Linear Quadratic Approximations for Nonlinear Multi-Player General-Sum Differential Games,” Berkeley Artificial Intelligence Lab, UC Berkeley.
- O8 2019, “Toward Robust Autonomy in Multi-Agent Safety-Critical Systems,” DARPA Assured Autonomy Program, Northrop Grumman.
- O9 2019, “Toward Robust Autonomy in Uncertain Safety-Critical Systems,” Nuro.
- O10 2019, “Toward Robust Autonomy in Uncertain Safety-Critical Systems,” Postmates X.
- O11 2018, “Probabilistically Safe Robot Planning with Confidence-Based Human Predictions,” NorCal Control Workshop, UC Santa Cruz.
- O12 2018, “Probabilistically Safe Robot Planning with Confidence-Based Human Predictions,” Berkeley Artificial Intelligence Lab, UC Berkeley.
- O13 2017, “Planning, Fast and Slow with FaSTrack,” Berkeley Artificial Intelligence Lab, UC Berkeley.

**Software**

- W1 D. Fridovich-Keil, “ILQGames: Iterative linear-quadratic games,” 2019
- W2 D. Fridovich-Keil, “FaSTrack: Fast and safe tracking,” 2018

**RESEARCH TOPICS**

Posing interactive motion planning problems as multi-player, noncooperative dynamic games and designing efficient algorithms to solve them. Additionally, building a rapprochement between machine learning methods and classical techniques for robust, adaptive, and geometric control.

**PH.D. SUPERVISION IN PROGRESS**

- 1. Hamzah Khan
- 2. Jonathan Salfity

**OTHER STUDENT RESEARCH COMMITTEES (Current)**

- Ph.D. Defense Committees - 1
- M.S. Committees - 0

**OTHER RESEARCH SUPERVISION**

**Ph.D. Qualifying Committees**

Steven Carr

Yusuf Savas

**M.S. Report Committees**

Yujing Zhou

**David Fridovich-Keil, Assistant Professor**

The University of Texas at Austin

Department of Aerospace Engineering and Engineering Mechanics

Dr. David Fridovich-Keil is the Director of the Control and Learning for Autonomous Robotics (CLeAR) Laboratory, and a core member of the UT Robotics faculty. He received his B.S.E. in Electrical Engineering from Princeton University and his Ph.D. in Electrical Engineering & Computer Sciences from the University of California, Berkeley. His research spans optimal control, dynamic game theory, learning for control and robot safety, and his Ph.D. dissertation proposed some of the first efficient techniques for solving noncooperative, game-theoretic motion planning problems.