

Albert Hao Li

Contact

California Institute of Technology
1200 E. California Blvd.
MC 9-94
Pasadena, CA 91125, USA

e-mail: alberthli@caltech.edu
website: alberthli.github.io

Education

California Institute of Technology
Ph.D., Control and Dynamical Systems
Advisor: Aaron Ames
GPA: 4.130 / 4.000

Pasadena, CA
2021-Present

Stanford University
M.S., Mechanical Engineering
GPA: 4.120 / 4.000

Stanford, CA
2019-2021

University of California, Berkeley
B.S., Mechanical Engineering
Minor, Electrical Engineering and Computer Science
GPA: 3.928 / 4.000

Berkeley, CA
2015-2019

Awards and Honors

Kortschak Scholars Graduate Fellowship
UC Berkeley College of Engineering High Honors

2021
2019

Research

Advanced Mechanical Bipedal Experimental Robotics Lab
PI: Aaron Ames

Caltech
2021-Present

Assistive Robotics and Manipulation Lab
PI: Monroe Kennedy III

Stanford University
2019-2021

Hybrid Robotics Lab
PI: Koushil Sreenath

UC Berkeley
2019

Berkeley Emergent Space Tensegrities Lab
PI: Alice Agogino

UC Berkeley
2018-2019

Laboratory for Automation Science and Engineering
PI: Ken Goldberg

UC Berkeley
2017

Industry Experience

Apple Inc.
Apple Watch Product Design Intern

Cupertino, CA
2018

Publications

Journal Publications

- [J1] Andrew Preston Sabelhaus, **Albert Hao Li**, Kimberley Sover, Jacob Madden, Andrew Barkan, Adrian Agogino, and Alice Agogino, “Inverse Statics Optimization for Compound Tensegrity Robots,” *IEEE Robotics and Automation Letters*, vol. 5, no. 3, pp. 3982-3989, 2020.

Conference Publications

- [C3] **Albert Hao Li***, Philipp Wu*, Monroe Kennedy III, “Replay Overshooting: Learning Stochastic Latent Dynamics with the Extended Kalman Filter,” *2021 IEEE International Conference on Robotics and Automation (ICRA)*, Xi’an, China, 2021, pp. 852-858. ***Equal Contribution.**
- [C2] Katherine Lin Poggensee*, **Albert Hao Li***, Daniel Sotsaichich*, Bike Zhang, Prasanth Kottaru, Mark Mueller, and Koushil Sreenath, “Ball Juggling on the Bipedal Robot Cassie,” *2020 European Control Conference (ECC)*, Saint Petersburg, Russia, 2020, pp. 875-880. ***Equal Contribution.**
- [C1] Jeffrey Mahler, Matthew Matl, Xinyu Liu, **Albert Li**, David Gealy, Ken Goldberg, “Dex-Net 3.0: Computing Robust Vacuum Suction Grasp Targets in Point Clouds Using a New Analytic Model and Deep Learning,” *2018 IEEE International Conference on Robotics and Automation (ICRA)*, Brisbane, QLD, 2018, pp. 5620-5627.

Presentations and Talks

Ball Juggling on the Bipedal Robot Cassie	Berkeley, CA
<i>Bay Area Robotics Symposium 2019 (jointly with Bike Zhang)</i>	<i>2019</i>

Reviewing Activities

IEEE Robotics and Automation Letters (RA-L)	<i>2020, 2021</i>
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Teaching

Advanced Dynamics, Controls, and System Identification (ME334)	Stanford University
<i>Teaching Assistant</i>	<i>2021</i>
Dynamic Systems, Vibrations, and Control (ME161)	Stanford University
<i>Teaching Assistant</i>	<i>2020</i>