

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

IEEE International Automated Vehicle Validation Conference (IAVVC), Local Arrangements Chair, 2023

Workshop on Strategic, Multi-Agent Interaction, Conference on Robot Learning (CoRL), 2022

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

Conference Activities: Editor

Associate Editor, IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), 2023

Associate Editor, IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), 2022

Conference Activities: Program Committee

Uncertainty in Artificial Intelligence (UAI), 2023

Distributed Autonomous Robotic Systems (DARS), 2022

IFAC Workshop on Cyber-Physical Human Systems, 2022

Uncertainty in Artificial Intelligence (UAI), 2022

Learning for Dynamics and Control (L4DC), 2022

OTHER PROFESSIONAL HIGHLIGHTS

Funding Panels and Review Activity

NSF CPS, Spring 2023

Canadian NSERC, Fall 2022

Conference and Journal Review Activities

AIAA Journal of Guidance, Control, and Dynamics

International Journal of Robotics Research

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

Department Committees

Diversity, Equity, and Inclusion Committee, 2021-present

Texas Robotics

Robotics Minor Curriculum Committee, 2022-present

Robotics Building Space Committee, 2022-present

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 L. Peters, V. Rubies-Royo, C. J. Tomlin, L. Ferranti, J. Alonso-Mora, C. Stachniss, and D. Fridovich-Keil, “Learning players’ objectives in continuous dynamic games from partial state observations,” *International Journal of Robotics Research* (accepted), 2023 [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*, 2023 [pdf](#)
- J3 Y. Yue, J. Salfity, D. Fridovich-Keil, and U. Topcu, “Inverse matrix games with unique quantal response equilibrium,” *Control Systems Letters*, 2022 [pdf](#)
- J4 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](#)
- J5 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](#)
- J6 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, C.-Y. Chiu, L. Peters, S. Sojoudi, C. J. Tomlin, and D. Fridovich-Keil, “Cost inference for feedback dynamic games from noisy partial state observations and incomplete trajectories,” in *International Conference on Autonomous Agents and Multiagent Systems (AAMAS)*, 2023 [pdf](#)
- C2 P. Washington, D. Fridovich-Keil, and M. Schwager, “GrAVITree: Graph-based approximate value function in a tree,” in *American Control Conference (ACC)*, 2023 [pdf](#)
- C3 Y. Yu, S. Chen, D. Fridovich-Keil, and U. Topcu, “Cost design in atomic routing games,” in *American Control Conference (ACC)*, 2023 [pdf](#)
- C4 S. Agarwal, D. Fridovich-Keil, and S. P. Chinchali, “Robust forecasting for robotic control: A game-theoretic approach,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2023 [pdf](#)
- C5 M. O. Karabag, D. Fridovich-Keil, and U. Topcu, “Alternating direction method of multipliers for decomposable saddle-point problems,” in *2022 58th Annual Allerton Conference on Communication, Control, and Computing*, IEEE, 2022 [pdf](#)
- C6 J. Sun, S. Kousik, D. Fridovich-Keil, and M. Schwager, “Self-supervised traffic advisors: Distributed, multi-view traffic prediction for smart cities,” in *IEEE International Conference on Intelligent Transportation Systems*, 2022 [pdf](#)
- C7 C.-Y. Chiu and D. Fridovich-Keil, “GTP-SLAM: Game-theoretic priors for simultaneous localization and mapping in multi-agent scenarios,” in *IEEE Conference on Decision and Control (CDC)*, 2022 [pdf](#)

- C8 L. Peters, D. Fridovich-Keil, L. Ferranti, C. Stachniss, J. Alonso-Mora, and F. Laine, “Learning mixed strategies in trajectory games,” in *Robotics: Science and Systems*, 2022 [pdf](#)
- C9 D. R. Anthony, D. P. Nguyen, D. Fridovich-Keil, and J. F. Fisac, “Back to the future: Efficient, time-consistent solutions in reach-avoid games,” in *IEEE International Conference on Robotics and Automation (ICRA)*, 2022 [pdf](#)
- C10 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 [pdf](#)
- C11 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](#)
- C12 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](#)
- C13 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](#)
- C14 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](#)
- C15 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](#)
- C16 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](#)
- C17 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](#)
- C18 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](#)
- C19 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](#)
- C20 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](#)
- C21 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](#)
- C22 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](#)
- C23 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](#)
- C24 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](#)

- C25 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](#)
- C26 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](#)
- C27 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 May 2023, “Dynamic Game Models for Multi-Agent Interactions: The Role of Information in Designing Efficient Algorithms,” Robotics Seminar, TU Delft
- O2 May 2023, “Dynamic Game Models for Multi-Agent Interactions: The Role of Information in Designing Efficient Algorithms,” Robotics Seminar, Princeton University
- O3 April 2023, “Dynamic Game Models for Multi-Agent Interactions: Forward and Inverse Solutions,” Babuška Forum, Oden Institute, UT Austin
- O4 November 2022, “Dynamic Game Models for Multi-Agent Interactions: Forward and Inverse Solutions,” CMS/EC 248 Guest Lecture, Caltech
- O5 October 2022, “Dynamic Game Models for Multi-Agent Interactions: Forward and Inverse Solutions,” Nuro [video](#)
- O6 September 2022, “Mixing Continuous Strategies: A Case Study in Trajectory Games,” Allerton, UIUC
- O7 May 2022, “Learning Mixed Strategies in Lifted Trajectory Games,” Autonomy Talks, ETH Zürich [video](#)
- O8 May 2022, “What is Feedback, Really?” EE290 Guest Lecture, UC Berkeley
- O9 April 2022, “Learning to Compete: Efficient Solutions for Noncooperative Games,” Texas Robotics Symposium, UT Austin
- O10 April 2022, “Learning in Noncooperative Games: Efficient Algorithms and Open Challenges,” Amazon Robotics
- O11 November 2021, “A Brief Tour of Dynamic Games for Multi-Agent Modeling,” Aerospace Engineering and Engineering Mechanics External Advisory Committee, UT Austin
- O12 November 2021, “A Brief Tour of Dynamic Games for Multi-Agent Modeling,” Aerospace Engineering Department Seminar, CU Boulder
- O13 October 2021, “A Brief Tour of Dynamic Games for Multi-Agent Modeling,” Control, Autonomy, and Robotics Seminar, UT Austin
- O14 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](#)
- O15 July 2021, “A Brief Tour of Dynamic Games for Multi-Agent Modeling,” Semiautonomous Seminar, UC Berkeley.
- O16 July 2021, Robotics Research Debate, Robotics: Science & Systems Pioneers Workshop.
- O17 April 2021, “Parallelizable Methods for Multimodal Stochastic Optimal Control,” NASA ULI Joint Meeting, Stanford.
- O18 2019, “A Scalable Framework for Real-Time Multi-Robot, Multi-Human Collision Avoidance,” Connected and Automated Vehicles, University of Michigan.
- O19 2019, “Iterative Linear Quadratic Approximations for Nonlinear Differential Games,” Robotic Manipulation and Interaction, UC Berkeley.

- O20 2019, “Iterative Linear Quadratic Approximations for Nonlinear Multi-Player General-Sum Differential Games,” Berkeley Artificial Intelligence Lab, UC Berkeley.
- O21 2019, “Toward Robust Autonomy in Multi-Agent Safety-Critical Systems,” DARPA Assured Autonomy Program, Northrop Grumman.
- O22 2019, “Toward Robust Autonomy in Uncertain Safety-Critical Systems,” Nuro.
- O23 2019, “Toward Robust Autonomy in Uncertain Safety-Critical Systems,” Postmates X.
- O24 2018, “Probabilistically Safe Robot Planning with Confidence-Based Human Predictions,” NorCal Control Workshop, UC Santa Cruz.
- O25 2018, “Probabilistically Safe Robot Planning with Confidence-Based Human Predictions,” Berkeley Artificial Intelligence Lab, UC Berkeley.
- O26 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
3. Fernando Palafox
4. Junette Hsin
5. Jacob Levy
6. Brett Barkley

M.S. SUPERVISION IN PROGRESS

1. Antonio Lopez

OTHER STUDENT RESEARCH COMMITTEES (Current)

Ph.D. Defense Committees - 1

M.S. Committees - 1

OTHER RESEARCH SUPERVISION

Ph.D. Qualifying Committees

Franck Djeumou
Alexander Nettekoven
Steven Carr

M.S. Report Committees

Aryaman Samyal
Rishabh Thakkar
Martin Braquet

Undergraduate Honors Projects

Chiadika Obinwa

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.