

Carlos Gonzalez

Education

2021–Present	Ph.D. Aerospace Engineering University of Texas, Austin, TX, USA Advisor: Dr. Luis Sentis	Expected 2026
2015–2016	M.S. Electrical and Computer Engineering, <i>with distinction</i> University of New Mexico, Albuquerque, NM, USA Advisor: Dr. Meeko Oishi Emphasis: Systems and Control	Cumulative GPA: 3.94 / 4.00
2010–2014	B.S. Mechanical Engineering, <i>cum laude</i> University of New Mexico, Albuquerque, NM, USA Advisor: Dr. Ron Lumia	Cumulative GPA: 3.72 / 4.00

Work Experience

2021–Present (Aug.)	Graduate Research Assistant , <i>University of Texas at Austin</i> , Austin, TX Project: Research in locomotion and multi-contact planning for humanoid robots <ul style="list-style-type: none">○ Develop and benchmark fast, collision-free multi-contact planning algorithms for humanoids○ Configure, test, and integrate COTS servo controllers (EtherCAT) into existing hardware○ Developed approach for online optimal horizon selection in Model Predictive Control [C5] Project: Mechatronic design of omniwheel robot with visual and force sensing capabilities <ul style="list-style-type: none">○ Designed and prototyped mechanical structure of mobile robot capable of carrying a person○ Developed and open-sourced low-level code for EtherCAT devices with ROS integration [C6]
2020–2021 (Sep.)–(July)	Research Associate , <i>Institute for Human & Machine Cognition</i> , Pensacola, FL Projects: Legged robot controls engineer for exoskeleton Quix and humanoid robot Atlas <ul style="list-style-type: none">○ Designed and implemented (in Java) push recovery and balance strategies on Atlas○ Improved force sensing and control capabilities of exoskeleton Quix○ Wrote software integration for motor control via CAN for exoskeleton Eva and humanoid Nadia
2018–2020 (July)	Research Fellow , <i>Istituto Italiano di Tecnologia</i> , Genoa, Italy Project: Implementation of a balance controller on the (torque-controlled) quadruped robot HyQ <ul style="list-style-type: none">○ Simulated a novel balance control strategy to make HyQ balance on two point feet on Gazebo○ Implemented the controller on the real HyQ and made the robot balance on a support line○ Incorporated a motion controller to the balance controller to achieve line walking in simulation○ Submitted and presented the main simulations and experimental results in IROS [C8]
2016–2018	Research Assistant , <i>New York University</i> , Brooklyn, NY, USA Project: Sensitivity analysis of balance-stability of legged systems <ul style="list-style-type: none">○ Designed a computational approach to establish the balance-stability of legged robots by combining numerical optimization and motion planning algorithms, publications [C10] and [J2]○ Derived quasi-analytical solutions to quantify the changes in balance-stability of legged systems as design constraints (e.g., torque limits) change, published work in [C9]
2015–2016	Research Assistant , <i>University of New Mexico</i> , Albuquerque, NM, USA Project: Hybrid system identification for prognosis of Parkinson's Disease <ul style="list-style-type: none">○ Implemented and compared several state-of-the-art methods in hybrid system identification○ Derived an alternate identification approach using optimization methods for hybrid systems, showing more accurate and precise detection of submovements in Parkinson's disease patients
2014	Research Student , <i>University of New Mexico</i> , Albuquerque, NM, USA Project: Control of a smart microelectromechanical material to be used as a microgripper <ul style="list-style-type: none">○ Designed and presented research proposal plan to academic advisor○ Designed and performed experiments to validate the proposed approach, published work on [J3]

Software Skills

Proficient	Git, MATLAB, Simulink
Intermediate	C++, ROS, Python, Java, Linux, LATEX, OnShape, SolidWorks, EAGLE
Basic	LabView, Cortex

Publications

Journal Papers

- [J1] Seung Hyeon Bang, **Carlos Gonzalez**, Junhyeok Ahn, Nicholas Paine, and Luis Sentis "Control and evaluation of a humanoid robot with rolling contact joints on its lower body," *Frontiers in Robotics and AI*, vol. 10, 2023. [[link](#)]
- [J2] Carlotta Mummolo, William Z. Peng, **Carlos Gonzalez**, and Joo H. Kim, "Contact-Dependent Balance Stability of Biped Robots," *Journal of Mechanisms and Robotics*, vol. 10, no. 2, p. 021009, 2018. [[link](#)]
- [J3] **Carlos Gonzalez** and Ron Lumia, "An IPMC microgripper with integrated actuator and sensing for constant finger-tip displacement," *Smart Materials and Structures*, vol. 24, no. 5, p. 55011, 2015. [[link](#)]

Conference Papers

- [C1] Seung Hyeon Bang, **Carlos Gonzalez**, Gabriel Moore, Dong Ho Kang, Mingyo Seo, Ryan Gupta and Luis Sentis, "RPC: A modular framework for robot planning, control, and deployment," in *IEEE/SICE International Symposium on System Integration (SII)*, 2025. [[link](#)]
- [C2] **Carlos Gonzalez** and Luis Sentis, "Guiding Collision-Free Humanoid Multi-Contact Locomotion using Convex Kinematic Relaxations and Dynamic Optimization," in *IEEE-RAS 23rd International Conference on Humanoid Robots (Humanoids)*, 2024. [[link](#)]
- [C3] Seung Hyeon Bang, Jaemin Lee, **Carlos Gonzalez** and Luis Sentis, "Variable inertia model predictive control for fast bipedal maneuvers," in *IEEE Conference on Decision and Control*, 2024. [[link](#)]
- [C4] Mingyo Seo, Steve Han, Kyutae Sim, Seung Hyeon Bang, **Carlos Gonzalez**, Luis Sentis and Yuke Zhu, "Deep imitation learning for humanoid loco-manipulation through human teleoperation," in *IEEE-RAS 22nd International Conference on Humanoid Robots (Humanoids)*, 2023. [[link](#)]
- [C5] **Carlos Gonzalez**, Seung Hyeon Bang, Po-han Li, Sandeep Chinchali, and Luis Sentis, "Learning Adaptive Horizon Maps Based on Error Forecast for Model Predictive Control," in *IEEE Conference on Decision and Control*, 2023. [[link](#)]
- [C6] **Carlos Gonzalez**, Samantha Lee, Francisco Montano, Steven Ortega, Dong Ho Kang, Mehar Jaiswal, Junfeng Jiao and Luis Sentis, "Design of a Person-Carrying Robot for Contact Compliant Navigation," in *Proceedings of the ASME International Design Engineering Technical Conference*, 2023. [[link](#)]
- [C7] Junhyeok Ahn, Seung Hyeon Bang, **Carlos Gonzalez**, Yuanchen Yuan, Luis Sentis, "Data-Driven Safety Verification for Legged Robots," in *IEEE-RAS International Conference on Humanoid Robots*, 2022. [[link](#)]

- [C8] **Carlos Gonzalez**, Victor Barasuol, Marco Frigerio, Roy Featherstone, Darwin G. Caldwell, and Claudio Semini, “Line walking and balancing for legged robots with point feet,” in *IEEE/RSJ International Conference on Intelligent Robots and Systems*, 2020. [link]
- [C9] **Carlos Gonzalez**, Carlotta Mummolo, and Joo H. Kim, “Sensitivity of balancing in legged systems under torque constraint variations,” in *Proceedings of the ASME International Design Engineering Technical Conference*, 2018, pp. 1–9. [link]
- [C10] Carlotta Mummolo, William Z. Peng, **Carlos Gonzalez**, and Joo H Kim, “Contact-Dependent Balance Stability of Walking Robots,” in *ASME 2017 International Design Engineering Technical Conferences and Computers and Information in Engineering Conference*, 2017, pp. 1–7. [link]
- [C11] **Carlos Gonzalez**, Daniel Svenkeson, Diana J. Kim, Martin J. McKeown, and Meeko Oishi, “Detection of manual tracking submovements in Parkinson’s disease through hybrid optimization,” *IFAC-PapersOnLine*, vol. 48, no. 27, pp. 291–297, 2015. [link]

Academic Service

Conference IEEE IROS (2025, 2024, 2023), IEEE RAL (2025), IEEE ICRA (2025), IEEE Humanoids
Review (2024), IEEE BioRob (2024)