Apurva Patil

📱 +1 669-362-7100 | ✉ apurvapatil@utexas.edu | 🏠 patil-apurva.github.io/portfolio/ | 🔗 linkedin.com/in/apurva-d-patil | 🐙 [apurva-patil](https://github.com/apurva-patil)

🎓 EDUCATION

The University of Texas at Austin

PhD, Mechanical Engineering [(Robotics Portfolio Program)](#) *Aug 2021 - May 2025*
Specialization: Controls, Autonomy and Robotics
Advisor: [Takashi Tanaka](#), [Luis Sentis](#), GPA: **4.0/4.0**

MS, Mechanical Engineering [(Robotics Portfolio Program)](#) *Aug 2019 - May 2021*
Advisor: [Takashi Tanaka](#), [Luis Sentis](#), GPA: **4.0/4.0**

College of Engineering Pune, India
BTech, Mechanical Engineering; GPA: **9.39/10** (Class Rank: **2/185**) *Aug 2013 - May 2017*

💼 PROFESSIONAL EXPERIENCE

Tensor Auto San Jose, CA
Machine Learning Engineer for Motion & Behavior Planning *Jun 2025 - Present*

- Working on integrating ML-based approaches with classical (rule-based) planning algorithms
- Developing a joint prediction and planning framework for interactive, human-like decision-making using **Transformer-based architectures** and **imitation learning**.

Amazon Robotics Seattle, WA
Applied Scientist II Intern (Vulcan Stow team) *May - Aug 2024*

- Developed a real-time motion planning algorithm for Vulcan, an 8-DOF manipulator, enabling efficient item stowing and retrieval from densely packed shelves in the Amazon fulfillment centers

Cruise San Fransisco, CA
Motion Planning Intern *Sep - Dec 2023*

- Worked on making the trajectories of autonomous vehicles safer and more comfortable during **remote assistance**, **auto parking and unparking**

Apptronik Austin, TX
Software and Controls Intern *May - Aug 2020*

- Developed a **sampling-based, real-time motion planning** algorithm Hierarchical Dynamic Roadmap (HDRM) for Apptronik's robotic manipulators
- Benchmarked the algorithm on **6 DOF manipulators** with the virtual workspace developed in **Gazebo**

💻 RECENT PROJECTS

***PhD Thesis*: Advancing Frontiers of Path Integral Theory for Stochastic Optimal Control**
Advisor: Prof. Takashi Tanaka and Luis Sentis, UT Austin *May 2021 - May 2025*

- Developed theoretical frameworks and algorithms to solve stochastic optimal control problems such as **risk-constrained motion planning** via the **path integral** control approach (an approach to synthesize optimal control policies **on-the-fly** using online Monte-Carlo simulations)
- Worked on analyzing the **sample complexity** of path integral control
- Developed digital twins (simulators) of physical systems like quadcopters using gray-box modeling techniques

***Master's Thesis*: Safety-based Motion Planning in Uncertain Environments**
Advisor: Prof. Takashi Tanaka and Luis Sentis, UT Austin *Aug 2019 - May 2021*

- Developed algorithms to estimate **end-to-end collision probabilities** of **motion plans** for autonomous agents with discrete and continuous-time dynamics, navigating in **uncertain environments**
- Incorporated the developed risk estimation framework in motion planners to generate **optimal safe trajectories** in the presence of uncertainties

Reinforcement Learning Based Risk-Bounded Motion Planning

Advisor: Prof. Peter Stone and Scott Niekum, UT Austin   *Jan - May 2022*

- Proposed an extension of **semi-gradient SARSA** and **TD(0)** algorithms to solve **risk-bounded motion planning** and end-to-end **risk estimation** problems for autonomous vehicles in continuous-space. The proposed model allows the user to adjust the **risk-averse level** of the autonomous agent.

Bachelor's Thesis: Design and Development of a Humanoid Torso

Advisor: Prof. Shantipal Ohol, College of Engineering Pune, India   *Aug 2016 - May 2017*

- Built a humanoid torso to **pick and place** objects by obtaining visual and audio data via **Microsoft Kinect**
- Designed **5 DOF robot arms** and **multi-finger adaptive grippers**, established a real-time control of the robot arms to attain the desired position and orientation of the end-effectors

✚ SKILLS

Languages: Python, C++, **Tools and software packages**: MATLAB/Simulink, PyTorch, TensorFlow, ROS, OpenCV, NuSMV, Slugs, PRISM, LabVIEW, AutoCAD, SolidWorks, ANSYS, ParaView, MeshLab, Git, Isaac Sim

☰ RELEVANT PUBLICATIONS (GOOGLE SCHOLAR)

- **A. Patil**, K. Morgenstein, L. Sentis, T. Tanaka, "Path Integral Methods for Synthesizing and Preventing Stealthy Attacks in Nonlinear Cyber-Physical Systems", *submitted to TAC*. [Paper]
- **A. Patil**, A. Duarte, F. Bisetti, T. Tanaka, "Strong Duality and Dual Ascent Approach to Continuous-Time Chance-Constrained Stochastic Optimal Control", *submitted to Transactions of Automatic Control, (TAC)*.
- C. Martin, **A. Patil**, W. Li, T. Tanaka, D. Chen, "Model Predictive Path Integral Control for Roll-to-Roll Manufacturing", *Modeling, Estimation and Control Conference, (MECC)*, 2025. (**Best Student Paper**)
- **A. Patil**, R. Funada, T. Tanaka, L. Sentis "Task Hierarchical Control via Null-Space Projection and Path Integral Approach", *American Control Conference (ACC)*, 2025. [Paper]
- M. Baglioni, **A. Patil**, L. Sentis, A. Jamshidnejad, "Achieving Multi-UAV Best Viewpoint Coordination in Obstructed Environments", *submitted to Robotics and Autonomous Systems*. [Paper]
- **A. Patil**, G. Hanasusanto, T. Tanaka, "Discrete-Time LQR via Path Integral Control and Its Sample Complexity Analysis", *IEEE Control Systems Letters (L-CSS)*, 2024. [Paper]
- **A. Patil**, M. Karabag, T. Tanaka, U. Topcu, "Simulator-Driven Deceptive control via Path Integral Approach", *IEEE Conference on Decision and Control (CDC)* 2023. [Paper]
- **A. Patil**, Y. Zhou, D. Fridovich-Keil, T. Tanaka, "Risk-Minimizing Two-Player Zero-Sum Stochastic Differential Game via Path Integral Control", *IEEE Conference on Decision and Control (CDC)* 2023. [Paper]
- **A. Patil**, T. Tanaka, "Upper and Lower Bounds for End-to-End Risks in Stochastic Robot Navigation", *IFAC World Congress*, 2023. [Paper]
- **A. Patil**, A. Duarte, A. Smith, F. Bisetti, T. Tanaka, "Chance-Constrained Stochastic Optimal Control via Path Integral and FDM", *IEEE Conference on Decision and Control (CDC)*, 2022 [Paper]
- **A. Patil**, T. Tanaka, "Upper Bounds for Continuous-Time End-to-End Risks in Stochastic Robot Navigation", *European Control Conference (ECC)*, 2022. [Paper]
- **A. Patil**, M. Kulkarni, A. Aswale, "Analysis of the inverse kinematics for 5 DOF robot arm using D-H parameters", *IEEE International Conference on Real-time Computing and Robotics*, 2017. [Paper]

🏆 AWARDS, ACHIEVEMENTS AND POSITIONS

- **Reviewer**: TAC, CDC, ACC, ECC, IFAC WC
- **Best Student Paper Award**, Modeling, Estimation and Control Conference (MECC)   *2025*
- **CDC 2022 Student Travel Support Award**, IEEE Control System Society   *2022*
- **H. Grady Rylander Excellence in Teaching Fellowship**, UT Austin   *2020*
- **TCS Best Student Award**, College of Engineering Pune, India   *2017*
- **Best Bachelor's Project Award**, College of Engineering Pune, India   *2017*
- **S. N. Bose Fellowship** for a research internship in the USA (1 in 47 students across India)   *2016*
- **National Robocon**: Winner *2017*, Runners-up *2016*, Best Innovative Design *2015*