

# Seung Hyeon Bang

4600 Mueller Blvd, Austin, TX 78723

Tel: (512) 662-9984 / Email: [bangsh0718@gmail.com](mailto:bangsh0718@gmail.com) / Homepage: <https://shbang91.github.io/>

## EDUCATION

---

- Aug. 2018 – present      **The University of Texas at Austin, Austin, TX**  
Doctor of Philosophy in Aerospace Engineering  
• Advisor: Luis Sentis
- Aug. 2018 – Aug. 2022      **The University of Texas at Austin, Austin, TX**  
Master of Science in Aerospace Engineering  
• Thesis topic: Operational Space Control of Compliant Isoelastic Robots and Their Interaction with an DIARC Cognitive Architecture  
• Advisor: Luis Sentis
- Aug. 2014 – May. 2018      **Stonybrook University, Stonybrook, NY**  
Bachelor of Engineering in Mechanical Engineering  
• *Summa Cum Laude*

## WORK AND RESEARCH EXPERIENCE

---

- Jan. 2019 – present      **Graduate Research Assistant**  
The University of Texas at Austin, Austin, TX  
• Planning, control, optimization, and machine learning algorithms for humanoid robots  
• Control and optimization algorithms for an isoelastic manipulator
- June. 2023 – August. 2023      **Robotics Software Engineer Intern**  
Appttronik Inc, Austin, TX  
• Development of inertia-aware model predictive control (MPC) algorithms for humanoid robots  
• Trajectory generation support for the Apollo humanoid robot bring up

## PUBLICATIONS

---

1. **SH. Bang**, C. Gonzalez, G. Moore, DH. Kang, M. Seo, and L. Sentis, “RPC: A Modular Framework for Robot Planning, Control, and Deployment,” *IEEE International Symposium on System Integration (SII)*, 2025 (To appear)
2. **SH. Bang**, C. Jové, and L. Sentis, “RL-augmented MPC Framework for Agile and Robust Bipedal Footstep Locomotion Planning and Control,” *IEEE-RAS International Conference on Humanoid Robots (Humanoids)*, 2024 (To appear)
3. **SH. Bang**, J. Lee, C. Gonzalez, and L. Sentis, “Variable Inertia Model Predictive Control for Fast Bipedal Maneuvers,” *IEEE Conference on Decision and Control (CDC)*, 2024 (To appear)
4. L. Rossini, E. Hoffman, **SH. Bang**, L. Sentis, and N. Tsagarakis, “A Real-Time Approach for Humanoid Robot Walking including Dynamic Obstacles Avoidance,” *IEEE-RAS International Conference on Humanoid Robots (Humanoids)*, 2023
5. M. Seo, S. Han, K. Sim, **SH. Bang**, C. Gonzalez, L. Sentis, and Y. Zhu, “Deep Imitation Learning for Humanoid Loco-manipulation through Human Teleoperation,” *IEEE-RAS International Conference on Humanoid Robots (Humanoids)*, 2023
6. **SH. Bang**, C. Gonzalez, J. Ahn, N. Paine, and L. Sentis, “Control and Evaluation of a Humanoid Robot with Rolling Contact Joints on its Lower Body,” *Frontiers in Robotics and AI*, 2023
7. C. Gonzalez, **SH. Bang**, P. Li, S. Chinchali, and L. Sentis, “Learning Adaptive Horizon Maps Based on Error Forecast for Model Predictive Control,” *IEEE Conference on Decision and Control (CDC)*, 2023
8. J. Ahn, **SH. Bang**, C. Gonzalez, Y. Yuan, and L. Sentis, “Data-driven safety verification for legged robots,”

9. J. Lee, J. Ahn, D. Kim, **SH. Bang**, and L. Sentis, "Online gain adaptation of whole-body control for legged robots with unknown disturbances," *Frontiers in Robotics and AI*, vol. 8, 2022.
10. J. Ahn, S. J. Jorgensen, **SH. Bang**, and L. Sentis, "Versatile locomotion planning and control for humanoid robots," *Frontiers in Robotics and AI*, vol. 8, 2021.
11. J. Lee, **SH. Bang**, E. Bakolas, and L. Sentis, "MPC-Based Hierarchical Task Space Control of Underactuated and Constrained Robots for Execution of Multiple Tasks," *IEEE Conference on Decision and Control (CDC)* 2020
12. J. Ahn, D. Kim, **SH. Bang**, N. Paine, and L. Sentis, "Control of a high performance bipedal robot using viscoelastic liquid cooled actuators," *IEEE-RAS International Conference on Humanoid Robots (Humanoids)*, 2019

## UNDER REVIEW

---

## TEACHING EXPERIENCE

---

Jan. 2022 – May. 2022	<b>Graduate Teaching Assistant</b> The University of Texas at Austin, Aerospace Engineering & Engineering Mechanics, <i>Austin, TX</i> • Decision and Control of Human-Centered Robots (ASE389)
Jan. 2021 – May. 2021	<b>Graduate Teaching Assistant</b> The University of Texas at Austin, Aerospace Engineering & Engineering Mechanics, <i>Austin, TX</i> • Flight Dynamics (ASE367K)
Sep. 2018 – Dec. 2018	<b>Graduate Teaching Assistant</b> The University of Texas at Austin, Mechanical Engineering, <i>Austin, TX</i> • Experimental Fluids Mechanics (ME 130L)

## SKILLS

---

Program Language	C++, Python, Matlab
Library	Pinocchio, PyTorch, Protobuf, ZeroMQ
Simulator	Dart, Pybullet, MuJoCo
Language	English (fluent), Korean (native)

## SOFTWARES

---

RPC	C++ library designed to integrate multiple physics-based simulators, planning and control modules, visualization tools, plotting and logging utilities, and operator interfaces for robotic systems. ( <a href="https://github.com/shbang91/rpc">https://github.com/shbang91/rpc</a> )
-----	--

## OPEN SOURCE CONTRIBUTIONS

---

PnC	C++ library designed for generating trajectories for a robot system and stabilizing the system over the trajectories. ( <a href="https://github.com/junhyeokahn/PnC">https://github.com/junhyeokahn/PnC</a> )
PyPnC	Python implementation of PnC. ( <a href="https://github.com/junhyeokahn/PyPnC">https://github.com/junhyeokahn/PyPnC</a> )
pink	<b>Python inverse kinematics</b> for articulated robot models based on Pinocchio ( <a href="https://github.com/stephane-caron/pink">https://github.com/stephane-caron/pink</a> )