

# SEIJI SHAW

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<b>CONTACT</b>	32 Vassar St. 32-33x Cambridge MA, 02139	seijis@mit.edu 415-699-4234
<b>EDUCATION</b>	<i>Ph.D. Electrical Engineering and Computer Science</i> Massachusetts Institute of Technology, Cambridge, MA Advisor: Prof. Nicholas Roy	2022-Present
	<i>M.S. Electrical Engineering and Computer Science</i> Massachusetts Institute of Technology, Cambridge, MA Advisor: Prof. Nicholas Roy	2022-Present
	<i>Sc.B. Mathematics-Computer Science, magna cum laude</i> Brown University, Providence, RI Advisor: Prof. George Konidakis Honors Thesis: <i>Towards Safe Learning in Robotic Manipulation</i>	2018-2022
<b>EMPLOYMENT</b>	<i>Graduate Researcher</i> Computer Science and Artificial Intelligence Lab, MIT Robust Robotics Group (PI: Nicholas Roy)	2022-Present
	<i>Undergraduate Researcher</i> Department of Computer Science, Brown University Intelligent Robot Lab (PI: George Konidakis)	2020-2022
	<i>Research Intern</i> Mitsubishi Electric Research Laboratories, Cambridge, MA Data Analytics Group (PI: Daniel Nikovski)	Summer 2021
	<i>Research Intern</i> Cedars-Sinai Medical Center Hong Lab (PI: TingTing Hong)	Summers 2015, 2019
<b>AWARDS AND HONORS</b>	<i>Best Paper in Robot Manipulation Award Finalist, ICRA</i>	2024
	<i>Senior Prize, Brown University Dept. of Computer Science</i>	2022
	<i>Sigma Xi, inducted</i>	2022
	<i>Outstanding Winner, COMAP Mathematical Contest in Modelling</i>	2020
	<i>Rachel Carson Award, COMAP Mathematical Contest in Modelling</i>	2020
<b>PRE-PRINTS</b>	2. Michael Noseworthy, Seiji Shaw, Chad Kessens, and Nicholas Roy. Amortized inference for efficient grasp model adaptation. 2023. Accepted to ICRA 2024	
	1. Thomas Cohn, Seiji Shaw, Max Simchowitz, and Russ Tedrake. Constrained bi-manual planning with analytic inverse kinematics. <i>arXiv preprint arXiv:2309.08770</i> , 2023. To Appear at ICRA 2024. Best Paper in Robot Manipulation Award Finalist	

<b>PUBLICATIONS</b>	3. Seiji Shaw, Devesh K Jha, Arvind Raghunathan, Radu Corcodel, Diego Romeres, George Konidaris, and Daniel Nikovski. Constrained dynamic movement primitives for safe learning of motor skills. In <i>IEEE/RSJ International Conference on Intelligent Robots and Systems</i> , 2023	
	2. Seiji Shaw, Ben Abbatematteo, and George Konidaris. Rmps for safe impedance control in contact-rich manipulation. In <i>International Conference on Robotics and Automation</i> , 2022	
	1. Tiffany Ding*, Soryan Kumar*, and Seiji Shaw*. A seabird population model to evaluate plastic pollution policies. <i>UMAP Journal of Undergraduate Mathematics and its Applications</i> , 41(3), 2020	
<b>GRANTS AND FELLOWSHIPS</b>	National Science Foundation Graduate Research Fellowship	2022-2025
	Ford Foundation Fellowship, Honorable Mention	2022
	Karen T. Romer Undergraduate Research and Teaching Award	2019
<b>TEACHING</b>	<i>Head Teaching Assistant, CSCI 1951R: Introduction to Robotics</i> Dept. Computer Science, Brown University Instructor: Stefanie Tellex	Fall 2020
<b>OUTREACH</b>	<i>Technical Volunteer in Quest for Embodied Intelligence</i> Quest for Artificial Intelligence, Massachusetts Institute of Technology	Fall 2022-Present
	<i>Choreorobotics Mentor and Controls Engineer</i> Dept. Theatre and Performance Studies, Brown University	Spring-Summer 2022
	<i>Workshop Instructor</i> Brown Design Workshop, Dept. of Engineering, Brown University	2019-2020
	<i>Mentor, Team 6000 Firehawk Robotics</i> Shalhevet High School, Los Angeles, California	2018-2019
	<i>Mentor, Team 5987 Galaxia</i> Reali Hebrew Day School, Haifa, Israel	2017-2018
<b>REFEREEING</b>	IEEE International Conference on Robotics and Automation	2023
	IEEE International Conference on Robotics and Automation	2024
<b>OTHER</b>	<i>Shabbat Program Coordinator, MIT GradHillel</i>	2023-Present
	<i>Orthodox Student Community Liaison, Brown-RISD Hillel</i>	2019-2021
	<i>Blacher Outstanding New Student Initiatives Award, Brown-RISD Hillel</i>	2019