

# Johann Laconte

*Ph.D. in Robotics*

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**Research Interests:** Robotics; Applied Mathematics; Traversability; State Estimation; Mapping.

## Education

- starting **Postdoc in Robotics**, *University of Toronto*.
- 09 2022 Development of mathematical tools for more resilient robots and intelligent vehicles  
**Supervisor:** Tim Barfoot
- 03 2022– **Postdoc in Robotics**, *Laval University, Canada*.
- 09 2022 Supervision of several research projects around field robotics in nordic environments, aiming for publication at ICRA 2023.  
**Supervisor:** François Pomerleau
- 2018–2021 **Ph.D. in Robotics**, *Clermont Auvergne University (UCA), France; Laval University, Canada*.  
Development of a theoretical framework for meaningful risk assessment in occupancy grids.  
**Supervisors:** Romuald Aufrère (UCA), François Pomerleau (Laval University), Roland Chapuis (UCA), Christophe Debain (National Research Institute for Agriculture, Food and the Environment)
- 2017–2018 **Master Degree in Robotics**, *Clermont Auvergne University*.  
Ranked 1/24.
- 2015–2018 **Engineering Degree in Computer Science and Modeling**, *Institut Supérieur d'Informatique, de Modélisation et de leurs Applications*.  
Ranked 2/120.

## Professional activities

- 2021 **Research Internship**, *Laval University, Quebec City, Canada, 2 Months*.  
Collaboration with the Northern Robotics Laboratory (Norlab), leading to the publications of Baril *et al.* [8] and J. Laconte *et al.* [9].
- 2021 **I-SITE IMOB3 Research Grant representative**.  
Ph.D. student representative of the I-SITE Clermont label, granting 10M euros per year for the research institute.
- 2018–2021 **Reviewing Services**.  
Reviewing of 5 conference papers (ICRA, IROS, ITSC) and 1 journal paper (RA-L).
- 2018–2021 **Organization of seminars**.  
Organization of various seminars in the research department.
- 2020 **Research Internship**, *Laval University, Quebec City, Canada, 2 Months*.  
Collaboration with the Northern Robotics Laboratory (Norlab), leading to the publications of Baril *et al.* [3] and Vaidis *et al.* [7].
- 2019 **Winter School**, *National Institute for Research in Digital Science and Technology (INRIA), Sophia Antipolis, France, 1 Week*.  
Winter school covering the basics in both mobile and manipulative robotics.
- 2018 **Research Internship**, *Laval University, Quebec City, Canada, 5 Months*.  
Investigation of the measurements bias coming from a light detection and ranging (lidar) sensor. Modeling of the return waveform and design of an experimental setup. Lead to the publication of J. Laconte *et al.* [2].
- 2017 **Internship**, *Thales, Elancourt, France, 5 Months*.  
Evaluations and improvements of state-of-the-art LIDAR Simultaneous Localization And Mapping (SLAM) algorithms.

## 2016–2018 Robotics Competitions.

Took part in several national and international robotics competitions (Robot Challenge, French Robot Cup, *La Nuit du Hack*, *Reconnaissance des Formes et Intelligence Artificielle*)

## Grants and Distinctions

- 2020 **Best Robot Vision Paper Award**, *Conference on Robots and Vision (CRV)*.  
For the paper: "Evaluation of Skid-Steering Kinematic Models for Subarctic Environments" [3]
- 2020 **Finalist for Best Student Paper Award**, *International Conference on Control, Automation, Robotics and Vision (ICARCV)*.  
For the paper: "An Information Driven Approach For Ego-Lane Detection Using Lidar And Open-StreetMap" [5]
- 2018 **Doctoral Research Grant**, *Innovative Mobility: Smart and Sustainable Solutions (IMOB3) Program*.
- 2018 **Graduate Research Grant**, *WOW! Wide Open to the World Program from I-Site CAP2025 project*.

## Languages

<b>English</b>	Fluent, TOEIC certificate	<b>French</b>	Native Speaker
<b>Chinese</b>	Basic Level, HSK2 certificate	<b>German</b>	Notions

## Teaching

- 2018–2021 **Digital Signal Processing**, *Graduate course*.  
Graduate course about Discrete Fourier Transform, Z transform, signal filtering and their applications.
- 2018–2021 **Control Theory**, *Graduate course*.  
Graduate course about Laplace transform, regulation, modeling and analysis of continuous systems.
- 2018–2021 **Projects Supervision**, *Graduate students*.  
Supervision of four robotics graduate projects of 60 or 120 hours per person.
- 2020 **Internship Mentoring**, *Ph.D. candidate student*.  
Mentoring of a graduate student working on path-planning algorithms.

## Scientific Publications

- [1] **J. Laconte**, C. Debain, R. Chapuis, F. Pomerleau, and R. Aufrère, "Lambda-field: A continuous counterpart of the bayesian occupancy grid for risk assessment," in *2019 International Conference on Intelligent Robots and Systems (IROS)*, 2019, pp. 167–172.
- [2] **J. Laconte**, S.-P. Deschênes, M. Labussiere, and F. Pomerleau, "Lidar measurement bias estimation via return waveform modelling in a context of 3d mapping," in *2019 International Conference on Robotics and Automation (ICRA)*, IEEE, 2019, pp. 8100–8106.
- [3] D. Baril, V. Grondin, S.-P. Deschênes, **J. Laconte**, M. Vaidis, V. Kubelka, A. Gallant, P. Giguere, and F. Pomerleau, "Evaluation of skid-steering kinematic models for subarctic environments," in *2020 17th Conference on Computer and Robot Vision (CRV)*, IEEE, 2020, pp. 198–205.
- [4] A. Kasmi, **J. Laconte**, R. Aufrère, D. Denis, and R. Chapuis, "End-to-end probabilistic ego-vehicle localization framework," *IEEE Transactions on Intelligent Vehicles*, vol. 6, no. 1, pp. 146–158, 2020.
- [5] A. Kasmi, **J. Laconte**, R. Aufrère, R. Theodose, D. Denis, and R. Chapuis, "An information driven approach for ego-lane detection using lidar and openstreetmap," in *2020 16th International Conference on Control, Automation, Robotics and Vision (ICARCV)*, IEEE, 2020, pp. 522–528.
- [6] M. Labussière, **J. Laconte**, and F. Pomerleau, "Geometry preserving sampling method based on spectral decomposition for large-scale environments," *Frontiers in Robotics and AI*, vol. 7, 2020.

- [7] M. Vaidis, **J. Laconte**, V. Kubelka, and F. Pomerleau, "Improving the iterative closest point algorithm using lie algebra," in *IROS 2020 Workshop: Bringing geometric methods to robot learning, optimization and control*, 2020.
- [8] D. Baril, S.-P. Deschênes, O. Gamache, M. Vaidis, D. LaRocque, **J. Laconte**, V. Kubelka, P. Giguère, and F. Pomerleau, "Kilometer-scale autonomous navigation in subarctic forests: Challenges and lessons learned," *arXiv preprint arXiv:2111.13981*, 2021.
- [9] **J. Laconte**, A. Kasmi, R. Aufrère, M. Vaidis, and R. Chapuis, "A Survey of Localization Methods for Autonomous Vehicles in Highway Scenarios," *Sensors*, 2021.
- [10] **J. Laconte**, A. Kasmi, F. Pomerleau, R. Chapuis, L. Malaterre, C. Debain, and R. Aufrère, "A novel occupancy mapping framework for risk-aware path planning in unstructured environments," *Sensors*, vol. 21, no. 22, p. 7562, 2021.
- [11] **J. Laconte**, E. Randriamiarintsoa, A. Kasmi, F. Pomerleau, R. Chapuis, C. Debain, and R. Aufrère, "Dynamic lambda-field: A counterpart of the bayesian occupancy grid for risk assessment in dynamic environments," in *2021 International Conference on Intelligent Robots and Systems (IROS)*, 2021.
- [12] J. Morceaux, **J. Laconte**, E. Randriamiarintsoa, T. Morell, L. Malaterre, D. Denis, R. Aufrère, and R. Chapuis, "Toward a generalized risk assessment method on occupancy grids," in *IROS 2021: Late Breaking Results*, 2021.