

Johann Laconte

Ph.D. Student, Post-Doc Applicant

08 rue d'Assas
63000 Clermont-Ferrand
France
☎ (+33)7 82 21 02 20
✉ laconte.johann@gmail.com
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Education

- 2018–2021 **Ph.D. in Robotics**, *Clermont Auvergne University (UCA), Laval University*.
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 of the class.
- 2015–2018 **Engineering Degree in Computer Science and Modeling**, *Institut Supérieur d'Informatique, de Modélisation et de leurs Applications*.
Ranked 2/120 of the class.

Professional activities

- 2018–2020 **Reviewing Services**.
Reviewing of 4 conference papers (ICRA, IROS, ITSC) and 1 journal paper (RA-L).
- 2018–2020 **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 D. Baril *et al.*, "Evaluation of skid-steering kinematic models for subarctic environments," in *2020 17th Conference on Computer and Robot Vision (CRV)*, IEEE, 2020, pp. 198–205
- 2020 **Finalist for Best Student Paper Award**, *International Conference on Control, Automation, Robotics and Vision (ICARCV)*.
For the paper A. Kasmi *et al.*, "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

- 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

English	Fluent, TOEIC certificate	French	Native Speaker
Chinese	Basic Level, HSK2 certificate	German	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.
- 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. Labussière, 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*, 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*, 2020.
- [7] M. Vaidis, **J. Laconte**, V. Kubelka, and F. Pomerleau, "Improving the iterative closest point algorithm using lie algebra," *2020 International Conference on Intelligent Robotics and Systems (IROS) Workshop "Bringing geometric methods to robot learning, optimization and control Workshop"*, 2020.
- [8] **J. Laconte**, A. Kasmi, F. Pomerleau, R. Chapuis, L. Malaterre, C. Debain, and R. Aufrère, "Lambda-field: A continuous counterpart of the bayesian occupancy grid for risk assessment and safe navigation," *Submitted to the International Journal of Robotics Research (IJRR)*, 2021.
- [9] **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," *Submitted to the 2021 International Conference on Intelligent Robots and Systems (IROS)*, 2021.