# ILIA SEVOSTIANOV

### **Computer Vision Engineer**

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**♀** Innopolis, Russia



## **EXPERIENCE**

### CV engineer

### **Autonomous Technologies Laboratory**

## February 2021 -

**♀** Innopolis, Russia

- Development of LED marker system for precise drone landing
- Development of safe landing system for UAV
- Development of LDWS system for electronic bus

### **Engineer Assistant**

#### **JBL Robotics**

August 2018 - February 2019 Moscow, Russia

- Developed ROS nodes to control a barista robot
- Designed cup holders and a gripper for the robot itself.

## **SKILLS**

Python C++, C

**MATLAB** 

**ROS** 

Linux

Git

CAD (SolidWorks, KOMΠAC 3D

CV (OpenCV, CUDA, PyTorch, Detectron2)

Tex



English Russian



## **EDUCATION / COURSES**

Robotics and Computer Vision Master Degree Innopolis University

## August 2019 - August 2021

Robotics and Mechatronics Bachelor's degree Bauman Moscow State Technical University

## **PROFILES**

#### Github

 The main profile on which open source code and projects are available

### WebSite

• Private website-portfolio

### LinkedIn

• LinkedIn link

## **ACHIEVEMENTS**

- Diploma for Outstanding Contribution to Science, 2021 year, Innopolis University
- Diploma for Outstanding Academic Achievements (full calendar year 2020) and Extracurricular Achievements, 2020 year, Innopolis University
- Aerobot 2020 competition . Victory. The line and landing platform of the UAV detection
- Best Student of the Robotics Department,
  2018 year, Bauman Moscow State Technical University

# **PUBLICATIONS**

- ИВАНЮТЕНКО В. Е. и др. СИСТЕМА ОПРЕДЕЛЕНИЯ ЗОНЫ ПРИЗЕМЛЕНИЯ БПЛА ДЛЯ ЗАДАЧИ БЕЗОПАСНОЙ АВТОНОМНОЙ ПОСАДКИ // Школа молодых новаторов. 2021. С. 98-101.
- Kirsanov D. et al. Stiffness analisys of the Tripteron parallel manipulator //2020 International Conference Nonlinearity, Information and Robotics (NIR). IEEE, 2020. C. 1-6.
- Kalinichenko S. V. et al. Simulation in MATLAB of a vertical walking three-link robot //AIP Conference Proceedings. – AIP Publishing LLC, 2019. – T. 2195. – №. 1. – C. 020008.