

# Mina SORIAL

R&D Software Engineer (Sensor Fusion, Machine Learning, Computer Vision)  
✉ mina.sorial@outlook.com | 📞 (+20) 1062739441 | 🌐 mina-sorial | 📍 Alexandria, Egypt

## EDUCATION

**ÉCOLE CENTRAL DE NANTES**  
M.Sc.ENG IN ADVANCED ROBOTICS  
2014- 2016 | Nantes, France

**ALEXANDRIA UNIVERSITY**  
BSC IN ELECTRONICS AND  
TELECOMMUNICATION  
2009- 2014 | Alexandria, Egypt

## DIPLOMAS

**ITI EGYPT**  
DIPLOMA IN SOFTWARE TESTING  
2017 | Alexandria, Egypt

## COURSEWORK

### GRADUATE

- C++ programming techniques
- Ros programming
- Computer vision
- Artificial intelligence
- Software architectures for robotics
- Intelligent vehicles
- Robotics control and modeling

### ONLINE

- Machine learning (Coursera/Stanford)
- Advanced kalman filtering and sensor fusion (udemy)
- Deep Learning Specialization (Coursera)

## OTHER ACTIVITIES

**CONFERENCES**  
OCEANS 2019 MTS/IEEE (Speaker)  
Seattle, WA, USA

**SUMMER SCHOOLS**  
(MLCC 2019) Machine Learning Crash  
Course (MIT - IIT - UNIGE)  
Genova, Italy

**WORKSHOPS**  
(BTS 2018) Breaking the Surface  
Biograd na Moru, Croatia

## PERSONAL SKILLS

- Problem solving
- Teamwork
- Self-motivation
- Curiosity
- Willingness to learn

## EXPERIENCE

### DIBRIS, UNIVERSITÀ DEGLI STUDI DI GENOVA

PHD CANDIDATE BIO-ENGINEERING AND ROBOTICS

October 2017 - May 2022 | Genova, ITALY

Project : Obstacle Detection System for Unmanned Surface Vehicle.

Supervisors : Profs. **Enrico SIMETTI**, **Francesca Odone**, **Giuseppe CASALINO**.

- Implementation of obstacle detection system for unmanned surface vehicle.
- Explore different types of detection sensors, Camera, LIDAR, and Radar.
- Propose an efficient object detection and tracking procedure to track objects across frames, exploiting YOLO object detection.
- 3D point cloud registration, segmentation and clustering.
- Implement Sensor fusion between camera, 3D LIDAR, and USV odometry information to locate obstacles in the world reference frame estimating their location heading and velocity.

Status: Withdrawn due to some health issues

### LS2N, ÉCOLE CENTRAL DE NANTES

RESEARCH ENGINEER INTERN (MASTER THESIS)

Jan 2016 – July 2016 | Nantes, France

Project: Real-time Platooning in Unknown Environment

Supervisors: Profs. **Philippe MARTINET**, **Olivier KERMORGANT**

- The implementation of platooning control system in which the vehicles automatically follow a manually driven leader car in Urban Environment. Under (Ubuntu, C++, Ros) environment.

### BRIGHTSKIES | EMBEDDED SOFTWARE ENGINEER INTERN

Summer 2013 | Alexandria, Egypt

- Design a car locking system using embedded C and a specially designed Kit.

## SKILLS

### SOFTWARE ENGINEERING

- Programming languages and tools  
C++   Python   C (basic)   Java (basic)   OpenCV  
PCL   ROS   Tensorflow (basic)   Matlab   L<sup>A</sup>T<sub>E</sub>X
- Agile software development
- Software Testing (Certified ISTQB Foundation Level)
- SDLC, STLC

### ROBOTICS

- Computer vision (Image Processing, Features detection and tracking, Visual geometry, Camera calibration, Pose Estimation)
- Artificial Intelligence (NN, CNN, RNN, LSTM, Hyperparameter Tuning, Regularization, Optimization)
- Localization, Bayesian Estimation, Sensor fusion (KF, EKF, UKF)
- Robotics modeling and control

## PUBLICATIONS

- [1] M. Sorial, I. Mouawad, E. Simetti, F. Odone, and G. Casalino. Towards a real time obstacle detection system for unmanned surface vehicles. In *OCEANS 2019 MTS/IEEE SEATTLE*, pages 1–8, 2019.