





Maxime Noizet

Robotics engineer, Ph.D.



27 yo, driving license

Compiègne, France

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Education

2021 2024	PhD in Robotics Université de Technologie de Compiègne, Sorbonne Universities Alliance (UTC)
2015 2020	Computer Engineering UTC <i>Specialization: Real-Time Systems and Embedded Computing</i>
2019 2020	Master's Degree in Automatic Control and Robotics of Intelligent Systems UTC

Courses

Nov. 2022	Use of GNSS for Precision Positioning ENSG
Ongoing	Professional Certificate: IBM AI Engineering Coursera

Languages

French	● ● ● ● ●
English	● ● ● ● ●
German	● ● ● ● ●
Japanese	● ● ● ● ●

Skills

Writing, Analysis, Autonomy, Adaptability, Collaboration, Project Management, Communication, Dissemination, Teaching, Popularization

References

Dr. Philippe XU
philippe.xu@ensta-paris.fr

Pr. Philippe BONNIFAIT
philippe.bonnifait@hds.utc.fr

Dr. Jean-Benoist Léger
jbleger@hds.utc.fr

Experience

Jan. 2025 July 2025	CNRS Research Engineer Robotic Perception and Localization	Heudiasyc, CNRS
July 2021 Dec. 2024	CNRS PhD Candidate in Robotics <i>Multi-sensor perception with vector maps for autonomous vehicle localization</i> <ul style="list-style-type: none">★ Integration of lidars and cameras with georeferenced elements from vector maps for localization★ Multimodal automatic annotation for images and lidar data★ Adaptation of object detection algorithms★ Multi-sensor fusion for localization in complex environments	Heudiasyc, CNRS, UTC
Nov. 2020 June 2021	CNRS Research Engineer Localization integrity for autonomous vehicles, development of a 1D approximation module for data fusion	Heudiasyc, CNRS
Feb. - Oct. 2020	Research Engineer Intern Long-term trajectory prediction for detected vehicles in complex urban environments	Renault Group, UTC
Sept. 2018 Feb. 2019	Assistant Engineer Intern Development of a visual programming feature for a CAD data optimization software	PiXYZ Software

Technical skills

General	Robotics, Intelligent vehicles, real-time software development, embedded systems, multi-sensor fusion, perception, machine learning, statistics, numerical analysis, automatics
Languages	C++, C, Python, LaTeX, R, Matlab, Assembly, UML, SQL
Technologies	ROS, Git, Qt, Docker, Eigen, PCL, Numpy, Scipy, Pandas, Scikit-learn, Scikit-image, OpenCV, Jupyter, Tensorflow, Cython

Projects

2021-2024	European Project: ERASMO (EUSPA) <ul style="list-style-type: none">★ <i>Role: Responsible for integration, data acquisition, demonstrations, and validation. Participation in dissemination activities.</i>★ High-integrity and high-precision localization system for autonomous navigation based on a multi-constellation GNSS PPP-RTK receiver, cameras, and lidars★ Development of road feature detectors and a data association module using vector maps★ Partners: GMV, Renault Group, Septentrio, Artisense, Nextium	Heudiasyc, CNRS
Spring 2021	National Project: Tornado (Ministry of Industry) Preparation for the demonstration: vehicle and infrastructure integration, scenario planning	Heudiasyc, CNRS
Autumn 2019	European Project: ESCAPE (GSA) Development of tools for localization integrity evaluation and visualization for demonstration	Heudiasyc, CNRS
Autumn 2019	Student Project: Teleoperation of Autonomous Vehicles Mission execution with real-time obstacle detection, obstacle avoidance maneuvers proposed by the teleoperator	UTC

Publications

June 2023	Map-aided annotation for pole base detectionIV23, Anchorage, USA
September 2023	Pole-based Vehicle Localization with Vector Maps: A Camera-LIDAR Comparative Study ITSC23, Bilbao, Spain
October 2024	Automatic Image Annotation for Mapped Features Detection IROS24, Abu Dabi, UAE