

Autonomy Engineer - Lidar/Perception Expert

Want to build LiDAR perception software that powers a rapidly growing fleet of autonomous robots in real-world logistics environments?

A high-growth UK robotics company is scaling fast. They're operating hundreds of robots in live customer environments and building the autonomy stack that will support thousands more.

They're hiring an Autonomy Engineer (LiDAR/Perception) to develop and scale the LiDAR-based perception and SLAM systems at the core of a Robot-as-a-Service platform.

If you're excited by the challenge of building reliable, scalable LiDAR perception for real-world autonomous robots - and want to be part of a team moving at startup speed - this is a role worth exploring.

What you'll be doing:

- Developing and maintaining autonomy software for deployed robotic systems
- Working with ROS2, modern C++ and Python
- Developing and maintaining LiDAR odometry and SLAM approaches
- Collaborating with deployment teams to support complex field operations
- Designing and validating sensor placement for optimal coverage and robustness

What they're looking for:

- Solid understanding of LiDAR-based SLAM algorithms (e.g. Cartographer, LOAM, LIO-SAM, HDL Graph etc.)
- Experience with pose graph optimisation, scan matching, and sensor fusion
- Familiarity with Open3D or PCL for point cloud processing
- Understanding of state estimation frameworks
- Experience integrating 3D and 2D LiDARs
- Knowledge of LiDAR calibration (IMU, camera, robot base)
- Familiarity with sensor synchronisation, timestamp alignment, and coordinate transformations
- Linux, Git, CI/CD, and containerisation skills

Strong advantage if you have:

- Experience designing robotics software at scale
- LiDAR-based segmentation or other perception pipelines
- Contributions to open-source robotics projects
- Participation in RoboCup, Formula Student AI, DARPA-style competitions

They move fast. Standards are high. Ownership is real.

On-site x3 days per week in Oxfordshire.

Apply now for immediate consideration.