
PEP LLUIS NEGRE

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Principal Computer Vision Engineer

Experience

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| 2020 - Current | <p>Principal Computer Vision Engineer</p> <p><i>ROVCO Subsea, United Kingdom</i></p> <p>Researching and prototyping emerging computer vision technologies to guide subsea exploration and inspection. Designing and developing the core of Rovco's cutting-edge live 3D vision for ROVs and AUVs. Working on tackling challenging underwater imagery problems to keep improving camera pose accuracy and dense 3D models.</p> |
| 2017 - 2020 | <p>Senior Computer Vision Engineer</p> <p><i>ROVCO Subsea, United Kingdom</i></p> <p>Designing online 3D underwater mapping algorithms, based on an accurate Visual-SLAM positioning system and semi-dense 3D reconstructions. I am developing cutting-edge solutions for reliable and impressive 3D underwater reconstructions to be executed online during the robot mission. The objective is to provide both ROVs pilots and technicians or inspectors with instant visualizations of marine structures.</p> |
| 2012 - 2017 | <p>Postgraduate Researcher</p> <p><i>Systems, Robotics and Vision Group, University of the Balearic Islands, Spain</i></p> <p>Co-responsible for the entire platform (software and hardware) of the autonomous underwater robot "Turbot". In charge of the whole localization pipeline based on various sensors: IMU, DVL, USBL, GPS and 2 stereo pairs. Specialized in stereo localization, loop closing detection and 3D reconstruction of the environment and the tools to visualize it.</p> <p>Responsible for the design and development of the operating interface of the vehicle based on HTML5, Google maps API and Rosbridge.</p> |
| 2012 - 2015 | <p>CEO at Binibook.com</p> <p><i>Binibook S.L.</i></p> <p>Lead of the platform to write and distribute books online. In charge of the website and apps developed for iOS and Android. Create value, manage the group and keep developing code in HTML5, Javascript, CSS, PHP, NodeJS, Xcode and Java.</p> |
| 2011 - 2012 | <p>Software Developer</p> <p><i>Sampol Communications S.L.</i></p> <p>Developing drivers for IAS/Wonderware, cameras, relies and many other sensors for factories and intelligent houses.</p> <p>Implementing power monitoring systems to improve the building efficiency with powerful web front-ends and databases.</p> <p>Responsible for the project of automatic reading of meters of water and electricity for the Palma de Mallorca Harbour's.</p> |
| 2009 - 2011 | <p>Control Engineer</p> <p><i>Alstom Power S.L.U.</i></p> <p>Responsible for the control design and tuning of the wind turbines ECO74 and ECO80.</p> <p>Specialized in system identification and fault-tolerant control in adverse weather conditions.</p> |

Education

2008 - 2010	Master Degree in Automatics and Robotics <i>University of Catalonia UPC, Spain</i> Advanced control techniques. Mobile robotics. Computer vision. Final grade: 8.23/10
2004 - 2008	Industrial Engineer in Industrial Electronics <i>University of the Balearic Islands, Spain</i> Computer vision. Robotics. Electronics. Control theory. Final grade: 6.74/10
2002 - 2004	Bachelor Degree Scientific-technological <i>IES Guillem Colom Casasnovas, Soller, Spain</i>

Skills

Tools & libraries

Expert in Linux command line, SSH, ROS, OpenCV, PCL, ceres-solver, g2o, git and docker.

Software

Senior programmer in C++ and web.

High background in python, C#, Java and Matlab.

Robotics

5+ years of experience in robotics systems development and operation. Highly focused on robot localization, sensor fusion and stereo vision-based localization systems.

Languages

Spanish and Catalan native.

English fluid (speaking, reading, writing).

Relevant Publications

P. L. Negre, F. Bonin-Font, G. Oliver. Global Image Signature for Visual Loop-Closure Detection. In Autonomous Robots, Published Online, Springer US, vol. 40, pp. 1403-1417, December 2016.

P. L. Negre, F. Bonin-Font, G. Oliver. Cluster-Based Loop Closing Detection for Underwater SLAM in Feature-Poor Regions. In IEEE International Conference on Robotics and Automation (ICRA), Stockholm (Sweden), 2016. **BEST STUDENT PAPER AWARD FINALIST.**

P. L. Negre, F. Bonin-Font, M. Massot, G. Oliver. Stereo-Vision Graph-SLAM for Robust Navigation of the AUV SPARUS II. In IFAC Workshop on Navigation, Guidance and Control of Underwater Vehicles (NGCUV), Girona, 2015.

P. L. Negre, F. Bonin-Font, G. Oliver. Stereo Graph-SLAM for Autonomous Underwater Vehicles. In Intelligent Autonomous Systems 13 (Proceedings of the 13th International Conference on Intelligent Autonomous Systems IAS13), Padova/Venice, pp. 351-360, 2014.

Patents

I. Wallace, L. Hill, B. Allen, P.L. Negre. 2019. Subsea camera module and multi camera system. GB2570748 / EP3712558, filed September 4, 2018, and issued December 3, 2019.

I. Wallace, L. Hill, P.L. Negre. N. Read. 2020. Subsea surveying system. GB2582554, filed March 21, 2019, and issued September 30, 2020.

Portfolio

Author or main contributor of the following repositories:

- [Stereo Slam](#). A stereo camera SLAM system, based on my paper of ICRA'16. Nominated for the best student paper award.
- [Libhaloc](#). A loop closure detection system, based on my paper of Autonomous Robots.

- Many contributions to ROS most popular visual odometers: [viso2](#) and [fovis](#).
- 3D mapping and reconstruction:
 - * Rema (private repo). A full registration and mapping library for stereo cameras, using PNP for image to image registration, g2o for graph optimization and Ceres Solver for bundle adjustment.
 - * [Uware](#). Simple tool for image to image registration, based on PNP and ICP.
- 3D visualization
 - * [Pointcloud web viewer](#). A 3D pointcloud web viewer ([sample page](#)).
- Sensor drivers:
 - * Camera drivers: https://github.com/srv/pg_spinnaker_camera and https://github.com/srv/prosilica_driver
- More than 600 public contributions in the last year from my github account: <https://github.com/plnegre>.

Other repositories that I am the owner or main contributor but are private due to licensing or security restrictions:

- ORB Tracker: visual odometry based on the popular ORB_SLAM2 algorithm.
- Collision avoidance: a local planner approach to avoid collisions, based on an octomap fed by stereo depth maps.
- Robot missions: web interface to teleoperate, setup autonomous missions and monitor the status of the robot.