Personal Data

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Born 12. 23. 1976 in Bayonne, France

Profile	I'm strongly interested in *computer vision for robotics*.

Education

2003	**PhD degree** in computer science and robotics, from Paul Sabatier University, Toulouse. I did my PhD in the Robotics and Artificial Intelligence Group of LAAS-CNRS, Toulouse, France. My thesis was about the use of planar, visual landmarks by mobile robots to perform the navigation task.
1999	**DEA degree** (French equivalent of Master Degree) in Artificial Intelligence and Pattern Recognition in Pierre and Marie Curie University (Paris VI)
1999	**Engineer degree** from École Nationale Supérieure de Techniques Avancées (ENSTA), top-ranked French "Grande école". My specialization was mainly centered on image processing, automatics and robotics.

Studentships

1999-2003	BDI Ph.D. studentship from *CNRS*.

Foreign Languages

French	mother tongue
English	fluent (with strong french accent)
Spanish	fluent (with strong mexican accent)
German	beginner

Computing Skills

Plaftorms	Windows 32s, UNIX (Solaris,Linux,OpenBSD)
Programming	C,C++ (advanced), Tcl/Tk, Java, HTML,PHP (beginner).
Applications	Matlab, LaTeX, emacs, Word, PowerPoint, Image processing softwares (Khoros, Aphelion)....
Areas	Artificial Intelligence, Robotics, Automatics, Computer Vision, Image Processing.

Work experience and realizations

1999-2003	Development of visual-based localization functions for a mobile robot at LAAS-CNRS. Integration onboard of the LAAS XR4000 robot.
2000-2001	Short stay at University of Illinois at Urbana-Champaign (Beckman Institute). Development of strategies to use visual landmarks in qualitative navigation.
1998	Development of a MS Access database and interface for Peugeot SA to improve the recycling process of used cars.

Teaching

2000	Image Processing Practical Works at Paul Sabatier University

Publications

Conferences

N. Arana, F. Lerasle, M. Briot, C. Lemaire & J.B. Hayet. *A Smart Sensor based Visual Landmarks Detection for Indoor Robot Navigation*. In Proc. Int. Conf. on Pattern Recognition (ICPR'02), Quebec, 2002.

V. Ayala, J.B. Hayet, F. Lerasle & M.Devy. *Visual Localization of a Mobile Robot in Indoor Environments using Planar Landmarks*. In Proc. Int. Conf. on Intelligent Robots ansd Systems (IROS'00), Tokyo, 2000.

J. Carbajo, F. Lerasle, M. Devy & J.B. Hayet. *Environment Modeling for Topological Navigation using Visual Landmarks and Range Data*. In Proc. Int. Conf. on Robotics and Automation (ICRA'03), 2003.

J.B. Hayet, F. Lerasle & M. Devy. *Planar Landmarks to Localize a Mobile Robot*. In Proc. Int. Symp. on Intelligent Robotic Systems (SIRS'00), 2000.

J.B. Hayet, C. Esteves, M. Devy & F. Lerasle. *Qualitative environment modeling with cooperating visual and range sensors*. In Proc. Int. Conf. on Intelligent Robots ansd Systems (IROS'02), Lausanne, 2002.

J.B. Hayet, F. Lerasle & M. Devy. *A Visual Landmark Framework for Indoor Mobile Robot Navigation*. In Proc. Int. Conf. on Robotics and Automation (ICRA'02), Washington, 2002.

P. Ranganathan, J.B. Hayet, M. Devy & F. Lerasle. *Topological navigation and Qualitative localization for indoor environment using Multisensory perception*. In Proc. Int. Symp. on Intelligent Robotic Systems (SIRS'01), Toulouse, 2001.

Journals

P. Ranganathan, J.B. Hayet, M. Devy & F. Lerasle. *Topological navigation and Qualitative localization for indoor environment using Multisensory perception*. Robotics and Autonomous Systems, vol. 41, no. 3, pages 137–144, 2002.

Interests

Music, Movies, Cycling, Hiking, Soccer.

History and Archeology.

Toulouse, 6th February 2003