

Poncelet Renaud
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French teacher on leave
and Ph.D. student at Inria in Robotics on Trajectory Planning for Autonomous Vehicles.

Publications

R. Poncelet, A. Verroust-Blondet and F. Nashashibi. Safe Geometric Speed Planning Approach for Autonomous Driving through Occluded Intersections. *ICARCV 2020 - International Conference on Control, Automation, Robotics and Vision*, December 2020.

P. de Beaucorps, A. Verroust-Blondet, R. Poncelet and F. Nashashibi. RIS : A Framework for Motion Planning among Highly Dynamic Obstacles. *ICARCV 2018 - International Conference on Control, Automation, Robotics and Vision*, November 2018.

Academic background

2017 - 2018	Master 2 in Intelligent Robotic Systems	Université Pierre et Marie Curie (France - 75)
2017	Agrégation competitive exam in Industrial Sciences for Engineers, Option : Mechanics	
2016 - 2017	Master 2 in Mechanics SPI, Option : Teaching Mechatronics	Université de Rennes 1 (France - 35)
	Magister Degree in Mechatronics 3 rd year	Ecole Normale Supérieure de Rennes (France - 35)
2015 - 2016	Master 1 in STS Electronics and Telecommunications	Université de Rennes 1 (France -35)
	Master 1 in STS Mechanics and Engineering Sciences	Université de Rennes 1 (France -35)
	Magister Degree in Mechatronics 2 nd year	Ecole Normale Supérieure de Rennes (France - 35)
2014 - 2015	License in STS Electronics and Telecommunications	Université de Rennes 1 (France - 35)
	Licence in STS Mechanics and Engineering Sciences	Université de Rennes 1 (France - 35)
	Magister Degree in Mechatronics 1 st year	Ecole Normale Supérieure de Rennes (France - 35)
2012 - 2014	Classe préparatoire to the Grandes Ecoles, Option : Physics, Techniques and Engineering Sciences	Lycée Dorian à Paris (France - 75)

Professional background

Teaching

2021-2022	Secondary Teacher in Industrial Engineering Sciences, Option : Mechanical Engineering	Lycée Polyvalent de Cachan (France - 94)
2019 - 2021	Lectures :	Sorbonne Universités / Polytech (France – 75)
	C language (L2)	Sorbonne Universités
	Object oriented programming / Python (M1)	Sorbonne Universités
	Parametric Identification (L3)	Polytech
	Automatic (M1)	Polytech
	Image processing (M1)	Polytech
2019	Mechatronics Fundamentals (M1)	ESILV – Paris (France – 75)

Research

2018 - 2022	Ph.D. Autonomous Navigation in the Presence of Highly Dynamic Obstacles with Uncertain Motion	Inria Paris (France – 75)
2018 6 months	Internship Path Planning in the Presence of Highly Dynamic Obstacles	Inria Paris (France – 75)
	Optimization of a Sensor Fusion for 3D Positioning	Master 2 UPMC (France – 75)
2016 2 months	Internship Integration of a Steam Cleaning Cable Robot for Autonomous Cleaning of Building Windows	Université de Laval (Canada - Québec)
2016	Participation in the Conception and Realization of an Electric Vehicle for the: "Shell Eco-Marathon" project in the Urban Concept category	Ecole Normale Supérieure de Rennes (France – 75)
2015	Design and Realization of an Automatic Xylophone for the : "Mechatronic instrument" project	Ecole Normale Supérieure de Rennes (France – 75)

Competencies

Software :

Carla, UnrealEngine, Blender, Reason, Matlab, Scilab, SolidWorks, Catia, Autodesk, Wireshark, Maple

Programming :

Python, Kotlin, C#, C, C++, ROS, Arduino, Assembleur sur dsp, VHDL, API langages, Grafcet, Ladder,
UML...

Languages

English – French