STEFAN LARSEN

DATE OF BIRTH 14th September 1998

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PUBLICATIONS:

Conferences:

- Larsen, S., Malis, E., Mouaddib, E. M. and Rives, P., "Change Detection and Model Update Framework for Accurate Long-Term Localization", IEEE/RSJ IROS Standing the Test of Time Workshop, 2024

Journals:

- Larsen, S., Helgesen, H. H., Walmsness, J. E., Kufoalor, G. K. M. and Johansen, T. A., "Automatic docking with extended dynamic positioning", Journal of Marine Science and Technology, 2024

- Walmsness, J. E., Helgesen, H. H., **Larsen, S.**, Kufoalor, G. K. M. and Johansen, T.A., "Automatic dock-to-dock control system for surface vessels using bumpless transfer", Ocean Engineering, 268, p.113425, 2023

EDUCATION:

2022 – 2025	Doctorat Informatique, Nice Université Côte d'Azur, France
2017 – 2022	Engineer, Cybernetics and robotics, NTNU Trondheim, Norway
2021, 1 week	ATHENS Programme at Télécom Paris, France
2016, 2 months	Exchange in Victoria, BC, Canada
2014 – 2017	Ski Upper Secondary School

WORK EXPERIENCE:

2022 – 2025 **PhD Student in Robotics – Centre Inria d'Université Côte d'Azur**
Researching on detection of change and update of environmental representation using sensor data acquired by multiple collaborative robots, for long-term localization and monitoring.

November – June 2021-2022 **Software Developer – Maritime Robotics AS**
Worked on dynamic positioning control and state observers for autonomous marine vessels, performing tests in simulator and field. Designing MPC algorithm for model identification of USV, and Kalman filter for observing environmental forces, using only GPS. Implemented and tested the methods on USV, with purpose to improve control during challenging conditions.

STEFAN LARSEN

August – December 2021	**Student Assistant – NTNU** Provided help and guidance for students taking the course Algorithms and Data Structures.
June – August 2021	**Research Assistant – NTNU** Developed software for autonomous docking of smaller ferries including experimental testing in simulator and field, with satisfying results. Designed and implemented dynamic positioning algorithm for docking of USV using only GPS data, Kalman filter for observing environmental forces, and fault-tolerance system for robust docking.
September – August 2020 – 2021	**Software Developer – Vortex NTNU** Developed software for AUV in a student organization. Work with computer vision, SLAM, sensor interfacing and ROS. Using stereovision to perform mapping, depth estimation and object detection. Designed for AUV, for the purpose of performing tasks and avoiding obstacles underwater.
June – November 2018	**Fundraiser – Norwegian Red Cross** Recruit monthly donors to Red Cross by sales door to door and responsibility for follow-up and guidance of colleagues

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PROGRAMMING:	Python, C++, C, Julia, Matlab, Go, Git, Linux, ROS
LANGUAGES:	Norwegian, Danish, English - (fluent), French - (good), Italian (beginner)
INTERESTS:	Electronics, football, running, cooking, languages, music, outdoor life