


INFORMAȚII PERSONALE

Markus Herrmann



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Sexul

FUNCȚIA, LOCUL DE MUNCĂ

Student doctorand în cadrul IOSUD – Universitatea Politehnică Timișoara, Colegiul Doctoral de Studii Inginerești, domeniul de doctorat „PATH DETECTION, ESTIMATION AND CORRECTION FOR ROBOT GUIDANCE”, sub conducerea științifică a prof.univ.dr.ing. Marius Otesteanu

EXPERIENȚA PROFESIONALĂ

Scrieți datele (01/2015- today)

Software-Engineer (CTO)

SOLID 3D Engineering GmbH, Im Foeckingsfeld, 45891 Gelsenkirchen

- Chief technology officer
- Software developer for 3D Robot measurements (C#/C++)
- Machine Learning / Deep Learning (C#/C++/Python)
- Research and development

Tipul sau sectorul de activitate Software engineering, chief technology officer

Scrieți datele (07/2008- 10/2014)

Software-Engineer (RnD)

VMT Bildverarbeitungssysteme GmbH Mallau Str. 50, 68219 Mannheim

- Implementations of 3D Robot guidance systems (C#, C++)
- Implementation of pattern recognition algorithms (C#, C++)
- Machine Learning (C#, Python)
- Planning and developments of software components

Tipul sau sectorul de activitate Software engineering (RnD)

Scrieți datele (10/2005- 07/2008)

Software-Engineer / Measurement Engineer

TecMedic GmbH Neidenburger Str. 43, 45897 Gelsenkirchen

- Software developer for 3D Robot measurements (JAVA/C++)
- 3D industrial measurements
- Integration of stochastic methods for minimal invasive surgery
- Assistance of science projects

Tipul sau sectorul de activitate Software engineering, education

EDUCAȚIE ÎN ÎNFORMARE

Scrieți datele (08/1998 – Today)

Universitatea Politehnică Timișoara

Scrieți nivelul EQF, dacă îl cunoașteți

Ph. D Program

Scrieți datele (08/1998 – 06/2001)

Fachhochschule Gelsenkirchen (University of Applied Sciences)

Scrieți nivelul EQF, dacă îl cunoașteți

- solution of the colinearity condition, and some applications of it. [No source information available], 1975.
- [10] H. Zhuang, Z. S. Roth, and R. Sudhakar. Simultaneous robot/world and tool/flange calibration by solving homogeneous transformation equations of the form $ax=yb$. IEEE Transactions on Robotics and Automation, 1994.
- [11] T. Shu, S. Gharaaty, W. Xie, A. Joubair, and I. A. Bonev. Dynamic path tracking of industrial robots with high accuracy by visual servoing. 2017 12th IEEE Conference on Industrial Electronics and Applications (ICIEA), 2017.
- [12] S. Ching-Long and Y. Lee. A simple robotic eye-in-hand camera positioning and alignment control method based on parallelogram features. Robotics 2018, 2018.
- [13] P. J. Besl and H. D. McKay. A method for registration of 3-D shapes. Pattern Analysis and Machine Intelligence, IEEE Transactions on, 1992.
- [14] S. Granger and X. Pennec. Multi-scale em-icp: A fast and robust approach for surface registration. European Conference on Computer Vision (ECCV 2002), volume 2353 of LNCS, 2002.
- [15] D. H. Douglas and T. K. Peucker. Algorithms for the reduction of the number of points required to represent a digitized line or its caricature. Cartographica: The International Journal for Geographic Information and Geovisualization, 1973.
- [16] M. Bonkovi, A. Hace, and K. Jezernik. A new method for uncalibrated visual servoing. 9th IEEE International Workshop on Advanced Motion Control, 2006., 2006.
- [17] P. Roebrock. Multi-sensor controlled assembly and application with manipulators. Universitatii Politehnica din Timisoara Seria Electronica si Telecomunicatii, 2009.
- [18] B. K. P. Horn. Tsai's camera calibration method revisited. MIT Press, Cambridge, Massachusetts and McGraw-Hill, New York.
- [19] D. C. Brown. Decentering distortion of lenses. Photogrammetric Engineering, May 1966.
- [20] K. Vijay, A. K. Rohatgi, Berthold, and Md. Ehsanes Saleh. An introduction to probability and statistics. Wiley Series in Probability and Statistics.
- [21] G. Golub and W. Kahan. Calculating the singular values and pseudo-inverse of a matrix. Journal of the Society for Industrial and Applied Mathematics Series B Numerical Analysis, 1965.

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Curriculum Vitae

- JSF
- Hibernate
- Continuous Integration
- OpenCV
- Machine Learning

IDE's/Tools:

- MS Visual Studio .NET
- MatLab (Octave)
- Eclipse (Eclipse CDT)
- TensorFlow (Keras)
- TeamCity
- Maven
- Git
- SVN
- TFS
- Jupyter Ntb

Operating systems:

- Linux
- Windows

Permis de conducere

Scrieți categoria permisului de conducere pe care îl dețineți. De exemplu:
AM/A1/A/B/C1/BE/C1E/CE/L

INFORMAȚII SUPLIMENTARE

- | | |
|-------------|---|
| Publicații | ▪ Automatisierung von Fertigungsprozessen großvolumiger Bauteile. 2010, Oldenburg |
| Prezentări | ▪ Verarbeitung von 3D-Laserlichtschnittsensordaten mit Smoothing Splines, 2012 Baden Baden, Germany |
| Proiecte | |
| Conferințe | ▪ Fast and robust point cloud matching based on EM-ICP prepositioning, 2012, Timisoara, Romania |
| Seminarii | |
| Distincții | ▪ A novel approach for automated car body panel fitting, 2013 Washington, DC, USA |
| Afilieri | ▪ An over-determined path correction algorithm for sparse dimensional Measurements, 2013 Cambridge, UK |
| Referințe | ▪ A method to determine the extrinsic parameter of laser triangulation sensors, with restricted mobility, 2014 Timisoara, Romania |
| Citări | ▪ A MAP estimator based on geometric Brownian motion for sample distances of laser triangulation data, 2016, Optics and Lasers in Engineering (Journal) |
| Cursuri | |
| Certificări | |

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