

Alan Papalia

Website: alanpapalia.github.io
Email: apapalia@mit.edu
LinkedIn: [alan-papalia-06883b105](https://www.linkedin.com/in/alan-papalia-06883b105)
GitHub: github.com/alanpapalia

EDUCATION

Massachusetts Institute of Technology PhD Robotics, Advisor: John Leonard	Cambridge, MA 2019–2024 (est)
University of Illinois at Urbana-Champaign BS Mechanical Engineering; Focus: Computer Science	Urbana, IL 2015–2019

EXPERIENCE

Massachusetts Institute of Technology Graduate Research Assistant, Simultaneous Localization and Mapping (SLAM)	Cambridge, MA Fall 2019 - Current
<ul style="list-style-type: none">– Leveraged Lagrangian duality to design optimality certification algorithm for range-only SLAM– Designed information theoretic, multi-agent path-planning algorithms, reducing localization error when compared to SOTA by up to 48% [1]– Developed nonlinear least-squares SLAM library for multi-robot systems with inter-robot ranging– Implemented metric embedding and semidefinite optimization algorithms for network localization to investigate application of inference algorithms in wireless contact tracing [2]	
Oregon State University Undergraduate Robotics Researcher	Corvallis, OR Summer 2018
<ul style="list-style-type: none">– Implemented object pose-tracking systems for robotic grasping experiments– Developed library for automated collection and processing of RGB-D images	

PUBLICATIONS

- [1] **A. Papalia** and J. Leonard, “Network localization based planning for autonomous underwater vehicles with inter-vehicle ranging”, in *2020 IEEE/OES Autonomous Underwater Vehicles Symposium (AUV)*, IEEE.
- [2] L. Clark, **A. Papalia**, J. T. Carvalho, L. Mastrostefano, and B. Krishnamachari, “Inter-mobile-device distance estimation using network localization algorithms for digital contact logging applications”, *Smart Health*, vol. 19, 2021.

PROJECTS

Outlier Resilient Point Cloud Registration

- Developed full pipeline for outlier resilient point cloud rejection, capable of running in under 100 ms
- Integrated state-of-the-art outlier rejection, up to 43% rejection rate under Gaussian noise

Low-Cost Collaborative Robot Localization

- Constructed low-cost robot (\$1200) for testing of collaborative range-only SLAM algorithms
- Benchmarked and integrated several state-of-the-art visual SLAM systems into low-cost robot network for research in feature-sparse and range-measurement based localization

SKILLS

- **Robotics:** SLAM, Optimization, Planning
- **Programming:** C++, Python, Julia, MATLAB
- **Libraries:** ROS, OpenCV, Pandas, CVX, GTSAM

SCHOLARSHIPS AND AWARDS

- WHOI Next Wave Fellowship (1 year full tuition)
- Illinois Engineering Achievement Scholarship
- GM Society of Automotive Engineers Award