Curriculum Vitae



Name:

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Actual Role:

Project Assistant at Chalmers University of Technology

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09/2018 **07/2021** Bologna	**Bachelor Degree in Physics :** I graduated with 110/110 with a thesis on the Loiano's Telescope Optimization for space debris detection.
11/2020 Bologna	**I joined the Unibo Motorsport Autonomous Driving Team**
09/2021 **10/2023** Bologna / Trondheim	**Master Degree in Artificial Intelligence :** I graduated with 110 L /110 with a thesis on an autonomous driving system for sailing boats. I have spent the second year in Trondheim (Norway) at the NTNU university thanks to the Erasmus project.
11/2023 **10/2026** Bologna	**PhD in Computer Vision applied to Autonomous Driving :** I started my PhD focusing on End-to-End autonomous driving systems, ending up publishing at ICRA 2025 my first research paper: *Drive with the Flow.* After that work I entered the world of event cameras focusing on stereo depth estimation. I have published a paper at ICCV 2025: *Depth AnyEvent: A Cross-Modal Distillation Paradigm for Event-Based Monocular Depth Estimation* and another one, accepted and in press in *IET Image Processing*: *Towards Event-based Stereo Depth Estimation at Millisecond Resolution.* The latter presents MADNet-ε, a model predicting disparity maps every 6.9 ms (about 145 FPS) that is the most accurate method on the DSEC benchmark when events are accumulated over only 10 ms.
09/2024 **10/2026** Bologna	**I was the Unibo Motorsport Autonomous Driving 1:10 scale Car Team Leader**

05/2025 Atlanta	**My team and I won the RoboRacer Autonomous Driving World Championship at Atlanta U.S.A.**
03/2026 **09/2026** Göteborg	**Research period abroad at Chalmers University of Technology :** Six months in the Department of Mechanical Engineering, hosted by Marco L. Della Vedova, working on metric monocular visual odometry in natural environments, where satellite positioning is unreliable. The resulting joint publication is under review at *IEEE Access*: *Metric Trajectory Estimation from First-Person Video of Runners in Forest Environments.*
06/2026 Vienna	**My team and I got the second and third position at the RoboRacer Autonomous Driving World Championship at Vienna Austria :** We entered two cars out of twenty-nine teams: the Atlanta-winning one, essentially unchanged, and a new one running the nonlinear Model Predictive Controller I developed, which replaces the previous pure-pursuit and Frenet overtaking pipeline with a single optimisation problem.
11/2026 **Now** Göteborg	**Project Assistant at Chalmers University of Technology :** After finishing my PhD I joined the Vehicle Engineering and Autonomous Systems division of the Department of Mechanical Engineering, the same group that hosted my research period abroad.