Dongnan Hu

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EDUCATION

East China University of Science and Technology **Shanghai, China**
Master in Control Engineering *September,2021-Present*

Supervisor: Prof. Yang Tang (IEEE Fellow)
GPA: 84.75/100.00 (9th among 182 students)

Nanjing Tech University **Nanjing, China**
B.S. in Mechanical Engineering *September,2018-June,2020*

PUBLICATIONS

- **ECC2024** *"Motion Planning and Control of Hybrid Flying-Crawling Quadrotors"*
  Dongnan Hu, Ruihao Xia, Xin Jin, Yang Tang.
  European Control Conference 2024 (Under review)
  Preprint: https://arxiv.org/abs/2312.08718
  Attached Video: https://youtu.be/G-84DAaqdJw

RESEARCH EXPERIENCE

"Motion Planning and Control of Hybrid Flying-Crawling Quadrotors"
Supervised by Prof. Yang Tang *June,2022-November,2023*

- I proposed a planner that generates hybrid terrestrial-aerial trajectories satisfying the kinematic and dynamic requirements of the multimodal quadrotors.
- Given the reliance on flight autopilots for crawling motions, quadrotors cannot independently adjust the speeds of every motor. I developed a controller enabling ground trajectory tracking within this constraint.

RESEARCH INTEREST

Autonomous Navigation, Motion Planning and Control

AWARDS AND ACHIEVEMENTS

- Second-class Scholarship for Master's Academic Achievement in the session of 2022-2023.
- First-class Scholarship for Master's Academic Achievement in the session of 2021-2022.
- Second Prize in the 18th "Huawei Cup" Chinese Graduate Mathematical Modeling Competition in December,2021.

KEY SKILLS

Programming Language	C/C++,Python
Research Tool	Matlab
Robot Tool	ROS,PX4
Mechanical software	Solidworks, Catia, Workbench

SELF EVALUATION

- Solid mathematical and physics foundation.
- Proficient in C/C++, Python. Experienced with ROS and PX4. Possess 2 years of development experience in the Linux environment, capable of independently completing robotic task development.
- Strong spatial imagination and mechanical design skills.
- Proficient in the integration, testing, and maintenance of mechatronic systems.