Lanyue Tang

May, 1999 | Shanghai, 201800, China

+86 181-3638-4651 | 2133393@tongji.edu.com

Education

Tongji University   *Shanghai, China*

Master of Transportation Planning and Management   *Sep 2021 - present*

- Supervisor: Assoc. Prof. Jian Sun
- Average score: 86.52/100 (GPA: 4.09/5)
- Main courses: Deep learning and its application transportation, Traffic planning theories and methods, Optimization Method, Traffic Flow Theory and Simulation Analysis

Southeast University   *Nanjing, China*

Bachelor of Traffic Engineering   *Sep 2017 – Jun 2021*

- Average score: 86.97/100 (GPA: 3.63/4)
- Main courses: Traffic analysis, Traffic data analysis, Traffic management and control, Traffic simulation

Research

Research Interests: Traffic simulation, Driving Simulator Experiment, Human-Computer Interaction, Trajectory Prediction

Ongoing Research:

Publications：

- Tang, L., Zhang, D., Tian, Y., Sun, J.* (2023), Parallel Computing-based Calibration for Microscopic Traffic Simulation Model, Transportation Research Record, Washington, DC.
- Tang, L., Fu, A., Yue, L*. (2023), Interactive Vehicle Trajectory Prediction Considering Abnormal Emotion Based on SOR Cognitive Framework, 2023 7th CAA International Conference on Vehicular Control and Intelligence (CVCI).

Projects

Driver modelling and Scenario Generation – Huawei Technologies Co., Ltd.   *May 2022 – Sep 2023*

Core member

- Established a multi-style driver model of left-turn vehicle interaction at the intersection based on the actual collected trajectory data to meet the heterogeneity of drivers in the actual traffic environment. Deployed the established model in the VTD autonomous driving simulation environment, and the simulation results were extracted to complete the calculation and analysis of PET, jerk and other indicators.

Honors

- Outstanding Student of the Fifth Yinfu Class   Mar *2023*
- YunYing scholarship   Oct 2019

Skills

Language: CET-4, CET-6

Programming: Python、Pytorch、TensorFlow

Software: Carla, Tobii Pro Lab, UE4, MATLAB, Road Runner, VISSIM.