

Tairan Liu

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Athens, GA, U.S.A.

Education

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| Louisiana State University | BATON ROUGE, LA, U.S.A. |
| Doctor of Philosophy | <i>May 2020</i> |
| Mechanical Engineering, Department of Mechanical & Industrial Engineering | |
| University of Science and Technology of China | HEFEI, ANHUI, P.R.CHINA |
| Bachelor of Natural Science | <i>Jul. 2012</i> |
| Theoretical and Applied Mechanics, Department of Modern Mechanics | |

Research Interest

- Multi-Agent/Robot System
 - Cyber-Physical System
 - Large-Scale Networked System
 - Cooperative Control
 - Distributed System/Algorithm
 - Multi-Agent Reinforcement Learning
 - Human-Robot/Swarm Interaction
 - Lyapunov-Based Nonlinear Control
 - Robotics (Aerial/Ground/Underwater)
 - Multi-Robot Smart Manufacturing
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Professional Experience

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| University of Georgia // Postdoc // Research | ATHENS, GA, U.S.A. |
| Coverage Control with Heterogeneous Robots | <i>Sep. 2020 – Present</i> |
| Ongoing research: new concepts and algorithms of coverage control. Details to be unveiled later. | |
| Aerial Robotics in Agricultural Measurements and Operations | <i>Sep. 2020 – Present</i> |
| Ongoing research: testbed design and implementation. Details to be unveiled later. | |
| Louisiana State University // PhD // Research | BATON ROUGE, LA, U.S.A. |
| Multi-Agent System Formation Control | <i>Jul. 2016 – May 2020</i> |
| Proposed new formation control methods, provided mathematical proofs, conducted computational and experimental validation. | |
| Aerial Robotic Network for Agricultural Applications | <i>Jul. 2016 – Oct. 2019</i> |
| Designed and built a quadrotor fleet from scratch. Developed autonomous flight control firmware on MCU and flight control/monitor applications on PC. Developed distributed control network for quadrotors. (Funded by the LSU Economic Development Assistantship (EDA) program.) | |

Computational Molecule Synthesis

Oct. 2015 – May 2016

Developed open-source software which can decompose large molecules to small bio-active fragments, then use fragments to generate target molecules or new molecules for drug design.

Multicopter Copter Applications in Agriculture

Feb. 2015 – Jun. 2015

Developed an application to process aerial images. Optimized the software for better processing speed.

Louisiana State University // PhD // Teaching

BATON ROUGE, LA, U.S.A.

Teaching Assistant and Lab Instructor

Jan. 2020 – May 2020

Fundamentals of Instrumentation and Measurement (ME 3603).

Teaching Assistant and Lab Instructor

Jan. 2016 – May 2016

Autonomous Vehicles (ENGR 4200).

Teaching Assistant and Lab Instructor

Aug. 2015 – Dec. 2015

Machine Design Lab (ME 4201).

University of Science and Technology of China

HEFEI, ANHUI, P.R.CHINA

Bionic Four-Tail Fin UUV (Mimic Dragonfly)

Aug. 2011 – Jan. 2013

Developed program on MCU for motor control, developed remote control and wireless data transfer programs on PC and MCU for the bionic UUV with four oscillatory tail fins. The tail fins were designed to mimic the motion pattern of dragonfly.

Bionic Long Undulatory Fin UUV (Mimic Black Ghost Knifefish)

Nov. 2011 – Jun. 2012

Designed and built a UUV to mimic the propulsion pattern of black ghost knifefish. Developed program on Arduino for the UUV. Studied the effects of the frequency and amplitude of the swaying fin ray, wave number in the fin surface, and the speed of the incoming flow on propulsion thrust.

Bionic Double-Tail Fin UUV

Sep. 2011 – May 2012

Conducted experiments to optimize the performance of the double tail fin UUV. Developed a whole system to automatically conduct experiment, collect and process data, and plot results.

Flow Trajectory After Passing Dual Circular Cylinders

Oct. 2011 – Nov. 2011

Designed and built an adjustable dual-circular-cylinder model for the fluid experiment. Conducted experiments with hydrogen bubbles, laser beam, and high resolution high speed camera to study the water flow trajectory after passing dual circular cylinders.

Composite Bionic Actuators

Apr. 2011 – Aug. 2011

Assisted with motion pattern design. Developed programs on Arduino for the actuators.

Publications

Refereed Journal Articles

8. **Tairan Liu** and Marcio de Queiroz. An orthogonal basis approach to formation shape control. *Automatica*. Accepted
7. **Tairan Liu** and Marcio de Queiroz. Distance + angle-based control of 2-d rigid formations. *IEEE Transactions on Cybernetics*. In press

6. **Tairan Liu**, Victor Fernandez-Kim, and Marcio de Queiroz. Switching formation shape control with distance + area/angle feedback. *Systems & Control Letters*, Jan. 2020. Article 104598
5. Milad Khaledyan, **Tairan Liu**, Victor Fernandez-Kim, and Marcio de Queiroz. Flocking and target interception control for formations of nonholonomic kinematic agents. *IEEE Transactions on Control Systems Technology*, 28(4):1603–1610, 2020
4. **Tairan Liu**, Marcio de Queiroz, Pengpeng Zhang, and Milad Khaledyan. Further results on the distance and area control of planar formations. *International Journal of Control*. In press
3. Pengpeng Zhang, Marcio de Queiroz, Milad Khaledyan, and **Tairan Liu**. Control of directed formations using interconnected systems stability. *Journal of Dynamic Systems, Measurement, and Control*, 141(4):041003, 2019
2. Limeng Pu, Misagh Naderi, **Tairan Liu**, Hsiao-Chun Wu, Supratik Mukhopadhyay, and Michal Brylinski. eToxPred: a machine learning-based approach to estimate the toxicity of drug candidates. *BMC Pharmacology and Toxicology*, 20(1):2, 2019
1. **Tairan Liu**, Misagh Naderi, Chris Alvin, Supratik Mukhopadhyay, and Michal Brylinski. Break down in order to build up: Decomposing small molecules for fragment-based drug design with eMolFrag. *Journal of Chemical Information and Modeling*, 57(4):627–631, 2017

Conference Proceedings

2. **Tairan Liu**, Marcio de Queiroz, and Farid Sahebsara. Distance-based planar formation control using orthogonal variables. In *2020 IEEE Conference on Control Technology and Applications (CCTA)*, pages 64–69, Montréal, Canada, Aug. 2020
1. **Tairan Liu**, Marcio de Queiroz, Pengpeng Zhang, and Milad Khaledyan. Directed formation control of n planar agents with distance and area constraints. In *2019 Annual American Control Conference (ACC)*, pages 1824–1829, Philadelphia, PA, Jul. 2019

Manuscripts in Submission

1. **Tairan Liu**, Davoodi Mohammadreza, and Javad Mohammadpour Velni. Deployment of heterogeneous multi-agent systems with varying mass over a graph. In *2021 IEEE Conference on Control Technology and Applications (CCTA)*. In submission

Conference Abstracts, Posters, Presentations, and Talks

3. **Tairan Liu**. Start from distance-based formation control. University of Georgia, Athens, GA, May 2020
2. **Tairan Liu**. Directed formation control of planar agents with distance and area constraints. In *2019 MIE Graduate Student Conference*, LSU, Baton Rouge, LA, Apr. 2019
1. **Tairan Liu**, Misagh Naderi, Supratik Mukhopadhyay, and Michal Brylinski. Decomposing small molecules for fragment-based drug design with eMolFrag. In *SCALA 2018 - Scientific Computing Around Louisiana*, LSU, Baton Rouge, LA, Feb. 2018

Ph.D. Dissertation

Tairan Liu. *Distance-Based Formation Control: Theory, Applications, and Issues*. PhD dissertation, Louisiana State University, May 2020

Awards and Honors

Outstanding Graduate Research Assistant, 2019

Department of Mechanical and Industrial Engineering, Louisiana State University, Baton Rouge, LA, U.S.A.

LSU-ME Enrichment Award, 2014

Department of Mechanical and Industrial Engineering, Louisiana State University, Baton Rouge, LA, U.S.A.

Grants

Co-authored Proposal

Transportation Consortium of South-Central States, *Real-Time Work Zone Traffic Management via Unmanned Air Vehicles*, \$79,991, 18 months, Co-PIs: Charles Malveaux, Marcio de Queiroz, Xin Li, and Hany Hassan.

Skills

Hardware: Arduino, Raspberry Pi, STM32 Flight Controller (Pixhawk/Seriously Pro Racing), NodeMCU, XBee, Remote Control, etc.

Software: XCTU, QT Creator, TeXstudio, Inkscape, AutoCAD, FreeCAD, Blender, Arduino IDE, etc.

Programming Languages: Python, MATLAB/Simulink, C, C++ (*associated with GUI design with QT*) .

Natural Languages: Chinese (*mother tongue*) and English.

Others: HPC (*Philip@LSU, SuperMike-II@LSU, QB2@LONI*), LaTeX.

Other Experience

University of Science and Technology of China (USTC)

HEFEI, ANHUI, P.R.CHINA

Robo-Game Competition of USTC (2010)

Jun. 2010 – Oct. 2010

Participated in prototyping and building of autonomous and manned robots, and developed program on MCU for the autonomous robot.

Professional Activities

Membership

Institute of Electrical and Electronics Engineers (IEEE)

Institute of Electrical and Electronics Engineers - Control Systems Society (IEEE-CSS)

Reviewer

Automatica

IEEE Transactions on Cybernetics

IEEE Robotics and Automation Letters

IEEE Conference on Decision and Control

IEEE International Conference on Robotics and Automation

Graduate Level Courses

- Advanced Mechanical Systems Control
 - Introduction to Modern Control Theory
 - Advanced Linear Systems
 - Advanced Topics in Control
 - Industrial Robotics
 - Topics in Modern System Science
 - Advanced Engineering System Dynamics
 - Sensors and Actuators
 - Numerical Methods in Applied Mechanics
 - Advanced Vibrations
 - Mathematics Methods in Engineering
 - Intelligent Control and Applications in Power Systems
 - Stress Analysis in Mechanical Engineering
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Teaching Interest

Undergraduate Level Courses

- Classical Control Theory
- Modern Control Theory
- Intelligent Control and Applications
- Industrial Robotics
- Mechanics (Statics and Dynamics)
- Mechanical Vibrations
- Engineering System Dynamics
- Sensors and Actuators
- Numerical Methods
- Mathematics Methods in Engineering
- Autonomous Vehicles

Graduate Level Courses

- Advanced Linear Systems
- Nonlinear Control Theory
- Advanced Vibrations
- Advanced Dynamics
- Multi-copter Design and Control Practice
- Advanced Topics in Control: Distributed Algorithms for Multi-Agent Systems
- Advanced Topics in Control: Consensus Control for Multi-Agent Systems
- Advanced Topics in Control: Formation Control for Multi-Agent Systems
- Advanced Topics in Control: Coverage Control for Multi-Agent Systems