

Tairan Liu

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Baton Rouge, LA • U.S.A.

Education

Louisiana State University

Ph.D. Candidate (Dissertation Defended)

Mechanical Engineering, Dept. of Mechanical & Industrial Engineering

BATON ROUGE, LA, U.S.A.

Expected May 2020

GPA: 4.0

University of Science and Technology of China

Bachelor of Natural Science

Theoretical and Applied Mechanics, Dept. of Modern Mechanics

HEFEI, ANHUI, P.R.CHINA

July 2012

Research Interests

- Multi-Agent System
 - Cyber-Physical System
 - Networked System
 - Cooperative Control
 - Distributed System
 - Lyapunov-Based Nonlinear Control
 - Robotics
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Professional Experience

Louisiana State University

Teaching Assistant

Fundamentals of Instrumentation and Measurement (ME 3603).

BATON ROUGE, LA, U.S.A.

January 2020 – May 2020

Multi-Agent System Formation Control

Proposed new formation control methods, provided mathematical proofs, conducted computational and experimental validation.

July 2016 – May 2020

Aerial Robotic Network for Agricultural Applications

Designed and built 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.)

July 2016 – October 2019

Computational Molecule Synthesis

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.

October 2015 – May 2016

Multirotor Copter Applications in Agriculture

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

February 2015 – June 2015

Teaching Assistant

Autonomous Vehicles (ENGR 4200).

January 2016 – May 2016

Teaching Assistant

Machine Design Lab (ME 4201).

August 2015 – December 2015

University of Science and Technology of China

Bionic Four-Tail Fin UUV (Mimic Dragonfly)

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 a dragonfly.

HEFEI, ANHUI, P.R.CHINA

August 2011 – January 2013

- Bionic Long Undulatory Fin UUV (Mimic Black Ghost Knifefish)** *November 2011 – June 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** *September 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 Cylinder** *October 2011 – November 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 cylinder.
- Composite Bionic Actuators** *April 2011 – August 2011*
Assisted with motion pattern design. Developed programs on Arduino for the actuators.
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Publications

Refereed Journal Articles

6. **Tairan Liu**, Victor Fernandez-Kim, and Marcio de Queiroz. Switching formation shape control with distance + area/angle feedback. *Systems & Control Letters*. In press
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*. In press
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

Manuscripts in Submission

1. **Tairan Liu** and Marcio de Queiroz. Distance + angle-based control of 2d rigid formations. *IEEE Transactions on Cybernetics*. Under review

Conference Proceedings

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

Conference Posters, Presentations, and Talks

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. Thesis

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

Awards and Honors

Outstanding 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 FC, NodeMCU, XBee, etc.

Software: XCTU, QT Creator, Microsoft Office, TeXstudio, Inkscape, AutoCAD, 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)

June 2010 – October 2010

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

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
 - Intelligent Control and Applications in Power Systems
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Professional Activities

Membership

Institute of Electrical and Electronics Engineers (IEEE), Student Member since 2017.

Reviewer

IEEE Transactions on Cybernetics
