

Nan Wang

708 Koshland Way ◦ Santa Cruz, CA 95064 ◦ (725) 300 - 9136
nanwang@ucsc.edu

ACADEMIC EXPERIENCE

University of California, Santa Cruz, Santa Cruz CA *Sep 2018—2023 (Expected)*
Ph.D. in Computer Sci. and Eng., **GPA:** 3.85/4.0, **Emphasis:** motion planning, hybrid systems, MPC.

Tongji University, Shanghai China *Sep 2015—Jun 2018*
M.E. in Control Sci. and Eng., **GPA:** 4.33/5.0, **Emphasis:** trajectory planning, autonomous vehicles.

East China Univ. of Sci. and Tech., Shanghai China *Sep 2011—Jun 2015*
B.E. in Automation, **GPA:** 3.50/4.0, **Emphasis:** path planning, tracking control.

SELECTED PROJECTS AND RESEARCH

Hybrid Systems Lab (UCSC, PI: Ricardo Sanfelice) **Graduate Student Researcher**

- Robotics Applications Projects *Sep 2021 - Present*
 - Implemented a tracking controller for **self-driving vehicles** with **global invariance** property.
 - Implemented a set-based planner for **drones** considering obstacles exhibiting **hybrid dynamics**.
- MPC-based Tracking Control for Hybrid Systems *Mar 2022 - Present*
 - Designed a **model predictive controller** for hybrid systems to track motion plans with proven **asymptotic stability** property.
- RRT Motion Planning Algorithm for Hybrid Systems *Sep 2021 - Mar 2022*
 - Designed an **RRT-based** motion planning algorithm for hybrid systems, called HyRRT, with the proven **probabilistic completeness** property. Implemented a HyRRT software tool that improves the computation performance by **95.5%**.
- Feasible Motion Planning for Hybrid Systems *Sep 2018 - Mar 2021*
 - Mathematically defined the motion planning problem, systematically formalized the **propagation**, **reversal**, and **concatenation** operations for hybrid systems, and designed a motion planning algorithm template for hybrid systems with proved **completeness** properties.

Lab of Vehicle Control & Networking (Tongji, PI: Jun Wang) **Research Assistant**

- Autonomous Vehicle Development *Jan 2018 - Aug 2018*
 - Led a team of three to develop the Decision Making, Planning, and Control Module on a **full-size autonomous vehicle platform**.
 - Developed a **finite state machine**-based decision making module using **Stateflow**.
- Flow Field-guided Trajectory Planning for Ground Vehicles *Mar 2017 - Jul 2018*
 - Developed a novel trajectory planning algorithm for the unmanned ground vehicles which navigates the vehicle using the **fluid field** information.
- Path Planning for Autonomous Parking Systems *Jul 2015 - Dec 2015*
 - Developed a **geometric** path planning method for autonomous parking systems that decreases the **minimal length** of the feasible parking lot by **7%**.

ADDITIONAL INFORMATION

Skills: MATLAB/Simulink, Python, C/C++, C#, CarMaker, CarSim, ROS, Git, HTML/CSS, L^AT_EX

Publications: IAVSD 2017, CDC 2017 and 2022, CCTA 2022, Dynamics of Vehicles on Roads & Tracks.

Teaching Assistantship: Analysis of Algorithm, Database Systems, Robot Automation, Computer Systems and C Programming.

Award: Chancellor's Fellowship. **Academic Service:** Technical committee member in IEEE CSS Technical Committee on Hybrid Systems