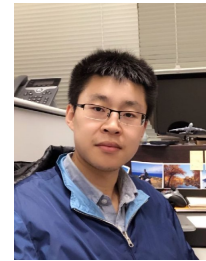


Boyang Li
Research Assistant Professor
Department of Aeronautical and Aviation Engineering
Email: bo-yang.li@polyu.edu.hk
Phone: 34008231



Biography

Dr Li received the B.Eng. and M.Eng. degrees in Aeronautical Engineering from Northwestern Polytechnical University (NPU), Xi'an, China, in 2012 and 2015, respectively, and the PhD degree in Mechanical Engineering from The Hong Kong Polytechnic University (PolyU), in 2019. After that, he was a Research Fellow at the Air Traffic Management Research Institute (ATMRI), Nanyang Technological University (NTU), Singapore. Before joining PolyU as a Research Assistant Professor, he was a Research Associate in Robotics for Extreme Environment at School of Engineering, the University of Edinburgh, UK.

Qualifications

Bachelor of Engineering, Northwestern Polytechnical University

Master of Engineering, Northwestern Polytechnical University

Doctor of Philosophy, The Hong Kong Polytechnic University

Employment

Research Assistant Professor

Research Assistant Professor

Department of Aeronautical and Aviation Engineering

The Hong Kong Polytechnic University

29 Jun 2020 → present

Member

IEEE

United States

Research outputs

Modular Robots for Enabling Operations in Unstructured Extreme Environments

Sayed, M. E., Roberts, J. O., Donaldson, K., Mahon, S. T., Iqbal, F., Li, B., Franco Aixela, S., Mastorakis, G., Jonasson, E. T., Nemitz, M. P., Bernardini, S. & Stokes, A. A., 20 Jan 2022, In: *Advanced Intelligent Systems*.

An End-to-End UAV Simulation Platform for Visual SLAM and Navigation

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Dynamic object tracking on autonomous UAV system for surveillance applications

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Image-based Visual Servoing of Rotorcrafts to Planar Visual Targets of Arbitrary Orientation

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Feng, Y., Tse, K., Chen, S., Wen, C. Y. & Li, B., 2 Feb 2021, In: *Sensors (Switzerland)*. 21, 4, p. 1-23 23 p., 1385.

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Zhou, W., Chen, S., Chang, C. W., Wen, C. Y., Chen, C. K. & Li, B., 3 Dec 2020, In: *IEEE Access*. 8, p. 218348-218359 12 p., 9279215.

An actuator allocation method for a variable-pitch propeller system of quadrotor-based uavs

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Transition Optimization for a VTOL Tail-Sitter UAV

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Experimental force data of a restrained rov under waves and current

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A nonlinear model predictive controller for remotely operated underwater vehicles with disturbance rejection

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