Jianglan Wei

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ACADEMIC BACKGROUND

- **University of California, Berkeley** — *2024.08 - 2025.08*
  Research Intern and Visiting Student — Berkeley, United States
  ◦ **Advisor:** Prof. Masayoshi Tomizuka
  ◦ **GPA:** 4.00/4.00

- **Huazhong University of Science and Technology** — *2022.09 - 2026.06 (expected)*
  BEng in Artificial Intelligence — Wuhan, China
  ◦ **Research Advisor:** Prof. Zhigang Zeng
  ◦ **Major GPA:** 91.23/100.00

PUBLICATIONS

- **Reimagination with Test-time Observation Interventions**   Paper
  Yuxin Chen*, **Jianglan Wei***, Chenfeng Xu, Boyi Li, Masayoshi Tomizuka, Andrea Bajcsy, Thomas Tian
  Best Paper Finalist *at RSS 2025 Out-of-Distribution Generalization Workshop*
  Under Review at ICRA 2026
  ◦ Propose a test-time strategy that enables world models to predict more reliable action outcomes in open-world scenarios where unanticipated visual distractors are inevitable.
  ◦ ReOI improves task success rate by up to 3x in the presence of noval distractors, significantly outperforms action verification that relies on world model predictions without imagination interventions.

- **MEReQ: Max-Ent Residual-Q Inverse RL for Sample-Efficient Alignment from Intervention**   Paper
  Yuxin Chen*, Chen Tang*, **Jianglan Wei**, Chenran Li, Thomas Tian, Xiang Zhang, Wei Zhan, Peter Stone, Masayoshi Tomizuka
  9th Annual Conference on Robot Learning (CoRL 2025)
  ◦ Propose an interactive imitation learning algorithm where human expert observes the policy's execution and provides interventions for the policy to imitate.
  ◦ Instead of inferring the complete human behavior characteristics, MEReQ infers a residual reward function that captures the discrepancy between the human expert and prior policy's underlying reward functions. This makes MEReQ more sample-efficient compared to baselines.

- **Interleave-VLA: Enhancing Robot Manipulation with Image-Text Interleaved Instructions**   Paper
  Cunxin Fan*, Xiaosong Jia*, **Jianglan Wei**, et al.
  Oral & Spotlight *at ICRA 2025 Vision-Language Foundation Models in Robotics Workshop*
  Under Review at ICLR 2026
  ◦ Propose a framework capable of comprehending image-text interleaved instructions and directly generating continuous action sequences in the physical world.
  ◦ Interleave-VLA improves out-of-domain generalization to unseen objects by 2-3x compared to SOTA baselines.

- **HDC-X: Efficient Medical Data Classification for Embedded Devices**   Paper
  Jianglan Wei*, Zhenyu Zhang*, Pengcheng Wang, Mingjie Zeng, Zhigang Zeng
  Under Review at ICLR 2026
  ◦ Propose a HDC-based medical data classifier capable of embedded deployment.

- **CodeAvatar: Learning Animatable Occlusion-Aware 3D Avatars in the Wild**   Paper
  Qinzheng Zhou, Hao Wang, **Jianglan Wei**, Lijing Lu, Zhihang Li
  Under Review at AAAI 2026
  ◦ Propose a framework that creates 3D human avatars from occluded monocular videos.

- **Energy-Efficient EMG Signal Classification via SNN-HDC Synergy**
  Chengxuan Zhou, Zhenyu Zhang, **Jianglan Wei**
  To be submitted to International Journal of Medical Informatics
  ◦ Propose a framework that combines SNN and HDC for sEMG signal classification.

HONORS AND AWARDS

- **Student Speaker for Berkeley Global Access Closing Ceremony** — *2025.05*
  University of California, Berkeley

- **UC Berkeley BGA Scholarship 2024 (Top 10 Students)** — *2024.12*
  University of California, Berkeley

- **National 1st Prize, CUMCM 2024 (Top 0.5%, 296 winners / 59278 teams)** — *2024.11*
  China Society for Industrial and Applied Mathematics (CSIAM)

- **Scholarship and Award for Merit Student 2023** — *2023.10*
  Huazhong University of Science and Technology