



✉ [jinkefan@sjtu.edu.cn](mailto:jinkefan@sjtu.edu.cn)

☎ +86 18217373192

📍 Shanghai

🔍 [Research Gate](#)

🌐 [Linked In](#)

🔍 [Google Scholar](#)

🏠 [Website](#)

**Birthday:** 16/08/1994

**Address:** 800, Dongchuan Road, Shanghai, China

**Research Interest:**

Autonomous navigation,  
Latent world model,  
Robust perception,  
Robust navigation.

# Kefan Jin Ph.D

*Post-doctoral Researcher*

## EDUCATION

### Post-doctoral Researcher

July 2023 - present

*Shanghai Jiao Tong University*

- School of Automation and Intelligent Sensing
- Supervisor: Prof. Hesheng Wang

### Doctor's Degree

Sept. 2016 - June 2023

*Shanghai Jiao Tong University*

- School of Ocean and Civil Engineering
- Supervisor: Prof. Hong Yi

### Bachelor's Degree

Sept. 2012 - June 2016

*Harbin Engineering University*

- College of Shipbuilding Engineering

## TEACHING AND MENTORING


- Teaching assistant of the undergraduate course Mobile Robotics in SJTU.
- Thesis advisor for four SJTU undergraduates and four SJTU Doctoral students.
- Advisor of two National Undergraduate Training Program for Innovation projects.


## SELECTED AWARDS


- IEEE ROBIO 2022 Best Conference Paper, 2022 IEEE International Conference on Robotics and Biomimetics, **Best Conference Paper**.
- T.J. Tran Best Paper in Robotics Award of 2021 IEEE International Conference on Robotics and Biomimetics.
- 2020 "Maritime Clash" China Intelligent USV Challenge Concept Design of Intelligent USV (Group A) First Prize.
- Patent of A Composite Power Unmanned Surface Vehicle, 2020-09-18, China, CN201811167376.6.


# Publications


---

K. Jin , Z. Liu, J. Wang, H. Wang,. **Unmanned surface vehicle navigation under disturbances: world model enhanced reinforcement learning**, *IEEE/ASME Transactions on Mechatronics*, 2025, doi: 10.1109/TMECH.2025.3552677. 

K. Jin , Z. Liu, J. Wang. **Predictive obstacle avoidance algorithm for underactuated unmanned surface vehicle under disturbances via reinforcement learning**, *Journal of Field Robotics*, 2025, doi: 10.1002/rob.22554 


K. Jin , H. Zhu, R. Gao, J. Wang, H. Wang, H. Yi, C.-J. Richard Shi. **DEMRL: Dynamic estimation meta reinforcement learning for path following on unseen unmanned surface vehicle**, *Ocean Engineering*, 2023, 288: 115958 

K. Jin , F. Mu, X. Han, G. Wang, Zhe Liu,. **Anomaly Detection For Robust Autonomous Navigation**, *IEEE International Conference on Robotics and Automation (ICRA)*, 2023 


K. Jin , J. Wang, H. Wang, X. Liang, Y. Guo, M. Wang, H. Yi. **Soft formation control for unmanned surface vehicles under environmental disturbance using multitask reinforcement learning**, *Ocean Engineering*, 2022, 260: 112035-112035 

K. Jin \*, H. Wang\*, C. Liu, Y. Zhai, L. Tang. **Graph Neural Network Based Relation Learning for Abnormal Perception Information Detection in Self-Driving Scenarios**, *IEEE International Conference on Robotics and Automation (ICRA)*, 2022. 


K. Jin , X. Han. **Conquering Ghosts: Hidden Markov Model based Heterogeneous Relation Learning for Robust Navigation**, *arXiv:2203.09952* 

Z. Liu\*, K. Jin \*, Y. Zhai, Y. Miao. **Learning Robust Vehicle Navigation Policy Under Interference and Partial Sensor Failures**, *IEEE International Conference on Robotics and Biomimetics (ROBIO)*, 2022 


K. Jin , H. Wang, H. Yi. **End-to-end trajectory tracking algorithm for unmanned surface vehicle using reinforcement learning**, *International Ocean and Polar Engineering Conference (ISOPE)*. 2019 


L. Zhuo, K. Jin , Z. Liu, H. Wang. **RESBev: Making the BEV Perception More Robust**, *IEEE International Conference on Robotics and Automation (ICRA)*, 2026, submitted 


J. Shi, Z. Liu, K. Jin , H. Wang. **A Multi-Agent Reinforcement Learning Approach Based on Local Shapley Value**, *IEEE Conference on Decision and Control (CDC)*, 2025, accepted 

Y. Zhao, Z. Liu, H. Wei, K. Wang, H. Wang, D. Zhai, K. Jin , H. Shao. **GIPD: Global Intent Prediction and Decomposition of Cooperative Multi-Robot System in Non-Communication Environments**, *International Conference on Intelligent Robots and Systems (IROS)*, 2025, accepted 

Y. Zhou, Y. Zhou, K. Jin , H. Wang. **Hierarchical Reinforcement Learning With Model Guidance for Mobile Manipulation**, *IEEE/ASME Transactions on Mechatronics*, 2025, doi:10.1109/TMECH.2025.3552677 

H . Zhu, K. Jin , R. Gao, R. J. Wang. **Timed-Elastic-Band-Based Variable Splitting for Autonomous Trajectory Planning**, *Symmetry*, 2025, doi: 10.3390/sym17060848. 

H. Wang, K. Jin , H. Wang. **Attacking End-to-End Visual Navigation Model: How Weak Existing Learning-Based Approaches Can Be?**, *IEEE International Conference on Robotics and Biomimetics (ROBIO)*, 2021 

Z. Liu, Q. Liu, L. Tang, K. Jin , H. Wang, M. Liu, H. Wang. **Visuomotor reinforcement learning for multi-robot cooperative navigation**, *IEEE Transactions on Automation Science and Engineering*, 2022 vol. 19, no. 4, pp. 3234-3245 

# ACADEMIC EXPERIENCE

---

## Post-doctoral Researcher

2023 - present

|IRMV Lab |Shanghai Jiao Tong University

- Develop a robust latent world model to predict navigation states under motion uncertainty.
- Develop a spatiotemporal information consistency learning method to detect and recover diverse perception anomalies.
- Develop a ROBEV method that can be easily deployed on existing BEV perception approaches, enhancing their robustness against perception anomalies.
- Develop a robust end-to-end navigation policy that enables reliable navigation in the presence of perception anomaly and motion disturbances.

## Graduate Researcher

2016 - 2023

|MIES Lab |Shanghai Jiao Tong University

- Develop a meta-RL-based navigation policy that enables few-shot adaptation for diverse dynamic characteristics.
- Propose a soft formation policy that enables adaptation to dynamic formation shapes and scales

# SERVICE

---

- Associate Editor of ICRA 2025.
- Reviewer of international journal and conference: TASE, OE, RIA, RAL, JFR, TMECH, IROS, ICRA, NIPS.

# SKILLS

- Programming: Competent in PyTorch, ROS, OpenCV.
- Practical experience in applying the RL-based methods in practical vehicles.