

Anqi Li

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EDUCATION AND RESEARCH EXPERIENCE

Peking University

B.S. in Intelligent Science and Technology & B.B.A in Management

Advisor: [Prof. He Wang](#); GPA: 3.52/4.00

Sep 2023 - present

University of California, Berkeley

Visiting Student

Advisor: [Prof. Masayoshi Tomizuka](#)

Jan 2026 - present

Galbot Inc.

Research Intern, Department of Large Models

Working on multimodal foundation models for embodied navigation and manipulation.

Feb 2025 - Feb 2026

PUBLICATIONS

UrbanVLA: A Vision-Language-Action Model for Urban Micromobility (*ICRA 2026*)

Anqi Li*, Zhiyong Wang*, Jiazhao Zhang*, Minghan Li, Yunpeng Qi, Zhibo Chen, Zhizheng Zhang[†], He Wang[†].

- Focusing on **urban micromobility**, UrbanVLA aligns noisy navigation-tool routes with visual observations to enable **scalable, long-horizon** urban navigation.
- Through a **two-stage training pipeline** including supervised fine-tuning and reinforced fine-tuning, UrbanVLA demonstrates the ability to operate **safely** and in compliance with **social norms**.

Embodied Navigation Foundation Model (*ICLR 2026*)

Jiazhao Zhang*, Anqi Li*, Yunpeng Qi*, Minghan Li*, Jiahang Liu, Shaoan Wang, Haoran Liu, Gengze Zhou, Yuze Wu, Xingxing Li, Yuxin Fan, Wenjun Li, Zhibo Chen, Fei Gao, Qi Wu, Zhizheng Zhang[†], He Wang[†].

- A **cross-embodiment and cross-task** navigation foundation model encompassing quadrupeds, drones, wheeled robots, and vehicles, spanning tasks including VLN, ObjectNav, tracking, and self-driving.

TrackVLA: Embodied Visual Tracking in the Wild (*CoRL 2025*)

Shaoan Wang*, Jiazhao Zhang*, Minghan Li, Jiahang Liu, Anqi Li, Kui Wu, Fangwei Zhong, Junzhi Yu, Zhizheng Zhang[†], He Wang[†].

- Simultaneously conducting **object recognition** and **visual tracking**, TrackVLA demonstrates robust tracking, long-horizon tracking and cross-domain generalization.

SKILLS AND INTERESTS

Technical Skills:

Programming: Python, PyTorch, C/C++, L^AT_EX, Mujoco

Languages: English (TOEFL: 111), Chinese (Native)

Research Interests:

My long-term research goal is to build intelligent robotic systems that operate reliably in complex, human-centered environments. Currently, I focus on **embodied navigation** and **whole-body humanoid control** with **vision-language-action (VLA)** models, exploring how general intelligence enables robust and adaptive navigation behaviors. In the future, I hope to extend these ideas toward a more unified framework of human-centered robotic intelligence that seamlessly integrates high level perception, planning, and low level action.