

## Publications

- [1] **Li J**, Li S E, Duan J, et al. Relaxed policy iteration algorithm for nonlinear zero-sum games with application to H-infinity control[J]. IEEE Transactions on Automatic Control, 2024, 69(1): 426-433.
- [2] **Li J**, Nagamune R, Zhang Y, Li S E. Robust approximate dynamic programming for nonlinear systems with both model error and external disturbance[J]. IEEE Transactions on Neural Networks and Learning Systems, 2023.
- [3] Duan J\*, **Li J\***, Chen X, Zhao K, S. E. Li, Optimization landscape of policy gradient methods for discrete-time static output feedback[J]. IEEE Transactions on Cybernetics, 2023.
- [4] **Li J**, Wang J, Li S E, Li K. Learning optimal robust control of connected vehicles in mixed traffic flow[C]// 2023 Conference on Decision and Control (CDC). IEEE, 2023: 1112-1117.
- [5] Duan J\*, **Li J\***, Li S E, et al. Relaxed actor-critic with convergence guarantees for continuous-time optimal control of nonlinear systems[J]. IEEE Transactions on Intelligent Vehicles, 2023, 8(5): 3299-3311.
- [6] **Li J**, Li S E, Tang K, et al. Reinforcement solver for H-infinity filter with bounded noise[C]//2020 15th IEEE International Conference on Signal Processing (ICSP). IEEE, 2020, 1: 62-67.
- [7] Duan J, **Li J**, Li S E, et al. Optimization landscape of gradient descent for discrete-time static output feedback[C]//2022 American Control Conference (ACC). IEEE, 2022: 2932-2937.
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- [9] Duan J, Ren Y, Zhang F, **Li J**, et al. Encoding Distributional Soft Actor-Critic for Autonomous Driving in Multi-Lane Scenarios[J]. IEEE Computational Intelligence Magazine, 2024.
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- [13] Li K, Li S E, Gao F, Lin Z, **Li J**, et al. Robust distributed consensus control of uncertain multi-agents interacted by eigenvalue-bounded topologies[J]. IEEE Internet of Things Journal, 2020, 7(5): 3790-3798.
- [14] Wang W, Zhang Y, Gao J, Jiang Y, Yang Y, Zheng Z, Zou W, **Li J**, et al. A general optimal control problem solver for industrial control applications[J]. Communications in Transportation Research, 2023, 3: 100096.