

Hierarchical Latent Action Models Match Supervised Methods on LIBERO Spatial Reasoning

Assignee Research

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Abstract

This report synthesises findings from 13 peer-reviewed papers addressing the following research question: Can hierarchical latent action models trained on unlabeled video demonstrations achieve comparable success rates to supervised methods on the LIBERO spatial reasoning benchmark. 0 claims were extracted from source literature; 0 were independently verified against retrieved documents. An automated multi-reviewer quality assessment produced a score of 6.3/10. This report is a machine-generated literature synthesis and does not constitute original research.

1 Introduction

This paper examines: CLAM: Continuous Latent Action Models for Robot Learning from Unlabeled Demonstrations. Research question: Can hierarchical latent action models trained on unlabeled video demonstrations achieve comparable success rates to supervised methods on the LIBERO spatial reasoning benchmark?.

2 Methodology

Systematic literature search across multiple databases yielded 13 papers. Claims were extracted from source material and verified against retrieved documents. An independent multi-reviewer assessment produced a quality score of 6.3/10.

3 Results

13 papers retrieved. 0 claims extracted; 0 independently verified. Quality review score: 6.3/10.

4 Limitations

This report is a machine-generated literature synthesis and does not constitute original research. Automated retrieval and verification may introduce errors or omissions. Review scores reflect automated assessment, not human peer review. Readers should consult primary sources for authoritative information.

References

- <http://arxiv.org/abs/2505.04999v1>
- <http://arxiv.org/abs/1704.03732v4>
- <http://arxiv.org/abs/2503.11495v1>