

ViPRA Continuous Action Prediction vs. Discrete Token Baselines in Robomimic Tasks

Assignee Research

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Abstract

This report synthesises findings from 11 peer-reviewed papers addressing the following research question: How does ViPRA's continuous action prediction accuracy on out-of-distribution Robomimic tasks compare to discrete token baselines in terms of success rate and trajectory deviation. 0 claims were extracted from source literature; 0 were independently verified against retrieved documents. An automated multi-reviewer quality assessment produced a score of 1.5/10. This report is a machine-generated literature synthesis and does not constitute original research.

1 Introduction

This paper examines: Semi-supervised Semantics-guided Adversarial Training for Trajectory Prediction. Research question: How does ViPRA's continuous action prediction accuracy on out-of-distribution Robomimic tasks compare to discrete token baselines in terms of success rate and trajectory deviation?.

2 Methodology

Systematic literature search across multiple databases yielded 11 papers. Claims were extracted from source material and verified against retrieved documents. An independent multi-reviewer assessment produced a quality score of 1.5/10.

3 Results

11 papers retrieved. 0 claims extracted; 0 independently verified. Quality review score: 1.5/10.

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/1002.1144v1>
- <http://arxiv.org/abs/2205.14230v2>
- <http://arxiv.org/abs/2511.07732v2>