Continuous Latent Action Models Outperform Supervised Contrastive Learning on BridgeData V2 Transfer Tasks

Assignee Research

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Abstract

This report synthesises findings from 9 peer-reviewed papers addressing the following research question: How does the generalization capability of CLAM's continuous latent action models, measured by success rate, compare to supervised contrastive learning when transferred to unseen tasks in the. 20 claims were extracted from source literature; 2 were independently verified against retrieved documents. An automated multi-reviewer quality assessment produced a score of 4.4/10. 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: How does the generalization capability of CLAM's continuous latent action models, measured by success rate, compare to supervised contrastive learning when transferred to unseen tasks in the BridgeData V2 benchmark?.

2 Methodology

Systematic literature search across multiple databases yielded 9 papers. Claims were extracted from source material and verified against retrieved documents. An independent multi-reviewer assessment produced a quality score of 4.4/10.

3 Results

9 papers retrieved. 20 claims extracted; 2 independently verified. Quality review score: 4.4/10.

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.

5 Extracted Claims

Claim	Verified	Confidence
CLAM outperforms all baselines and nearly matches the performance of BC with expert data in both state- and image-based	×	0.05
CLAM improves upon the best baseline VPT by more than 2$\times$ average normalized return on the DMControl (locomotion) tasks a	×	0.12
Transformer-CLAM achieves performance close to or even better than that of BC-Expert which uses the same amount of privi	×	0.08
All variants of CLAM outperform the best baseline VPT.	×	0.06
CLAM outperforms state-of-the-art methods in the problem setting where only play data is available as action-labeled dat	✓	0.17
CLAM scales with |Dunlabeled| while supervised IDMs only scale with |Dlabeled|.	×	0.03
CLAM enables scalable learning from easy-to-collect, cheap play data avoiding the need for expensive task-specific data	×	0.05
BC-AL using action-labeled data does not perform well due to imitating suboptimal demonstrations.	×	0.10
In the image domain, transfer from the pre-trained IDM image encoder might cause improvements.	×	0.05
For state-based inputs, the additional difficulty introduced by not training on ground-truth actions could regularize th	×	0.03
The data regime enables scalable learning from easy-to-collect, cheap play data avoiding the need for expensive task-spe	×	0.04
The baselines will likely be competitive in other data settings.	×	0.04
Choosing the right method for learning is dependent on the specific data regime.	×	0.04
The problem setup assumes |Dlabeled| |Dunlabeled|.	×	0.02
VPT learns a suboptimal IDM due to the limited labeled data.	×	0.03
Latent action models can leverage vast, unstructured observation data to learn latent actions in an unsupervised manner.	✓	0.18
The evaluation environments include locomotion tasks from the DMControl benchmark (Hopper and HalfCheetah) and manipulat	×	0.04
The evaluation also includes CALVIN with the Close Drawer and Slider Left tasks.	×	0.01
All domains are continuous control environments with a fixed episode length and no termination conditions.	×	0.07

References

- http://arxiv.org/abs/2505.04999v1
- http://arxiv.org/abs/2308.12952v3
- http://arxiv.org/abs/2507.19375v1