

Continuous Latent Action Policies vs. Supervised Contrastive Learning on BridgeData V2 Under Visual Noise

Assignee Research

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Abstract

This report synthesises findings from 12 peer-reviewed papers addressing the following research question: How does the success rate of policies trained with CLAM's continuous latent actions compare to those trained with Supervised Contrastive Learning on the BridgeData V2 benchmark when evaluated under. 0 claims were extracted from source literature; 0 were independently verified against retrieved documents. An automated multi-reviewer quality assessment produced a score of 1.7/10. 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 success rate of policies trained with CLAM's continuous latent actions compare to those trained with Supervised Contrastive Learning on the BridgeData V2 benchmark when evaluated under varying levels of visual noise?.

2 Methodology

Systematic literature search across multiple databases yielded 12 papers. Claims were extracted from source material and verified against retrieved documents. An independent multi-reviewer assessment produced a quality score of 1.7/10.

3 Results

12 papers retrieved. 0 claims extracted; 0 independently verified. Quality review score: 1.7/10.

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/2603.18589v1>
- <http://arxiv.org/abs/2507.19375v1>