

Scalability of Habitat-Sim vs. Embodied AI Platforms in RoboStack Multi-Agent RL

Assignee Research

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Abstract

This report synthesises findings from 15 peer-reviewed papers addressing the following research question: How does Habitat-Sim’s scalability compare to other embodied AI platforms when measuring training throughput (samples/second) for large-scale multi-agent reinforcement learning across diverse 3D. 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: Habitat-GS: A High-Fidelity Navigation Simulator with Dynamic Gaussian Splatting. Research question: How does Habitat-Sim’s scalability compare to other embodied AI platforms when measuring training throughput (samples/second) for large-scale multi-agent reinforcement learning across diverse 3D environments in the RoboStack benchmark?.

2 Methodology

Systematic literature search across multiple databases yielded 15 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

15 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/2603.15054v1>
- <http://arxiv.org/abs/1904.01201v2>
- <http://arxiv.org/abs/2604.12626v1>