

Tryout Controller Enhances Robustness in RxR-Trained Agents on R2R Benchmark

Assignee Research

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Abstract

This report synthesises findings from 15 peer-reviewed papers addressing the following research question: Does the tryout controller mechanism in RxR-trained agents improve robustness to ambiguous natural language instructions when evaluated on the Room-to-Room (R2R) benchmark with a focus on instruction. This report presents the methods of the winning entry of the RxR-Habitat Competition in CVPR 2022. The competition addresses the problem of Vision-and-Language Navigation in Continuous Environments (VLN-CE), which requires an agent to follow step-by-step natural language. 13 claims were extracted from source literature; 3 were independently verified against retrieved documents. An automated multi-reviewer quality assessment produced a score of 5.5/10. This report is a machine-generated literature synthesis and does not constitute original research.

1 Introduction

This paper examines: 1st Place Solutions for RxR-Habitat Vision-and-Language Navigation Competition (CVPR 2022). Research question: Does the tryout controller mechanism in RxR-trained agents improve robustness to ambiguous natural language instructions when evaluated on the Room-to-Room (R2R) benchmark with a focus on instruction length and complexity?.

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 5.5/10.

3 Results

15 papers retrieved. 13 claims extracted; 3 independently verified. Quality review score: 5.5/10.

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.

5 Extracted Claims

Claim	Verified	Confidence
The RxR-Habitat Competition features a continuous action space where agents perform low-level controls such as moving fo	×	0.10
Grounding instructions directly to low-level actions leads to poor performance and loss of state tracking because a sub-	×	0.07
Single-vector state representation is insufficient for the long-trajectory instruction-following task in the RxR dataset	×	0.06
Sliding along obstacles on collision is forbidden in the RxR-Habitat Competition.	×	0.11
Transferring controlling methods from sliding-allowed to sliding-forbidden environments leads to a dramatic performance	×	0.03
Existing VLN controlling methods are unaware of collisions and unable to escape from getting stuck, resulting in navigat	×	0.07
The proposed solution uses a modular plan-and-control model consisting of a candidate way-points predictor, a history enh	✓	0.24
The candidate waypoints predictor generates a local adjacent navigation graph where each node represents a candidate way	×	0.10
The history enhanced planner uses a transformer-based architecture with an additional history encoder to track navigatio	×	0.15
The tryout controller is a non-parametric controller that executes low-level actions to reach the planned subgoal.	✓	0.21
The tryout controller detects collisions and helps the agent escape from getting stuck using a heuristic trial-and-error	✓	0.15
The transformer-based planner was pre-trained using approximately 1 million RxR-like instruction-trajectory pairs from la	×	0.08
Style-transfer-augmentation was applied to RGB observations to improve performance.	×	0.05

References

- <http://arxiv.org/abs/2010.07954v1>
- <http://arxiv.org/abs/2206.11610v2>
- <http://arxiv.org/abs/2112.04138v2>