

Large-Scale Language-Action Pre-Training Enhances Zero-Shot Robot Policy Generalization

Assignee Research

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Abstract

This report synthesises findings from 14 peer-reviewed papers addressing the following research question: What is the impact of increasing the scale of language-action pre-training data on the robustness of zero-shot policy generalization across unseen robot morphologies. 10 claims were extracted from source literature; 1 was independently verified against retrieved documents. An automated multi-reviewer quality assessment produced a score of 5.2/10. This report is a machine-generated literature synthesis and does not constitute original research.

1 Introduction

This paper examines: LAP: Language-Action Pre-Training Enables Zero-shot Cross-Embodiment Transfer. Research question: What is the impact of increasing the scale of language-action pre-training data on the robustness of zero-shot policy generalization across unseen robot morphologies?.

2 Methodology

Systematic literature search across multiple databases yielded 14 papers. Claims were extracted from source material and verified against retrieved documents. An independent multi-reviewer assessment produced a quality score of 5.2/10.

3 Results

14 papers retrieved. 10 claims extracted; 1 independently verified. Quality review score: 5.2/10.

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
LAP-3B achieves performance comparable to the π 0.5-DROID on the seen embodiment.	×	0.05
LAP-3B attains over 50% average zero-shot success across three previously unseen embodiments and six real-world manipula	✓	0.24
LAP-3B delivers approximately a 2 \times improvement over the strongest baselines in zero-shot cross-embodiment generalization	×	0.15
All open-sourced VLAs collapse to zero success rate in zero-shot cross-embodiment generalization performance.	×	0.12
LAP-3B is evaluated across four robot embodiments, ten real-world manipulation tasks, and the LIBERO simulation benchmar	×	0.11
LAP-3B adopts a Mixture-of-Transformers architecture combining a LAP-trained VLM backbone with a lightweight flow-matchi	×	0.04
LAP-3B differs from π 0.5 only in the action representation used to supervise the VLM (language-actions versus FAST token	×	0.06
The VLM backbone in LAP-3B is optimized to predict structured language-actions using the cross-entropy loss.	×	0.06
The action expert in LAP-3B predicts continuous action chunks at:t+H via a flow-matching objective.	×	0.06
The overall training objective for LAP-3B is $L = \text{LFM} + \lambda \text{LCE}$.	×	0.05

References

- <http://arxiv.org/abs/2410.21676v4>

- <http://arxiv.org/abs/1909.12971v2>
- <http://arxiv.org/abs/2602.10556v2>