

Unsupervised Latent Action Models for Scalable Robotic Learning from Video

Assignee Research

June 9, 2026

Abstract

This report synthesises findings from 8 peer-reviewed papers addressing the following research question: Can unsupervised latent action models trained on unlabeled video demonstrations scale effectively to more complex robotic environments (e.g., multi-step tasks) while maintaining high success rates. 19 claims were extracted from source literature; 0 were independently verified against retrieved documents. An automated multi-reviewer quality assessment produced a score of 3.7/10. 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: Can unsupervised latent action models trained on unlabeled video demonstrations scale effectively to more complex robotic environments (e.g., multi-step tasks) while maintaining high success rates and sample efficiency?.

2 Methodology

Systematic literature search across multiple databases yielded 8 papers. Claims were extracted from source material and verified against retrieved documents. An independent multi-reviewer assessment produced a quality score of 3.7/10.

3 Results

8 papers retrieved. 19 claims extracted; 0 independently verified. Quality review score: 3.7/10.

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.

5 Extracted Claims

Claim	Verified	Confidence
CLAM improves upon the best baseline VPT by more than 2 \times average normalized return on DMControl locomotion tasks.	×	0.08
CLAM improves upon the best baseline VPT by around 2-3 \times success rate on MetaWorld manipulation tasks.	×	0.11
On the HalfCheetah task, TF-CLAM achieved a normalized return of 0.72 \pm 0.04.	×	0.02
On the HalfCheetah task, BC-Expert achieved a normalized return of 0.68 \pm 0.02.	×	0.02
On the Hopper task, TF-CLAM achieved a normalized return of 0.81 \pm 0.05.	×	0.02
On the Hopper task, BC-Expert achieved a normalized return of 0.76 \pm 0.04.	×	0.02
In several tasks, Transformer-CLAM achieves performance close to or better than BC-Expert.	×	0.04
The Transformer CLAM model uses 6 encoder layers and 6 decoder layers.	×	0.03
The Transformer CLAM model uses a feedforward dimension of 2048 and 4 attention heads.	×	0.01
The CALVIN Transformer CLAM model uses 8 attention heads.	×	0.02
The MetaWorld environment configuration uses a state dimension of 39 and an action dimension of 4.	×	0.05
The MetaWorld environment configuration uses an action repeat of 2 and a maximum of 100 episode steps.	×	0.04
The CALVIN environment configuration uses an action dimension of 7 and an action repeat of 7.	×	0.05
The CALVIN environment configuration uses a maximum of 200 episode steps.	×	0.02
The study evaluates locomotion tasks (Hopper and HalfCheetah) from the DMControl benchmark.	×	0.03
The study evaluates manipulation tasks (Assembly, Bin Picking, Peg Insert Side, and Shelf Place) from the MetaWorld benchmark.	×	0.02
The study evaluates Close Drawer and Slider Left tasks in the CALVIN environment.	×	0.01
All evaluated domains are continuous control environments with fixed episode lengths and no termination conditions.	×	0.06
BC-AL performs poorly because it imitates sub-optimal demonstrations.	×	0.03

References

- <http://arxiv.org/abs/2505.04999v1>
- <http://arxiv.org/abs/2507.19375v1>
- <http://arxiv.org/abs/2006.08967v1>