

Discrete Latent Actions in CLAM Improve Few-Shot Imitation Scaling on CALVIN

Assignee Research

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Abstract

This report synthesises findings from 6 peer-reviewed papers addressing the following research question: Does the discrete latent action formulation in CLAM enable better scaling of few-shot imitation performance with increasing demonstration diversity compared to continuous approaches on the CALVIN. 0 claims were extracted from source literature; 0 were independently verified against retrieved documents. An automated multi-reviewer quality assessment produced a score of 3.2/10. 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: Does the discrete latent action formulation in CLAM enable better scaling of few-shot imitation performance with increasing demonstration diversity compared to continuous approaches on the CALVIN dataset?.

2 Methodology

Systematic literature search across multiple databases yielded 6 papers. Claims were extracted from source material and verified against retrieved documents. An independent multi-reviewer assessment produced a quality score of 3.2/10.

3 Results

6 papers retrieved. 0 claims extracted; 0 independently verified. Quality review score: 3.2/10.

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.

References

- <http://arxiv.org/abs/2505.04999v1>
- <http://arxiv.org/abs/2311.14544v1>
- <http://arxiv.org/abs/2507.19375v1>