

# NoMaD: Navigation with Goal-Masked Diffusion

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# Outline

- 1 Motivation and Goal
- 2 Introduction
- 3 Literature Review
  - Goal Masking
  - Diffusion Policies
- 4 Training Details and Experiments
- 5 Results
  - Goal Conditioned Setting
  - Unconditioned setting
  - Distance and Diffusion Losses
  - Total Loss
- 6 Comparison with ViNT
- 7 Challenges Faced
- 8 Team Contributions
- 9 Conclusion and Future Work
- 10 Appendices

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# Motivation and Goal

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- Task-oriented navigation — reaching specified goals
- Task-agnostic exploration — discovering and mapping new areas

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### The Challenge

These two objectives are typically handled by *separate systems*.

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- **Local Exploration:** Learning short-horizon control policies for diverse actions
- **Global Planning:** Using those policies to achieve long-horizon, goal-directed behavior

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### Key Question

Can a *single model* unify both tasks — exploration and navigation?

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# What is NoMaD?

**NoMaD** is a transformer-based diffusion policy designed for long-horizon, memory-efficient navigation.

It supports both:

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- **Open-ended exploration** — learning diverse behaviors without explicit goals

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It combines a transformer backbone to encode the high-dimensional visual stream, with diffusion models that predict a sequence of future actions in a generative manner.

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# Overview of NoMaD Architecture

## Visual Goal-Conditioned Navigation

Backbone: ViNT (Visual Navigation Transformer)

How does ViNT work?

- Receives: A sequence of past and current observations  $o_t = o_{t-P:t}$
- **Visual Encoder:** Each observation is processed using an EfficientNet-B0 encoder to extract feature embeddings.

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EfficientNet?

- A new method of Scaling CNNs to improve accuracy and efficiency
- It uses a **compound scaling** to uniformly scale all dimensions of depth, width, and resolution.

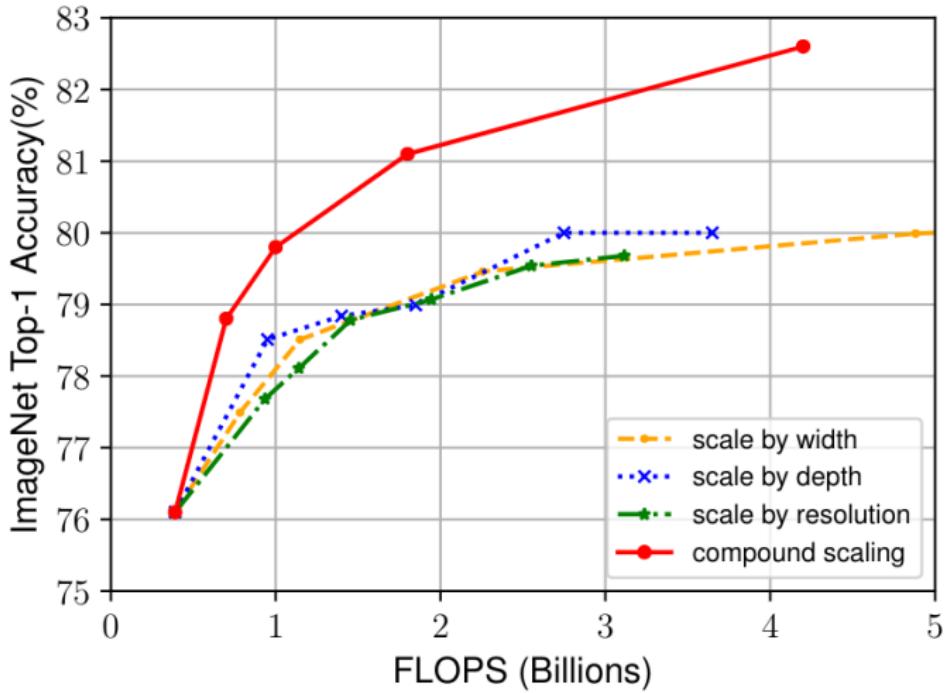


Figure: Compound Scaling

Use Network Architecture Search (NAS) to find the best baseline network (EfficientNet-B0)

## Optimization Objective:

$$\text{ACC}(m) \times \left[ \frac{\text{FLOPS}(m)}{T} \right]^w$$

- $\text{ACC}(m)$ : accuracy of model  $m$
- $\text{FLOPS}(m)$ : floating point operations
- $T$ : target FLOPS
- $w = -0.07$ : controls trade-off between accuracy and FLOPS

# EfficientNet Scaling

## Compound Scaling

EfficientNet introduces a principled way to scale up CNNs using a single compound coefficient  $\phi$ .

- Simultaneously scales:

- Network depth  $d$
- Width  $w$
- Input resolution  $r$

- Scaling formulas:

$$d = \alpha^\phi, \quad w = \beta^\phi, \quad r = \gamma^\phi$$

- Constants  $\alpha$ ,  $\beta$ , and  $\gamma$  are determined via grid search.

**Subject to constraint:**

$$\alpha \cdot \beta^2 \cdot \gamma^2 \approx 2$$

Ensures that the model scales within a fixed computational budget.

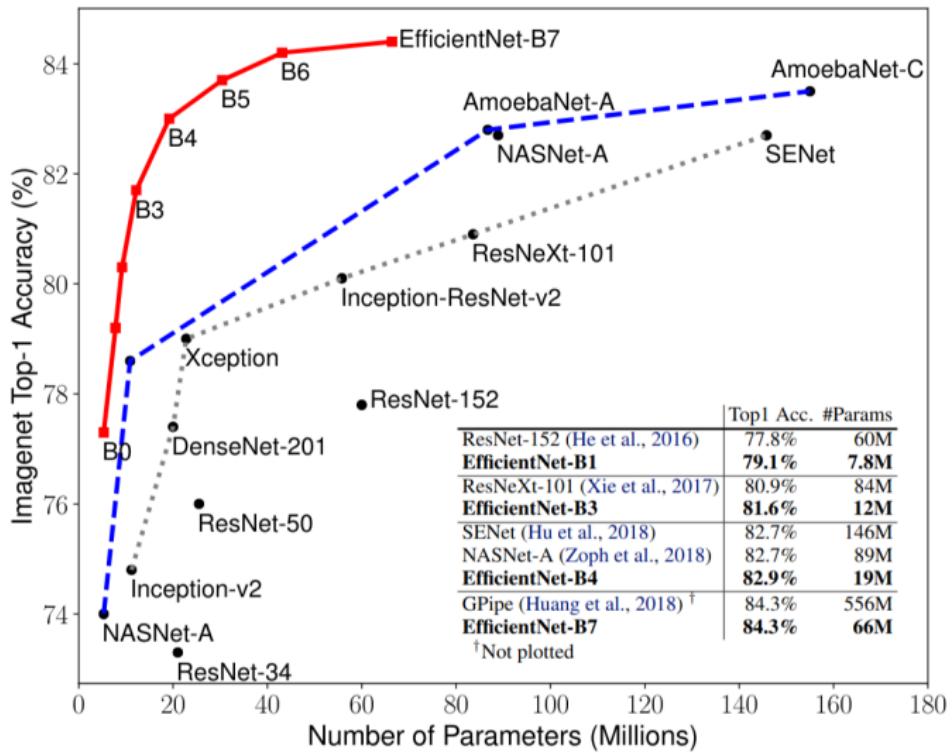


Figure: Accuracy on imagenet

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Backbone: ViNT (Visual Navigation Transformer)

How does ViNT work?

- Receives: A sequence of past and current observations  $o_t = o_{t-P:t}$
- **Visual Encoder:** Each observation is processed using an EfficientNet-B0 encoder to extract feature embeddings.
- **Goal Fusion:** The current and goal images are combined using a goal-fusion encoder.
- **Transformer Attention:** These fused features (tokens) are passed through a Transformer model to generate a context vector  $c_t$ .
- **Predictions:** The context vector is used to predict:
  - A distribution over future actions:  $a_t = f_a(c_t)$
  - An estimate of temporal distance to the goal:  $d(o_t, o_g) = f_d(c_t)$

# Extending to Long-Horizon Planning with Topological Memory

However, ViNT is inherently goal-conditioned—it cannot operate in the absence of a goal image, limiting its ability to explore autonomously.

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## Solution

To enable open-ended exploration, NoMaD incorporates a Topological Memory  $\mathcal{M}$ :

- ① Nodes represent previously encountered visual observations.
- ② Edges represent traversable paths, established using ViNT's predicted distances.

This enables:

- **Subgoal Planning:** The model can plan a sequence of subgoals to reach a target location.
- **Frontier Exploration:** The model can autonomously explore new areas by identifying frontiers in the topological map.

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# Overview of NoMaD Architecture

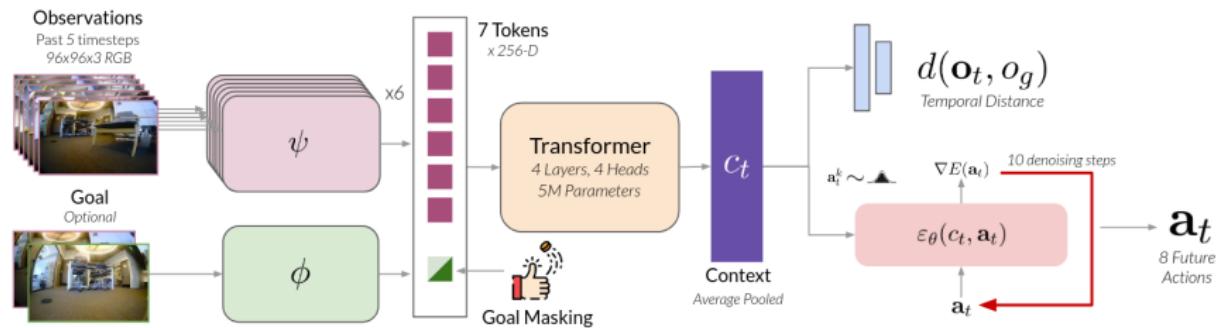
NoMaD = {EfficientNet + Vision Transformer} ← ViNT  
+ Diffusion Policies

Nomad builds upon ViNT by:

## Attention based Goal Masking:

Introduces a binary mask  $m$ , and modifies the context vector  $c_t$  as:

$$c_t = f(\psi(o_i), \phi(o_t, o_g), m)$$



# Overview of NoMaD Architecture

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## Diffusion Policies:

To model complex, multimodal action distributions, NoMaD employs a diffusion model to approximate the conditional distribution of the next action as:  $p(a_t|c_t)$ .

**1. Forward Process:** Start with a real action  $a_t^0$  and add gaussian noise to it over multiple steps.

$$a_t^k = \sqrt{\alpha_k} a_t^{k-1} + (\sqrt{1 - \alpha_k})\epsilon$$

where:

- $\epsilon \sim \mathcal{N}(0, I)$  is a random noise
- $\alpha_k$  is a noise scheduler (eg square cosine)
- By step K, the action is almost pure noise.

# Overview of NoMaD Architecture

NoMaD = {EfficientNet + Vision Transformer}  $\leftarrow$  ViNT  
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**2. Reverse Denoising:** starting from pure noise  $a_t^k \sim \mathcal{N}(0, I)$ , it denoises step by step to recover the final clean action  $a_t^0$ .

Each denoising step is :

$$a_t^{k-1} = \alpha(\alpha_t^k - \gamma_k \cdot \epsilon_\theta(c_t, a_t^k, k)) + \mathcal{N}(0, \sigma^2 \cdot I)$$

Where:

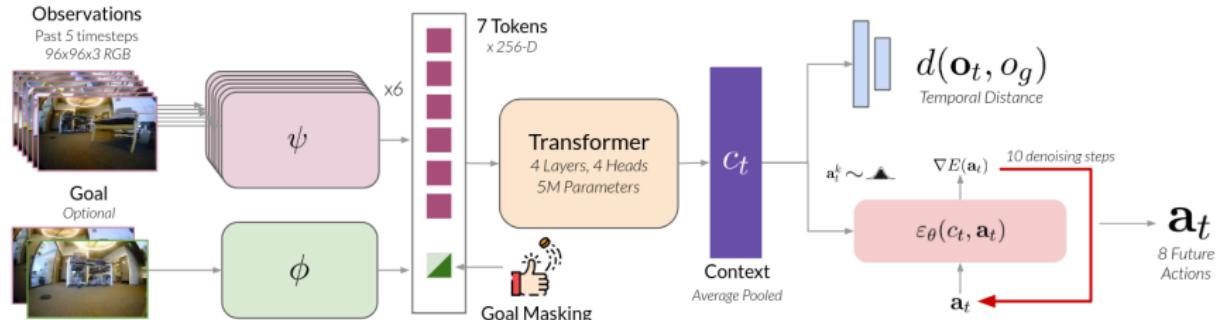
- Here,  $\epsilon_\theta$  is the noise prediction network conditioned on the context  $c_t$ , which may or may not include the goal depending on  $m$ .
  - It is a 1D conditional U-Net with 15 CNN layers.
  - Input: Noisy action  $a_t^k$ , Context vector  $c_t$ , and the diffusion step  $k$ .
  - the predicted noise vector  $\hat{\epsilon}_k$ , During training, it is compared to the true noise added earlier.
- $\gamma, \alpha, \sigma$  are scheduler constants.

# Overview of NoMaD Architecture

NoMaD = {EfficientNet + Vision Transformer}  $\leftarrow$  ViNT  
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**3. Action Decoder:** The denoised action  $a_t^0$  is then passed through a low-level action decoder to generate the final action  $a_t$ .

- The decoder maps the denoised action to a low-level control command for the robot.
- It can be a simple feedforward network or a more complex recurrent network.

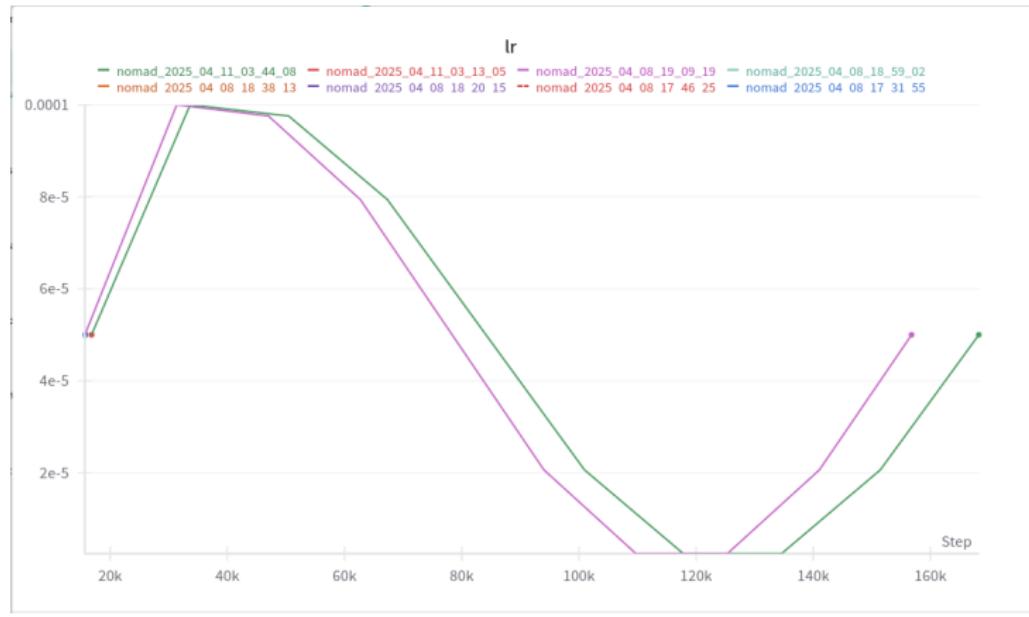


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# Training Details and Experiments

- Datasets used: Sacson/HuRoN, parts of RECON and SCAND
- Batch size: 47, Epochs: 10
- Optimizer: AdamW, Lr:  $10^{-4}$
- Scheduler: Cosine annealing



## Training Details and Experiments

- Goal Masking Probability:  $p_m = 0.5$
- Diffusion Steps: 10
- Noise Scheduler: Square Cosine

# Training Details and Experiments

- Goal Masking Probability:  $p_m = 0.5$
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## Training Objective

- **Diffusion Loss:** Measures the difference between the predicted and true noise.
- **Distance Loss:** Measures the difference between the predicted and true distance to the goal.

$$\mathcal{L}_{NoMaD}(\phi, \psi, f, \theta, f_d) = MSE(\epsilon^k, \epsilon_\theta(c_t, a_t^0 + \epsilon^k, k)) + \lambda \cdot MSE(d(o_t, o_g), f_d(c_t))$$

where:

- We set  $\lambda$  to  $10^{-4}$
- $\psi, \phi$  correspond to the visual encoders for the observation and goal images.
- $f$  corresponds to the transformer layers,  $\theta$  to diffusion parameters,
- $f_d$  corresponds to the temporal distance predictor.

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# Training Visualization with wandb

## Why Weights & Biases (wandb)?

We used wandb to log training progress, visualize losses, and monitor both model behavior and system resources (e.g., GPU/CPU utilization) throughout experimentation. Metrics such as **action loss**, **goal prediction error**, and the **learning rate schedule** were automatically tracked and visualized, which helped with debugging and plotting out results.



Figure: QR code to project webpage

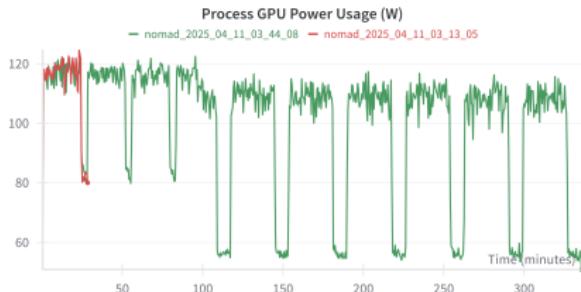


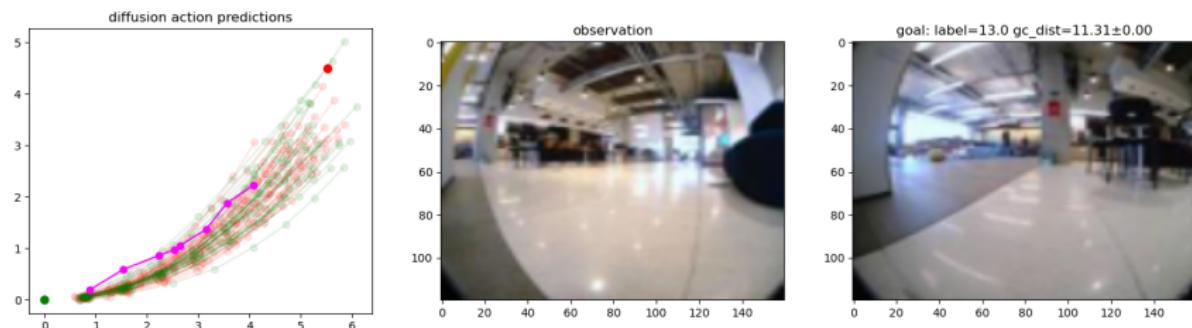
Figure: GPU power usage during training

# Action Samples generated by NoMaD

The figure illustrates a robot is trying to navigate towards a specific goal.

- The left plot shows action trajectories sampled by the diffusion model in 2D space.
- Green and red lines represent different stages of the diffusion process (noisy vs. denoised).
- The pink line shows the final selected action sequence

## During Training

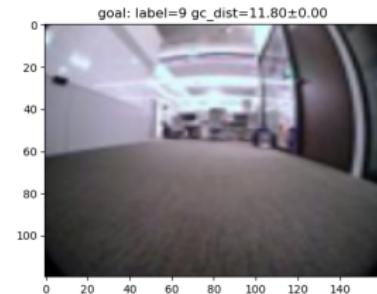
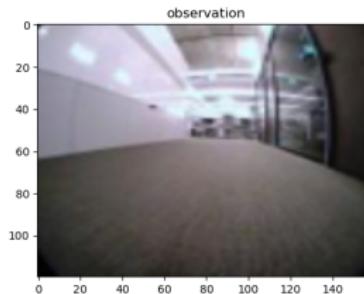
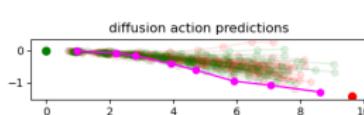


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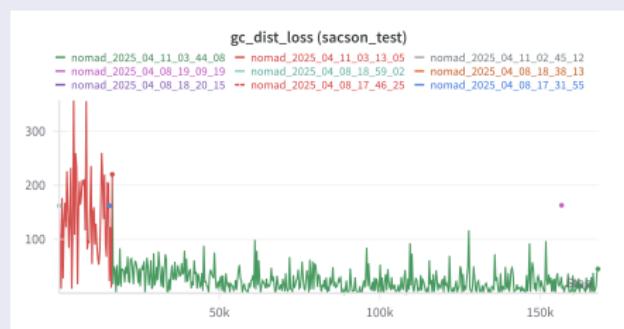
# Experiments and Results: (Goal Conditioned)

We set the goal mask  $m = 0$  to evaluate the model's performance in goal-directed navigation.

## Distance Loss



(a) Distance Loss on Training Set



(b) Distance Loss on Validation Set

**Figure:** Distance loss comparison between training and validation sets under goal-conditioned evaluation.

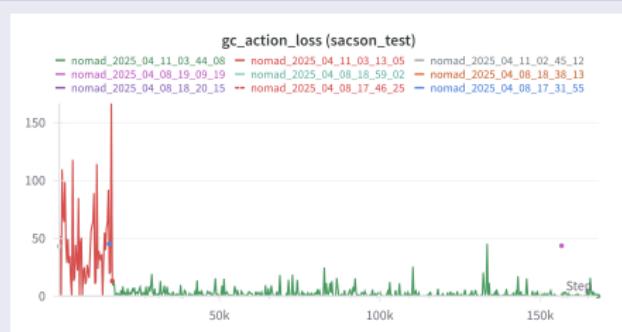
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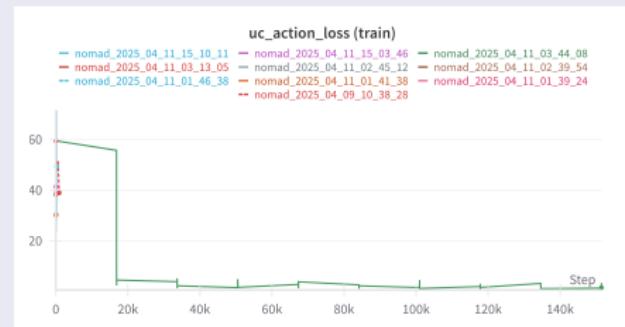


(b) Action Loss on Validation Set

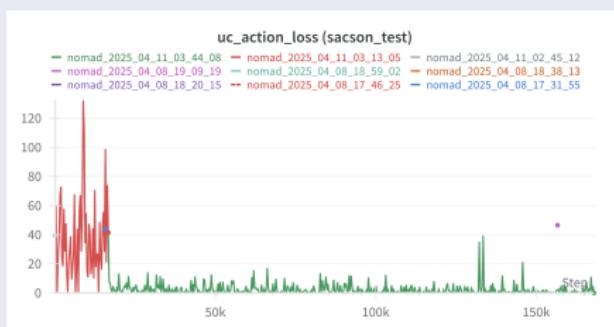
**Figure:** Action loss comparison between training and validation sets under goal-conditioned evaluation.

# Experiments and Results: (Unconditioned Setting)

## Action Loss Evaluation



**Training Set**



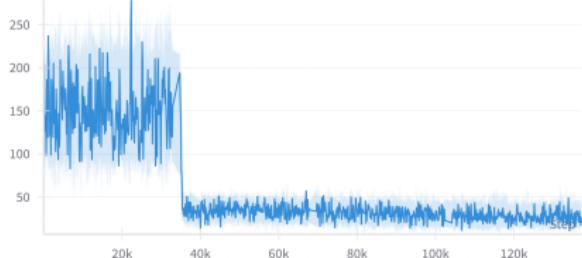
**Validation Set**

The unconditioned action loss measures model accuracy in open-loop, goal-agnostic settings. Lower loss indicates better generalization in exploratory behavior.

# Experiments and Results: Distance and Diffusion Losses

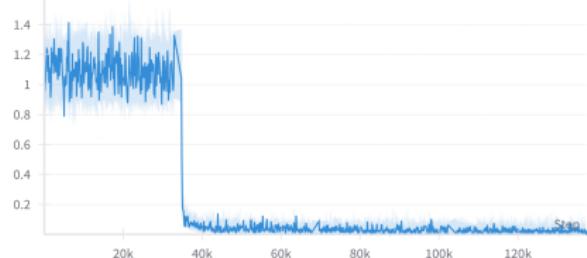
## Overall Metrics

dist\_loss



Distance Loss

diffusion\_loss

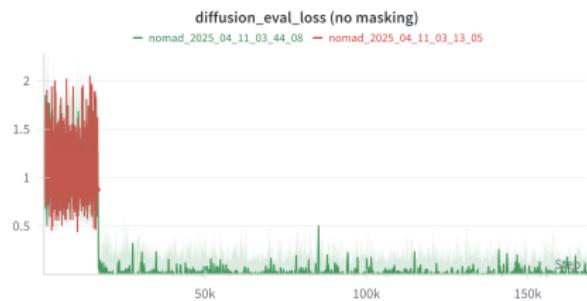


Diffusion Loss

The sharp drop in loss around 35k steps marks a point where the model begins to learn more effectively. The losses stabilize at a low value in the later stages, indicating that the model has successfully converged to a well-optimized solution for the training data.

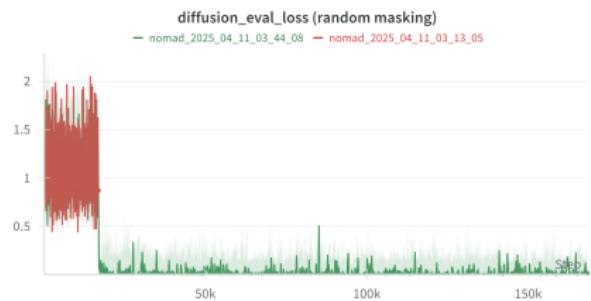
# Experiments and Results: Diffusion Loss on Validation Set

## Goal-Conditioned ( $m = 0$ )



**All tokens receive goal signal.**  
Evaluates the robot's ability to follow a target.

## Unconditioned ( $m = 1$ )

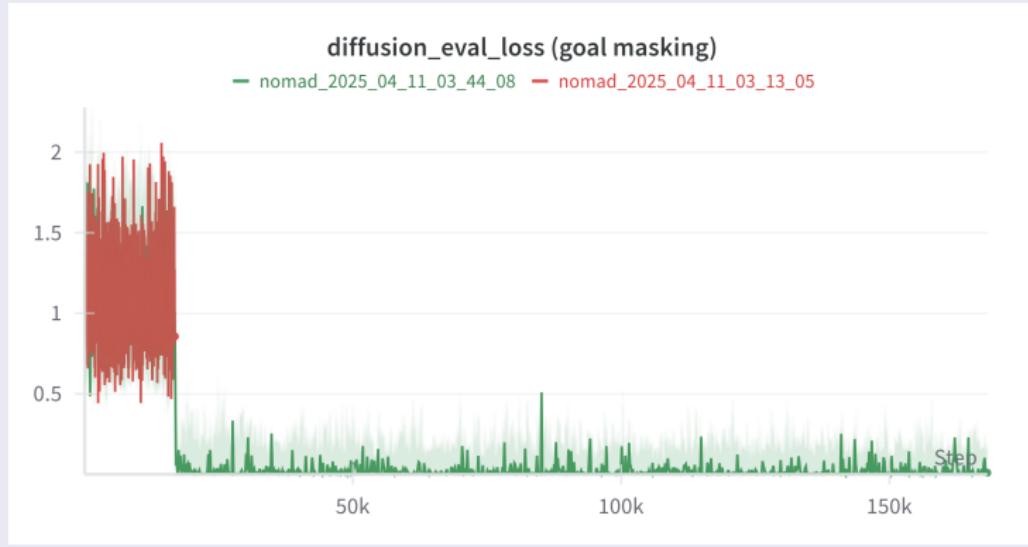


**No goal information.**  
Evaluates purely exploratory navigation behavior.

*We see that loss goes downstream in both cases.*

# Evaluation: Mixed Masking ( $m \sim \text{Ber}(0.5)$ )

## Stochastic Goal Conditioning

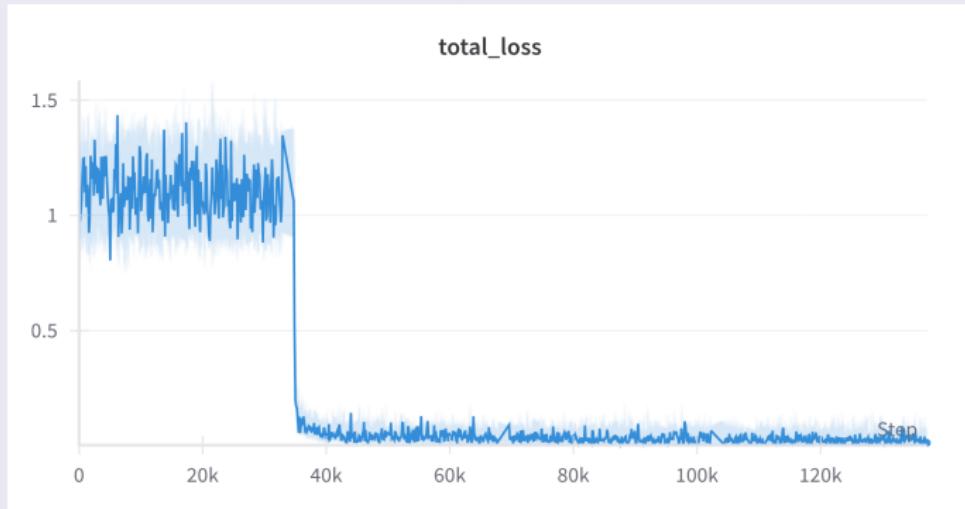


### Description:

Each token is randomly masked with probability 0.5. This encourages the model to balance between exploring and exploiting goal cues.

# Experiments and Results :Total Loss

## Total Loss



**Description:** The total loss combines both the diffusion and distance losses, providing a holistic measure of model performance. The model appears to converge to a stable solution.

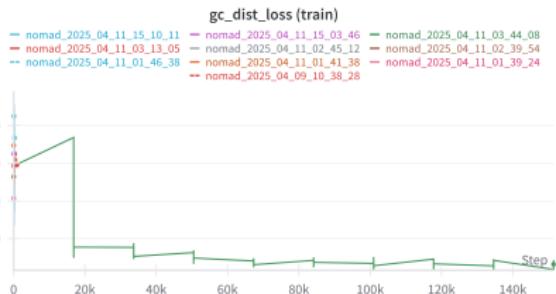
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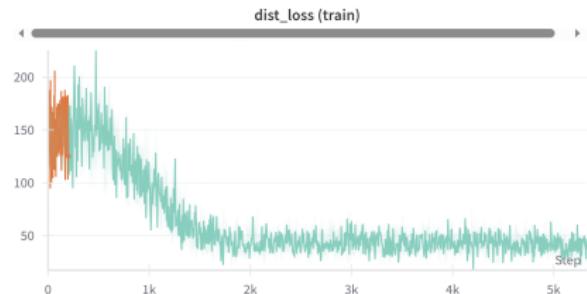
# Comparision with ViNT: Temporal Distance Loss

ViNT serves as a strong baseline for visual navigation with transformer-based context encoding. we trained the original ViNT architecture using the same dataset and training hyperparameters as used for NoMaD.

## NoMaD Distance Loss



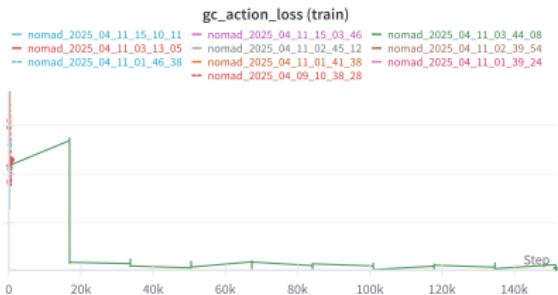
## ViNT Distance Loss



# ViNT vs NoMaD: Action Loss

We compare the quality of predicted waypoints by measuring the Mean Squared Error (MSE) between predicted and ground-truth actions.

NoMaD Action Loss



ViNT Action Loss

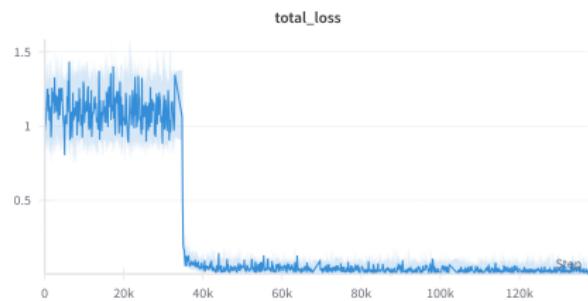


*Observation:* Interestingly, in the goal-conditioned (GC) setting, both ViNT and NoMaD demonstrated comparable performances.

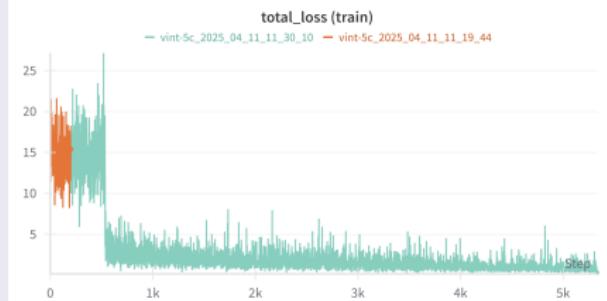
# Comparison with ViNT: Total Loss

To assess the overall effectiveness of NoMaD vs. ViNT, we compare the combined loss: action prediction loss + temporal distance prediction loss.

NoMaD Total Loss



ViNT Total Loss



Takeaway: Integration of a diffusion-based decoder in NoMaD does not negatively impact performance on goal-directed planning tasks.

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# Challenges Faced

- CUDA out of memory errors were common during training, especially with larger batch sizes. We mitigated this by reducing the batch size and using gradient accumulation.
- The model was initially not being able to learn effectively, leading to high loss values. We debugged this by checking the data pipeline and ensuring that the input images were correctly preprocessed and normalized.
- The system in UG computational labs did not have ROS installed, which was required to process the datasets. With the help of our TA, we used a docker file to set up a container with ROS and the required dependencies.
- The original codebase has several data-type related bugs which had to be fixed. For example, the original code was using `torch.float32` for some tensors, while the model expected them to be in `torch.float64`. This caused several errors during training.
- The initial implementation caused several system crashes due to heavy computational load.

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# Team Contributions

## **Abhishek Kumar Jha:**

- Implemented the Nomad Architecture and helped in the Training and Experiments
- Made the README file for the repository.
- Assisted in creating the report and Presentation.
- Contributed towards making the code demo video.
- Helped in integrating and debugging the diffusion policy repository

## **Namashivayaa V:**

- Explained the workflow of the suggested papers to the entire team.
- Contributed in report formation, by adding important formulas and results in the appendix section.
- Extracted the .bag files which were around 300GB.

# Team Contributions

## **Sehaj Ganjoo:**

- Implemented the ViNT architecture and trained it
- Helped in debugging the errors while training the NoMaD model
- Assisted in conducting experiments and analysis for the project
- Contributed towards the Presentation and project report

## **Shobhnik Kriplani:**

- Implemented the NoMaD architecture
- Developed the training pipeline
- Conducted experiments and analysis
- Made a website for the project

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# Conclusion and Future Work

- Successfully trained NoMaD using diffusion for visual navigation
- Showed compatibility with ViNT-based perception
- Future work:
  - Deploy NoMaD on real robots and check performance on real world environments
  - Explore the use of NoMaD for other tasks like object detection and tracking
  - Explore how we can improve the current architecture.
  - Try larger ViTs and alternate decoders

# Thank You!

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- 6 Comparison with ViNT
- 7 Challenges Faced
- 8 Team Contributions
- 9 Conclusion and Future Work
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# Appendices

## Appendices

- Appendix A: Additional Results
- Appendix B: References

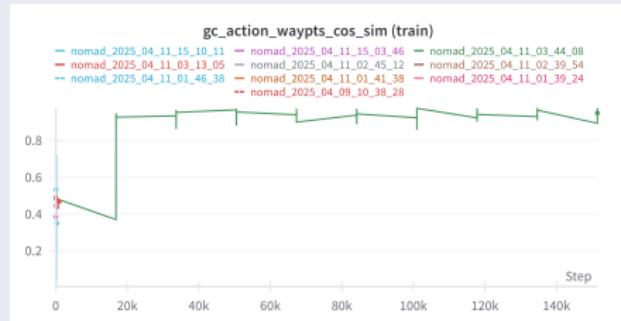
# Appendix A: Additional Results

## Additional Results

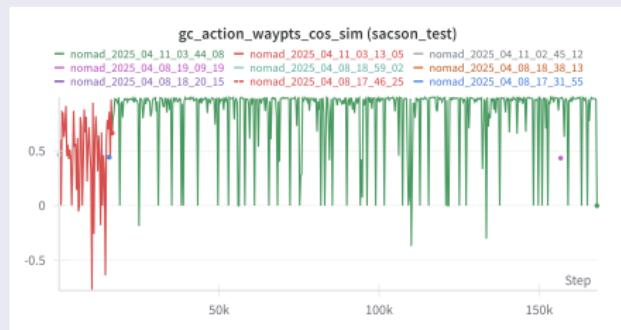
- Additional results and analysis of NoMaD's performance

# Experiments and Results: Cosine Similarity

## Goal-Conditioned Action Waypoints Cosine Similarity



Training Set

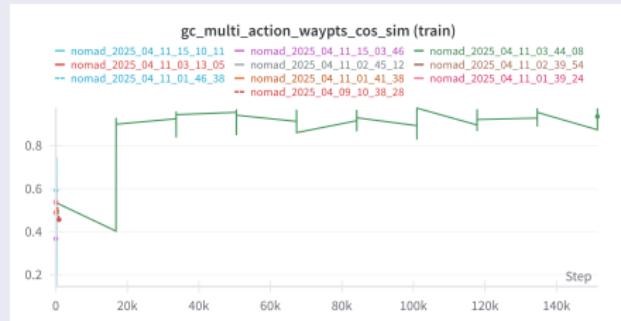


Validation Set

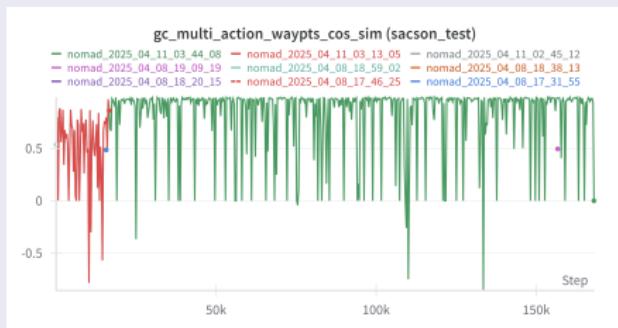
Cosine similarity evaluates directional alignment between predicted and ground-truth action waypoints. Higher values ( $\sim 1.0$ ) indicate better trajectory alignment under goal-conditioned settings.

# Experiments and Results: Multi-Action Cosine Similarity

## Goal-Conditioned Multi-Action Waypoints Cosine Similarity



Training Set



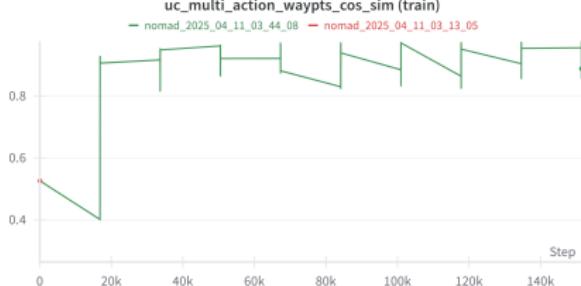
Validation Set

Multi-action cosine similarity compares the overall alignment of full predicted trajectory vectors with ground truth, rather than frame-by-frame. This provides a more holistic measure of long-horizon trajectory quality.

# Experiments and Results: UC Multi-Action Cosine Similarity

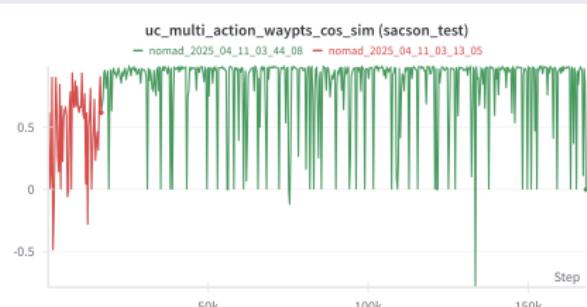
## Unconditioned Multi-Action Waypoints Cosine Similarity

uc\_multi\_action\_waypts\_cos\_sim (train)



**Training Set**

uc\_multi\_action\_waypts\_cos\_sim (sacson\_test)



**Validation Set**

Cosine similarity across the full predicted trajectory in unconditioned setting. Higher similarity indicates better alignment with ground-truth behavior.

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<https://github.com/robodhruv/visualnav-transformer>
- Cheng Chi et al., *Diffusion Policy: Visuomotor Policy Learning via Action Diffusion*, 2023. arXiv:2303.04137
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