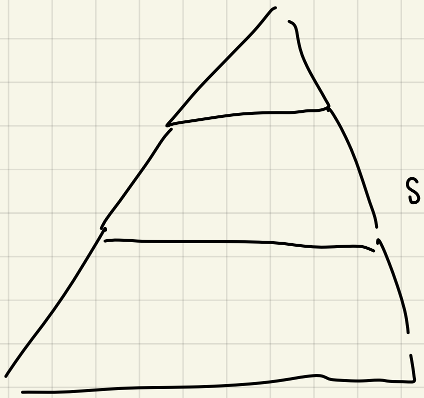
Pymarid.

NLP ✓

why still hard?

✓ nlp data.

✗ download motor control signal



real robot data / 24h/day (limit).

~~simulation~~

teleoperate

simulation data. / GPU.

good / limit.

internet data

GPT. (learn physical common sense)

++ noisy.

Principle No. 2 Matrix.

it's easier to simulate a prob than solve it.

? how to write a Api

self-generated data ⇒ RL.

Reward func ← behavior { desired / x desired

multiply data ⇒ Imitation learning

slow to collect.

1 human demo ⇒ $++ ↓data.

how to multiply? □ → □ □ □ □ □.

visual augmentation.

param ⇒ cerebellum?

HOVER. versatile controller ⇒ how train

human demo —change configuration→ machine-generated demo

⇓

Mimigen. mimigen. mimicgen. motion generator with it.

if not ++ human teleoperate data trajectory X.

task variation — filter out failing results.

in robocasa.

real → sim → real
collect multiply. improve

⇓,
save time/human ⊘

Principle No. 3
Foundation Agent.
single neural network ⇒ control all types robot.
⇓
Kinematic tree
→ humanoid
slightly diff.

sample → code candidate

eureka - simulation ⇒ Dreureka - reality.
~~pure-text~~ feedback reasoning
video ⇒ GPT ⇒ what's going on.

☆: Groot.
↑ data: embod control
instructions ⇒ actions

robocasa: generate tokens.
↑ eval.
↙
DGX: learn token — inference → Agx. deploy token.