



# Continual Learning for Robotics



**Manipulation**  
(Sec 2.1)



**Navigation**  
(Sec 2.2)



**Planning**  
(Sec 2.3)

Data



Continual World



Room-to-Room



Room-Across-Room



CL-ALFRED



BEHAVIOR

Techniques

Parameter Expansion

Memory Expansion

World Model

Parameter Isolation

Experience Replay

Regularization

MoE

PEFT

Generative Replay

Meta-Learning

Challenges



Benchmarks



Human-in-the-Loop



Continual World Models



Efficiency



Standardized Evaluation



Uncertainty Estimation



Imperfect Data



Federated



Embodiments & Sensors