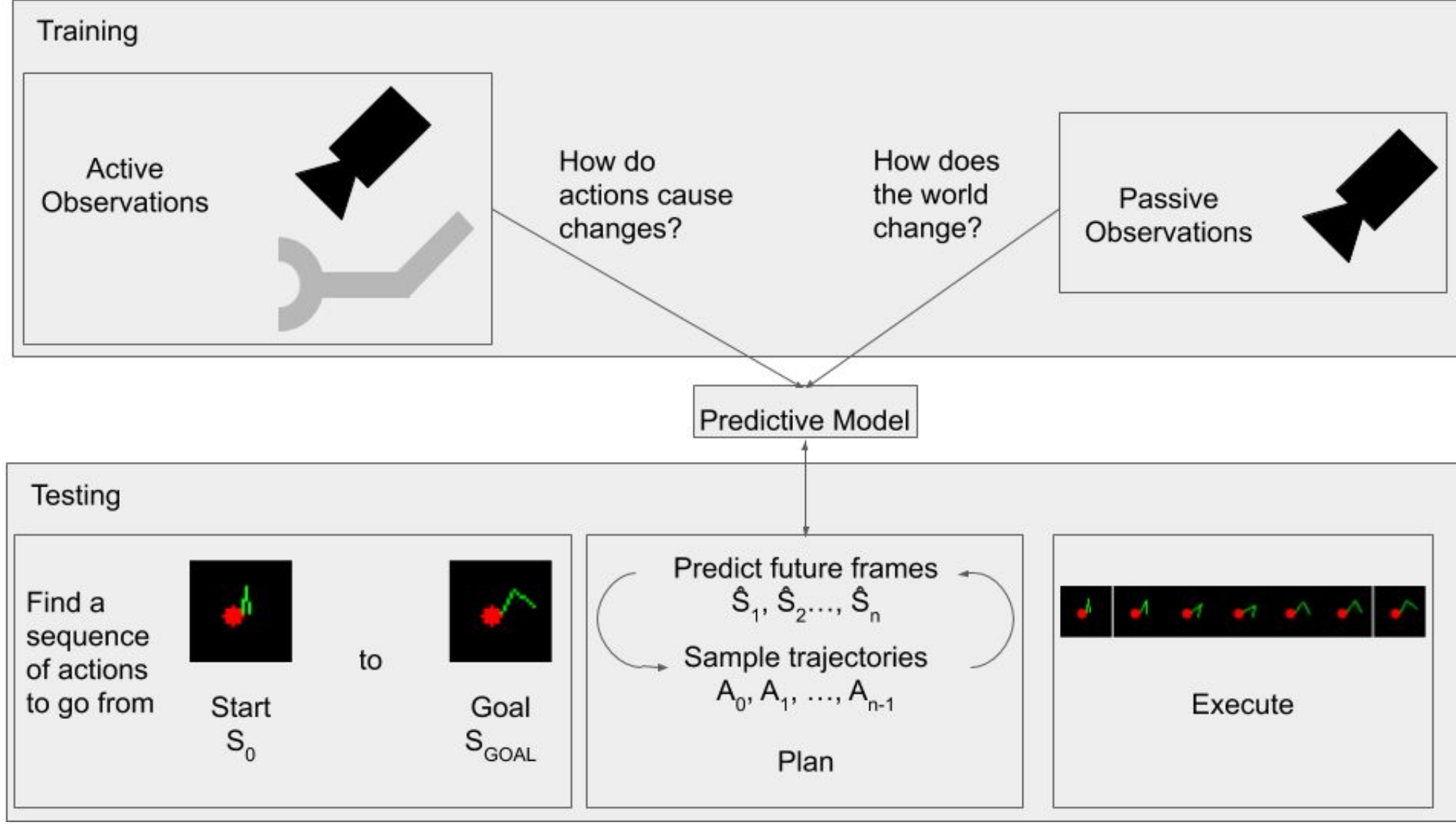
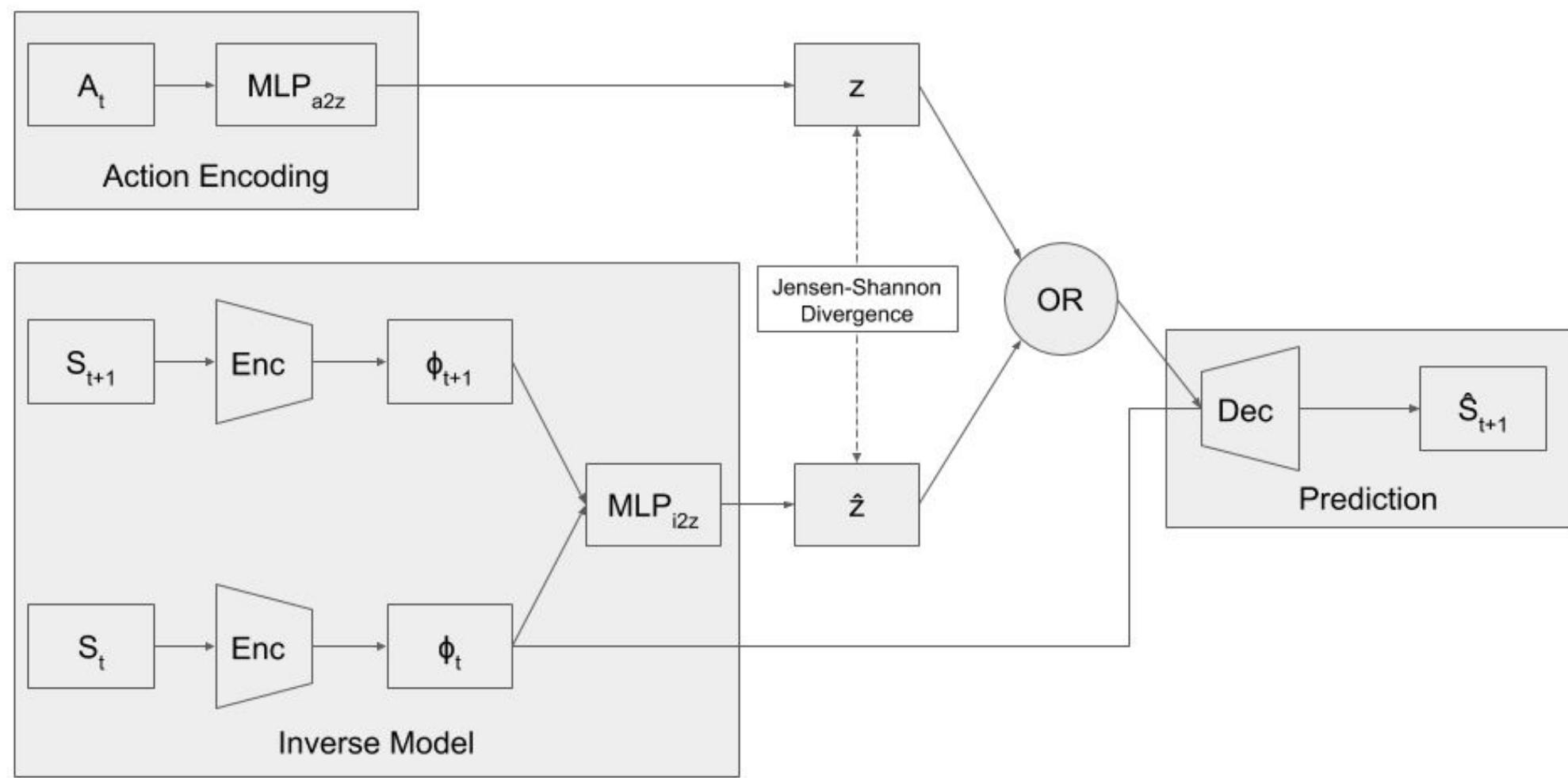


Visual Planning with Semi-Supervised Stochastic Action Representations

Motivation

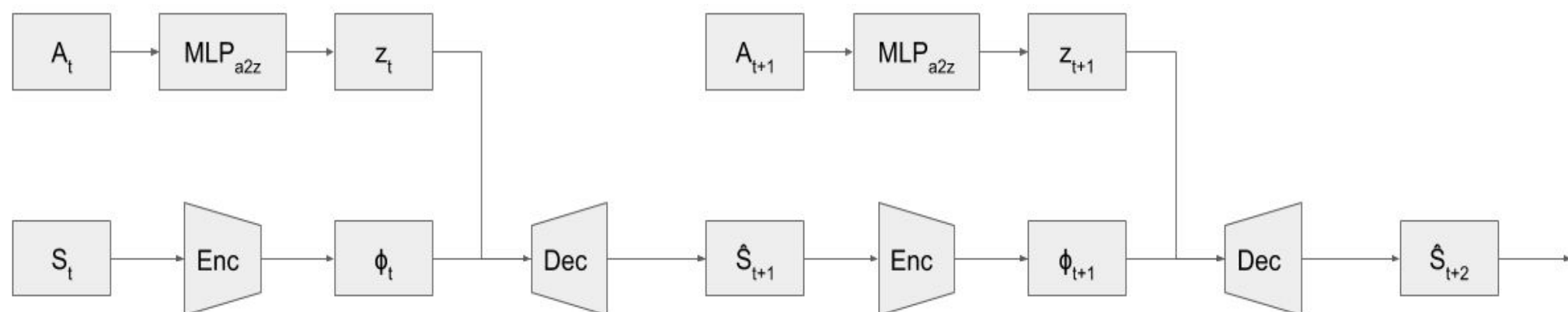


Semi-Supervised Action Representations



Our model generates stochastic action embeddings by either encoding the true action and by using a visual encoder. The two representations are pulled together with a Jensen-Shannon divergence loss. This allows to train the model via the visual encoder even when only a portion of the observations have corresponding actions.

Planning



Algorithm 1 The Cross Entropy Method

```

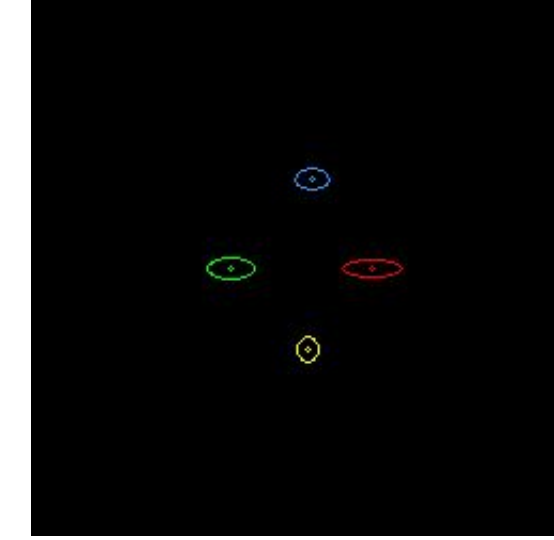
function CrossEntropyMethod( $X, \mu_0, \sigma_0^2$ )
  for  $i = 1$  to  $num\_iters$  do
     $trajectories[1 : N] \leftarrow sample(X, (\mu_{i-1}, \sigma_{i-1}^2))$ 
     $dists[1 : N] \leftarrow minDistance(trajectories[1 : N])$ 
     $trajectories \leftarrow sortByDists(trajectories, dists)$ 
     $\mu_i \leftarrow mean(trajectories[1 : N_{elite}])$ 
     $\sigma_i^2 \leftarrow variance(trajectories[1 : N_{elite}])$ 
  end for
  return  $sample(X, (\mu_{num\_iters}, \sigma_{num\_iters}^2))$ 
end function

```

We use our learned forward model with the cross entropy method to plan sequences of actions that reach the goal image.

Experiments

Our model learns to map the action representations z and \hat{z} to the same locations in the latent space, visualized in a two dimensional action latent space



Action encoder

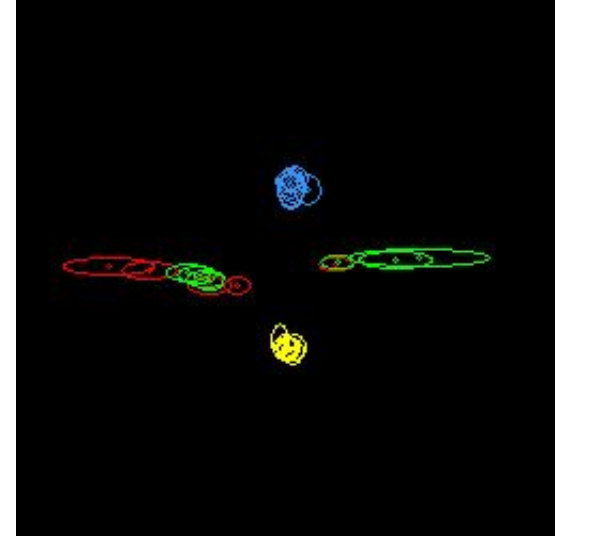
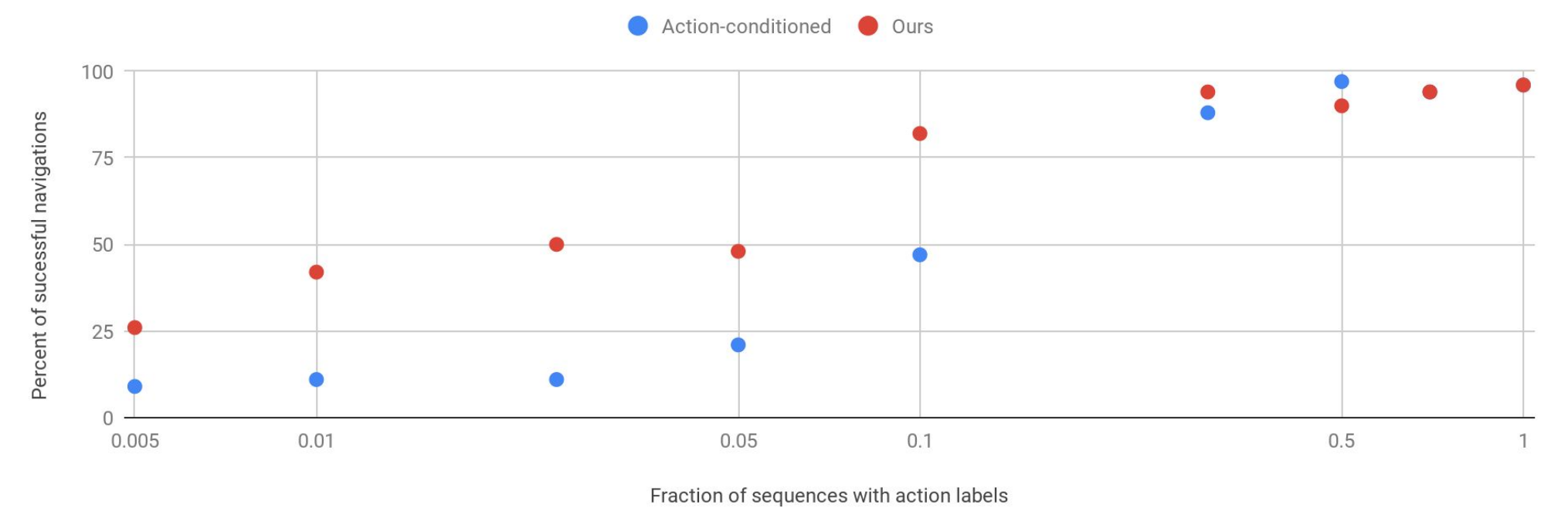


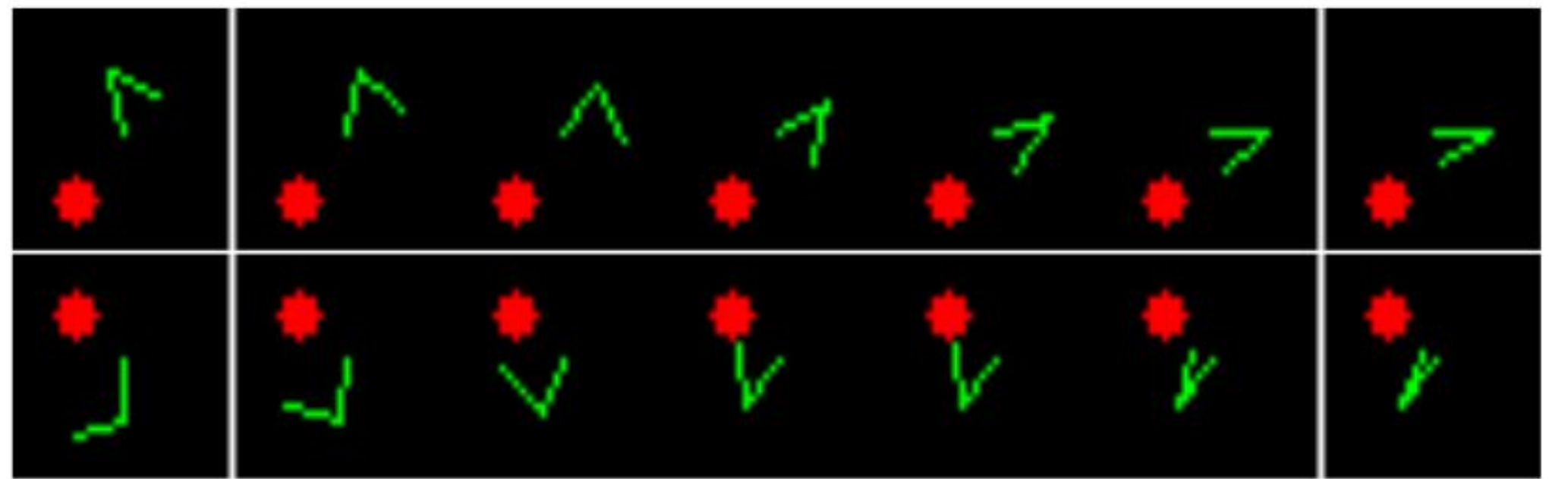
Image to action encoder

Planning success rate in the reacher environment

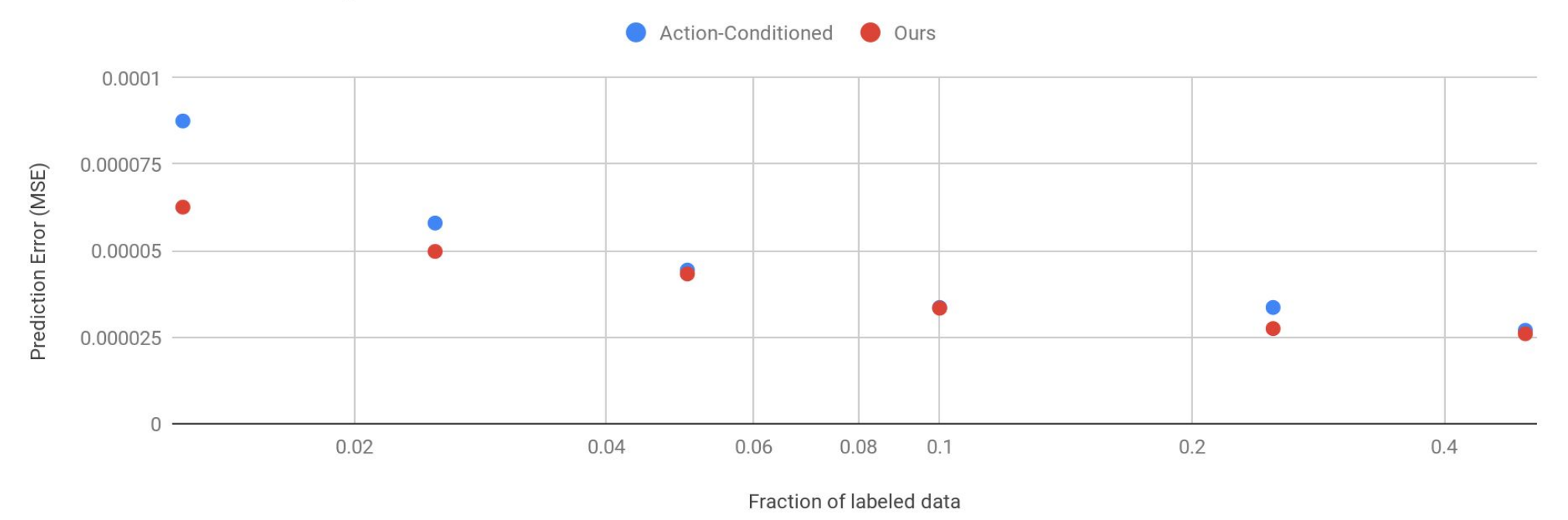


Our model learns a representation sufficient to plan executable trajectories for a 2-dof reacher.

As the amount of sequences with action labels decreases, the performance of our semi-supervised model degrades slower than a fully supervised model

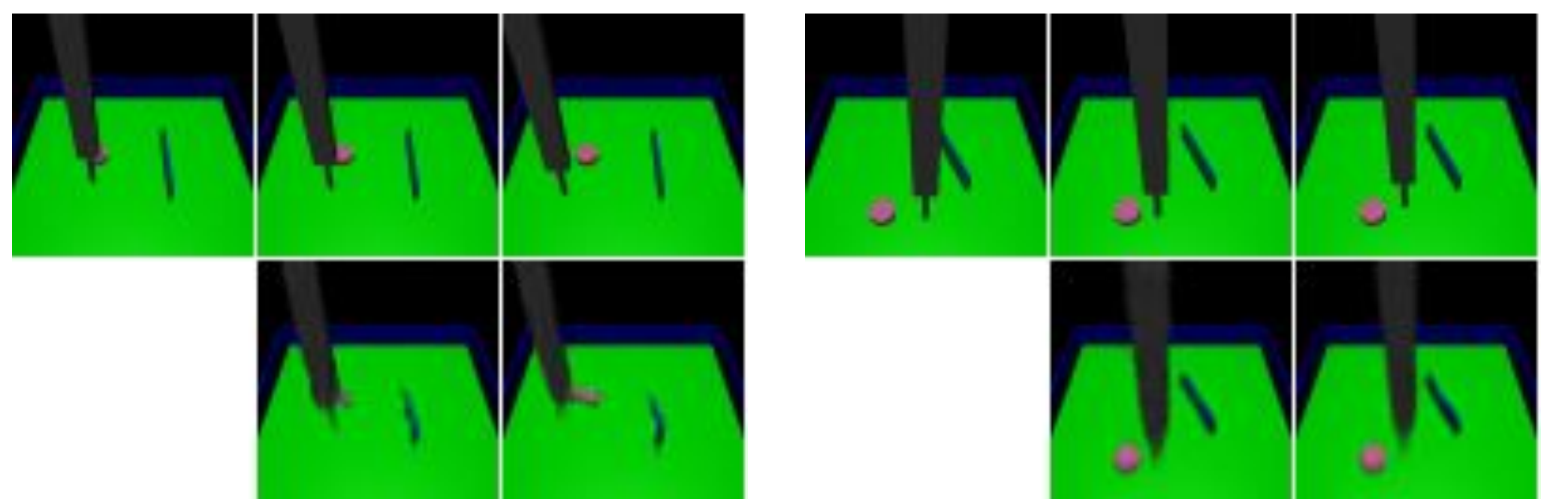


Prediction error in Mujoco



Our model was able to learn to predict future frames of video in a more complicated Mujoco simulation.

Even with only ~500 sequences of data with action labels, our system was able to generate realistic predictions of future frames.



Actioned-conditioned

Ours