

Mastering Diverse Domains through World Models

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Abstract

General intelligence requires solving tasks across many domains. Current reinforcement learning algorithms carry this potential but are held back by the resources and knowledge required to tune them for new tasks. We present DreamerV3, a general and scalable algorithm based on world models that outperforms previous approaches across a wide range of domains with fixed hyperparameters. These domains include continuous and discrete actions, visual and low-dimensional inputs, 2D and 3D worlds, different data budgets, reward frequencies, and reward scales. We observe favorable scaling properties of DreamerV3, with larger models directly translating to higher data-efficiency and final performance. Applied out of the box, DreamerV3 is the first algorithm to collect diamonds in Minecraft from scratch without human data or curricula, a long-standing challenge in artificial intelligence. Our general algorithm makes reinforcement learning broadly applicable and allows scaling to hard decision making problems.

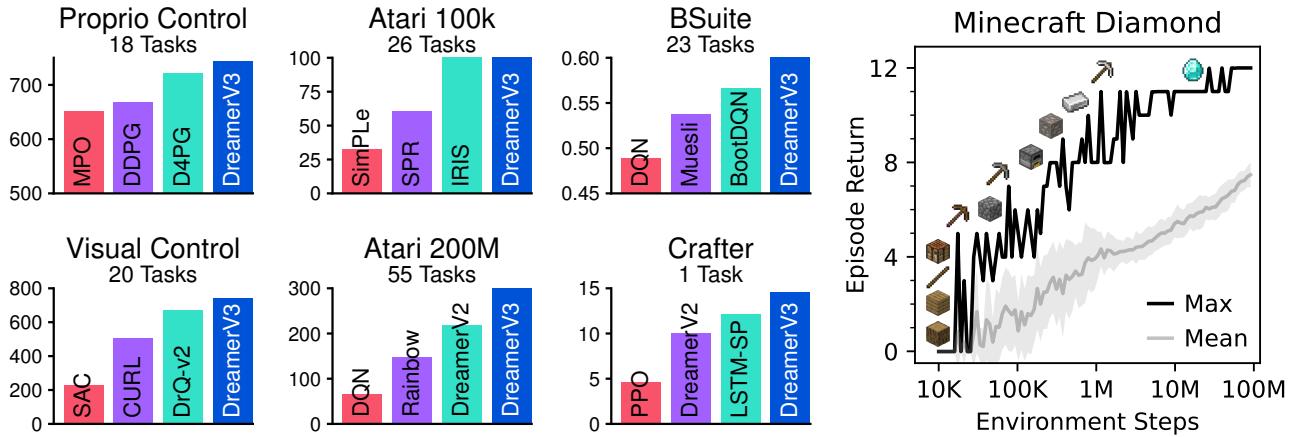


Figure 1: Using the same hyperparameters across all domains, DreamerV3 outperforms specialized model-free and model-based algorithms in a wide range of benchmarks and data-efficiency regimes. Applied out of the box, DreamerV3 also learns to obtain diamonds in the popular video game Minecraft from scratch given sparse rewards, a long-standing challenge in artificial intelligence for which previous approaches required human data or domain-specific heuristics.

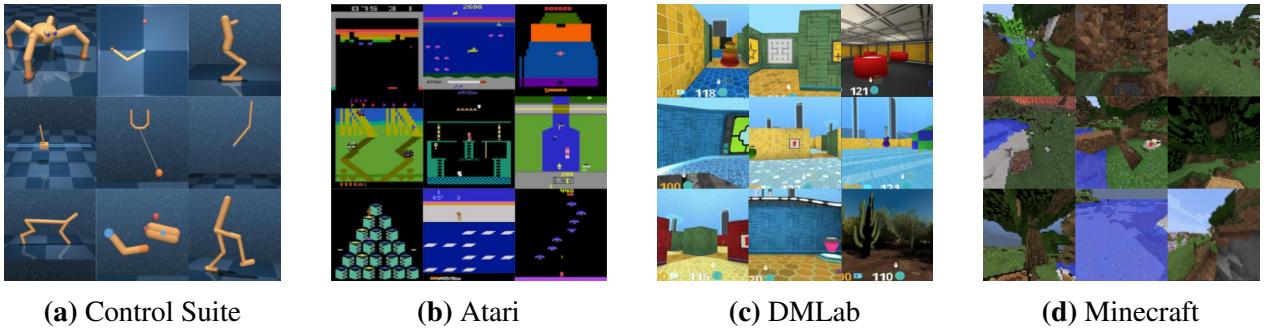


Figure 2: Four visual domains considered in this work. DreamerV3 succeeds across these diverse domains, ranging from robot locomotion and manipulation tasks over Atari games with 2D graphics to complex 3D domains such as DMLab and Minecraft that require spatial and temporal reasoning.

Introduction

Reinforcement learning has enabled computers to solve individual tasks through interaction, such as surpassing humans in the games of Go and Dota^{1,2}. However, applying algorithms to new application domains, for example from board games to video games or robotics tasks, requires expert knowledge and computational resources for tuning the algorithms³. This brittleness also hinders scaling to large models that are expensive to tune. Different domains pose unique learning challenges that have prompted specialized algorithms, such as for continuous control^{4,5}, sparse rewards^{6,7}, image inputs^{8,9}, and spatial environments^{10,11}. Creating a general algorithm that learns to master new domains out of the box—without tuning—would overcome the barrier of expert knowledge and open up reinforcement learning to a wide range of practical applications.

We present DreamerV3, a general and scalable algorithm that masters a wide range of domains with fixed hyperparameters, outperforming specialized algorithms. DreamerV3 learns a world model^{12,13,14} from experience for rich perception and imagination training. The algorithm consists of 3 neural networks: the world model predicts future outcomes of potential actions, the critic judges the value of each situation, and the actor learns to reach valuable situations. We enable learning across domains with fixed hyperparameters by transforming signal magnitudes and through robust normalization techniques. To provide practical guidelines for solving new challenges, we investigate the scaling behavior of DreamerV3. Notably, we demonstrate that increasing the model size of DreamerV3 monotonically improves both its final performance and data-efficiency.

The popular video game Minecraft has become a focal point of reinforcement learning research in recent years, with international competitions held for learning to collect diamonds in Minecraft¹⁵. Solving this challenge without human data has been widely recognized as a milestone for artificial intelligence because of the sparse rewards, exploration difficulty, and long time horizons in this procedurally generated open-world environment. Due to these obstacles, previous approaches resorted to human expert data and manually-crafted curricula^{16,17}. DreamerV3 is the first algorithm to collect diamonds in Minecraft from scratch, solving this challenge.

We summarize the four key contributions of this paper as follows:

- We present DreamerV3, a general algorithm that learns to master diverse domains while using fixed hyperparameters, making reinforcement learning readily applicable.
- We demonstrate the favorable scaling properties of DreamerV3, where increased model size leads to monotonic improvements in final performance and data-efficiency.

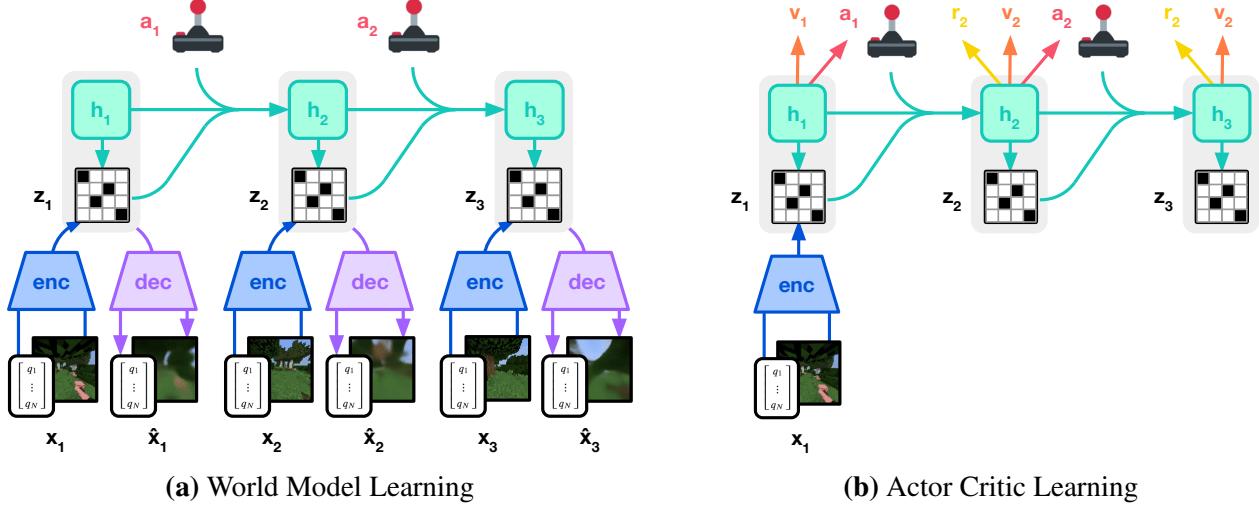


Figure 3: Training process of DreamerV3. The world model encodes sensory inputs into a discrete representation z_t that is predicted by a sequence model with recurrent state h_t given actions a_t . The inputs are reconstructed as learning signal to shape the representations. The actor and critic learn from trajectories of abstract representations predicted by the world model.

- We perform an extensive evaluation, showing that DreamerV3 outperforms more specialized algorithms across domains, and release the training curves of all methods to facilitate comparison.
 - We find that DreamerV3 is the first algorithm to collect diamonds in Minecraft from scratch without human data or curricula, solving a long-standing challenge in artificial intelligence.

DreamerV3

The DreamerV3 algorithm consists of 3 neural networks—the world model, the critic, and the actor—that are trained concurrently from replayed experience without sharing gradients, as shown in [Figure 3](#). To succeed across domains, these components need to accommodate different signal magnitudes and robustly balance terms in their objectives. This is challenging as we are not only targeting similar tasks within the same domain but aim to learn across different domains with fixed hyperparameters. This section first explains a simple transformation for predicting quantities of unknown orders of magnitude. We then introduce the world model, critic, and actor and their robust learning objectives. Specifically, we find that combining KL balancing and free bits enables the world model to learn without tuning, and scaling down large returns without amplifying small returns allows a fixed policy entropy regularizer. The differences to DreamerV2 are detailed in [Appendix C](#).

Symlog Predictions

Reconstructing inputs and predicting rewards and values can be challenging because their scale can vary across domains. Predicting large targets using a squared loss can lead to divergence whereas absolute and Huber losses¹⁸ stagnate learning. On the other hand, normalizing targets based on running statistics¹⁹ introduces non-stationarity into the optimization. We suggest *symlog predictions* as a simple solution to this dilemma. For this, a neural network $f(x, \theta)$ with inputs x and parameters

θ learns to predict a transformed version of its targets y . To read out predictions \hat{y} of the network, we apply the inverse transformation:

$$\mathcal{L}(\theta) \doteq \frac{1}{2} (f(x, \theta) - \text{symlog}(y))^2 \quad \hat{y} \doteq \text{symexp}(f(x, \theta)) \quad (1)$$

As shown in [Figure 4](#), using the logarithm as transformation would not allow us to predict targets that take on negative values. Therefore, we choose a function from the bi-symmetric logarithmic family²⁰ that we name *symlog* as the transformation with the *symexp* function as its inverse:

$$\text{symlog}(x) \doteq \text{sign}(x) \ln(|x| + 1) \quad \text{symexp}(x) \doteq \text{sign}(x) (\exp(|x|) - 1) \quad (2)$$

The *symlog* function compresses the magnitudes of both large positive and negative values. Unlike the logarithm, it is symmetric around the origin while preserving the input sign. This allows the optimization process to quickly move the network predictions to large values when needed. *Symlog* approximates the identity around the origin so that it does not affect learning of targets that are already small enough. For critic learning, a more involved transformation has previously been proposed²¹, which we found less effective on average across domains.

DreamerV3 uses *symlog* predictions in the decoder, the reward predictor, and the critic. It also squashes inputs to the encoder using the *symlog* function. Despite its simplicity, this approach robustly and quickly learns across a diverse range of environments. With *symlog* predictions, there is no need for truncating large rewards¹⁸, introducing non-stationary through reward normalization¹⁹, or adjusting network weights when new extreme values are detected²².

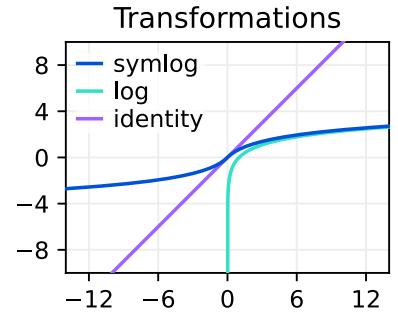


Figure 4: The *symlog* function compared to logarithm and identity.

World Model Learning

The world model learns compact representations of sensory inputs through autoencoding^{23,24} and enables planning by predicting future representations and rewards for potential actions. We implement the world model as a Recurrent State-Space Model (RSSM)¹⁴, as shown in [Figure 3](#). First, an encoder maps sensory inputs x_t to stochastic representations z_t . Then, a sequence model with recurrent state h_t predicts the sequence of these representations given past actions a_{t-1} . The concatenation of h_t and z_t forms the model state from which we predict rewards r_t and episode continuation flags $c_t \in \{0, 1\}$ and reconstruct the inputs to ensure informative representations:

$$\left. \begin{array}{ll} \text{RSSM} & \left\{ \begin{array}{ll} \text{Sequence model:} & h_t = f_\phi(h_{t-1}, z_{t-1}, a_{t-1}) \\ \text{Encoder:} & z_t \sim q_\phi(z_t | h_t, x_t) \\ \text{Dynamics predictor:} & \hat{z}_t \sim p_\phi(\hat{z}_t | h_t) \\ \text{Reward predictor:} & \hat{r}_t \sim p_\phi(\hat{r}_t | h_t, z_t) \\ \text{Continue predictor:} & \hat{c}_t \sim p_\phi(\hat{c}_t | h_t, z_t) \\ \text{Decoder:} & \hat{x}_t \sim p_\phi(\hat{x}_t | h_t, z_t) \end{array} \right. \end{array} \right\} \quad (3)$$

[Figure 5](#) visualizes long-term video predictions of the world world. The encoder and decoder use convolutional neural networks (CNN)²⁵ for visual inputs and multi-layer perceptrons (MLPs) for low-dimensional inputs. The dynamics, reward, and continue predictors are also MLPs. The representations are sampled from a vector of softmax distributions and we take straight-through

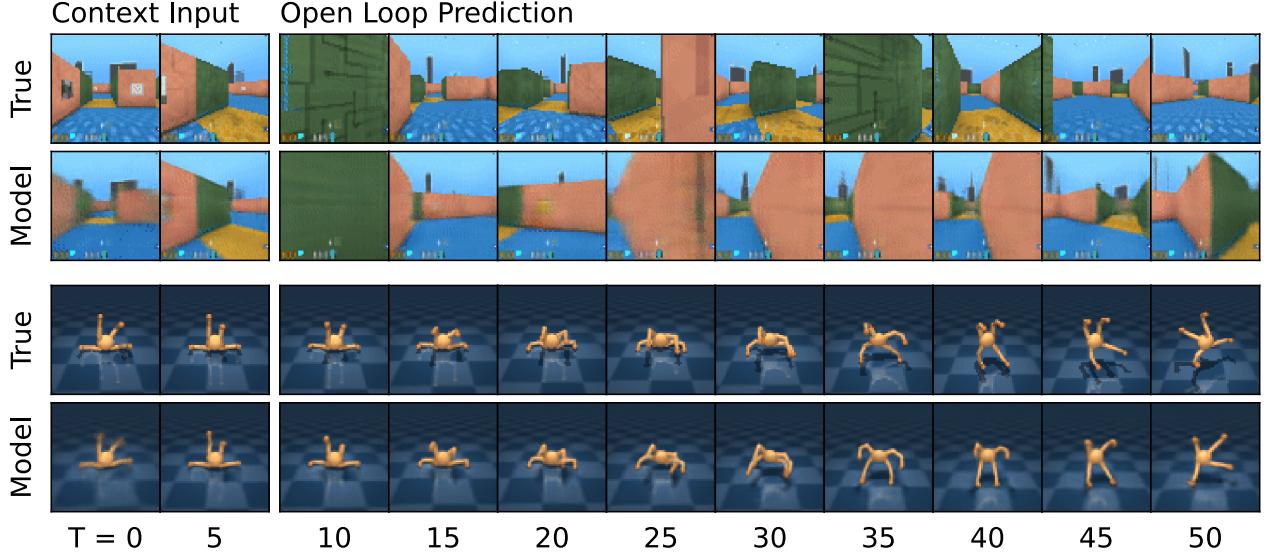


Figure 5: Multi-step video predictions in DMLab (top) and Control Suite (bottom). From 5 frames of context input, the model predicts 45 steps into the future given the action sequence and without access to intermediate images. The world model learns an understanding of the underlying 3D structure of the two environments. Refer to Appendix H for additional video predictions.

gradients through the sampling step^{26,27}. Given a sequence batch of inputs $x_{1:T}$, actions $a_{1:T}$, rewards $r_{1:T}$, and continuation flags $c_{1:T}$, the world model parameters ϕ are optimized end-to-end to minimize the prediction loss $\mathcal{L}_{\text{pred}}$, the dynamics loss \mathcal{L}_{dyn} , and the representation loss \mathcal{L}_{rep} with corresponding loss weights $\beta_{\text{pred}} = 1$, $\beta_{\text{dyn}} = 0.5$, $\beta_{\text{rep}} = 0.1$:

$$\mathcal{L}(\phi) \doteq \mathbb{E}_{q_\phi} \left[\sum_{t=1}^T (\beta_{\text{pred}} \mathcal{L}_{\text{pred}}(\phi) + \beta_{\text{dyn}} \mathcal{L}_{\text{dyn}}(\phi) + \beta_{\text{rep}} \mathcal{L}_{\text{rep}}(\phi)) \right]. \quad (4)$$

The prediction loss trains the decoder and reward predictor via the symlog loss and the continue predictor via binary classification loss. The dynamics loss trains the sequence model to predict the next representation by minimizing the KL divergence between the predictor $p_\phi(z_t | h_t)$ and the next stochastic representation $q_\phi(z_t | h_t, x_t)$. The representation loss trains the representations to become more predictable if the dynamics cannot predict their distribution, allowing us to use a factorized dynamics predictor for fast sampling when training the actor critic. The two losses differ in the stop-gradient operator $\text{sg}(\cdot)$ and their loss scale. To avoid a degenerate solution where the dynamics are trivial to predict but contain not enough information about the inputs, we employ free bits²⁸ by clipping the dynamics and representation losses below the value of 1 nat ≈ 1.44 bits. This disables them while they are already minimized well to focus the world model on its prediction loss:

$$\begin{aligned} \mathcal{L}_{\text{pred}}(\phi) &\doteq -\ln p_\phi(x_t | z_t, h_t) - \ln p_\phi(r_t | z_t, h_t) - \ln p_\phi(c_t | z_t, h_t) \\ \mathcal{L}_{\text{dyn}}(\phi) &\doteq \max(1, \text{KL}[\text{sg}(q_\phi(z_t | h_t, x_t)) \| p_\phi(z_t | h_t)]) \\ \mathcal{L}_{\text{rep}}(\phi) &\doteq \max(1, \text{KL}[q_\phi(z_t | h_t, x_t) \| \text{sg}(p_\phi(z_t | h_t))] \end{aligned} \quad (5)$$

Previous world models require scaling the representation loss differently based on the visual complexity of the environment. Complex 3D environments contain details unnecessary for control and thus prompt a stronger regularizer to simplify the representations and make them more predictable. In 2D games, the background is often static and individual pixels may matter for the task, requiring a weak regularizer to perceive fine details. We find that combining free bits with a small scale for

the representation loss resolve this dilemma, allowing for fixed hyperparameters across domains. Moreover, symlog predictions for the decoder unify the gradient scale of the prediction loss across environments, further stabilizing the trade-off with the representation loss.

We occasionally observed spikes in KL losses in earlier experiments, consistent with reports for deep variational autoencoders^{29,30}. To prevent this, we parameterize the categorical distributions of the encoder and dynamics predictor as mixtures of 1% uniform and 99% neural network output, making it impossible for them to become near deterministic and thus ensuring well-scaled KL losses. Further model details and hyperparameters are summarized in [Table W.1](#).

Actor Critic Learning

The actor and critic neural networks learn behaviors purely from abstract sequences predicted by the world model^{12,13}. During environment interaction, we select actions by sampling from the actor network without lookahead planning. The actor and critic operate on model states $s_t \doteq \{h_t, z_t\}$ and thus benefit from the Markovian representations learned by the world model. The actor aims to maximize the expected return $R_t \doteq \sum_{\tau=0}^{\infty} \gamma^\tau r_{t+\tau}$ with a discount factor $\gamma = 0.997$ for each model state. To consider rewards beyond the prediction horizon $T = 16$, the critic learns to predict the return of each state under the current actor behavior:

$$\begin{aligned} \text{Actor: } & a_t \sim \pi_\theta(a_t \mid s_t) \\ \text{Critic: } & v_\psi(s_t) \approx \mathbb{E}_{p_\phi, \pi_\theta}[R_t] \end{aligned} \tag{6}$$

Starting from representations of replayed inputs, the dynamics predictor and actor produce a sequence of imagined model states $s_{1:T}$, actions $a_{1:T}$, rewards $r_{1:T}$, and continuation flags $c_{1:T}$. To estimate returns that consider rewards beyond the prediction horizon, we compute bootstrapped λ -returns that integrate the predicted rewards and values^{31,32}:

$$R_t^\lambda \doteq r_t + \gamma c_t \left((1 - \lambda)v_\psi(s_{t+1}) + \lambda R_{t+1}^\lambda \right) \quad R_T^\lambda \doteq v_\psi(s_T) \tag{7}$$

Critic Learning A simple choice for the critic loss function would be to regress the λ -returns via squared error or symlog predictions. However, the critic predicts the expected value of a potentially widespread return distribution, which can slow down learning. We choose a discrete regression approach for learning the critic based on *twohot* encoded targets^{33,34,35,36} that let the critic maintain and refine a distribution over potential returns. For this, we transform returns using the symlog function and discretize the resulting range into a sequence B of $K = 255$ equally spaced buckets b_i . The critic network outputs a softmax distribution $p_\psi(b_i \mid s_t)$ over the buckets and its output is formed as the expected bucket value under this distribution. Importantly, the critic can predict any continuous value in the interval because its expected bucket value can fall between the buckets:

$$v_\psi(s_t) \doteq \text{symexp}(\mathbb{E}_{p_\psi(b_i \mid s_t)}[b_i]) = \text{symexp}(p_\psi(\cdot \mid s_t)^T B) \quad B \doteq [-20 \dots +20] \tag{8}$$

To train the critic, we symlog transform the targets R_t^λ and then twohot encode them into a soft label for the softmax distribution produced by the critic. Twohot encoding is a generalization of onehot encoding to continuous values. It produces a vector of length $|B|$ where all elements are 0 except for the two entries closest to the encoded continuous number, at positions k and $k + 1$. These two

entries sum up to 1, with more weight given to the entry that is closer to the encoded number:

$$\text{twohot}(x)_i \doteq \begin{cases} |b_{k+1} - x| / |b_{k+1} - b_k| & \text{if } i = k \\ |b_k - x| / |b_{k+1} - b_k| & \text{if } i = k + 1 \\ 0 & \text{else} \end{cases} \quad k \doteq \sum_{j=1}^B \delta(b_j < x) \quad (9)$$

Given twohot encoded targets $y_t = \text{sg}(\text{twohot}(\text{symlog}(R_t^\lambda)))$, where $\text{sg}(\cdot)$ stops the gradient, the critic minimizes the categorical cross entropy loss for classification with soft targets:

$$\mathcal{L}_{\text{critic}}(\psi) \doteq \sum_{t=1}^T \mathbb{E}_{b_i \sim y_t} [-\ln p_\psi(b_i \mid s_t)] = -\sum_{t=1}^T y_t^T \ln p_\psi(\cdot \mid s_t) \quad (10)$$

We found discrete regression for the critic to accelerate learning especially in environments with sparse rewards, likely because of their bimodal reward and return distributions. We use the same discrete regression approach for the reward predictor of the world model.

Because the critic regresses targets that depend on its own predictions, we stabilize learning by regularizing the critic towards predicting the outputs of an exponentially moving average of its own parameters. This is similar to target networks used previously in reinforcement learning¹⁸ but allows us to compute returns using the current critic network. We further noticed that the randomly initialized reward predictor and critic networks at the start of training can result in large predicted rewards that can delay the onset of learning. We initialize the output weights of the reward predictor and critic to zeros, which effectively alleviates the problem and accelerates early learning.

Actor Learning The actor network learns to choose actions that maximize returns while ensuring sufficient exploration through an entropy regularizer³⁷. However, the scale of this regularizer heavily depends on the scale and frequency of rewards in the environment, which has been a challenge for previous algorithms³⁸. Ideally, we would like the policy to explore quickly in the absence of nearby returns without sacrificing final performance under dense returns.

To stabilize the scale of returns, we normalize them using moving statistics. For tasks with dense rewards, one can simply divide returns by their standard deviation, similar to previous work¹⁹. However, when rewards are sparse, the return standard deviation is generally small and this approach would amplify the noise contained in near-zero returns, resulting in an overly deterministic policy that fails to explore. Therefore, we propose to scale down large returns without scaling up small returns. We implement this idea by dividing returns by their scale S , for which we discuss multiple choices below, but only if they exceed a minimum threshold of 1. This simple change is the key to allowing a single entropy scale $\eta = 3 \cdot 10^{-4}$ across dense and sparse rewards:

$$\mathcal{L}(\theta) \doteq \sum_{t=1}^T \mathbb{E}_{\pi_\theta, p_\phi} [\text{sg}(R_t^\lambda) / \max(1, S)] - \eta H [\pi_\theta(a_t \mid s_t)] \quad (11)$$

We follow DreamerV2²⁷ in estimating the gradient of the first term by stochastic backpropagation for continuous actions and by reinforce³⁹ for discrete actions. The gradient of the second term is computed in closed form.

In deterministic environments, we find that normalizing returns by their exponentially decaying standard deviation suffices. However, for heavily randomized environments, the return distribution can be highly non-Gaussian and contain outliers of large returns caused by a small number of particularly easy episodes, leading to an overly deterministic policy that struggles to sufficiently

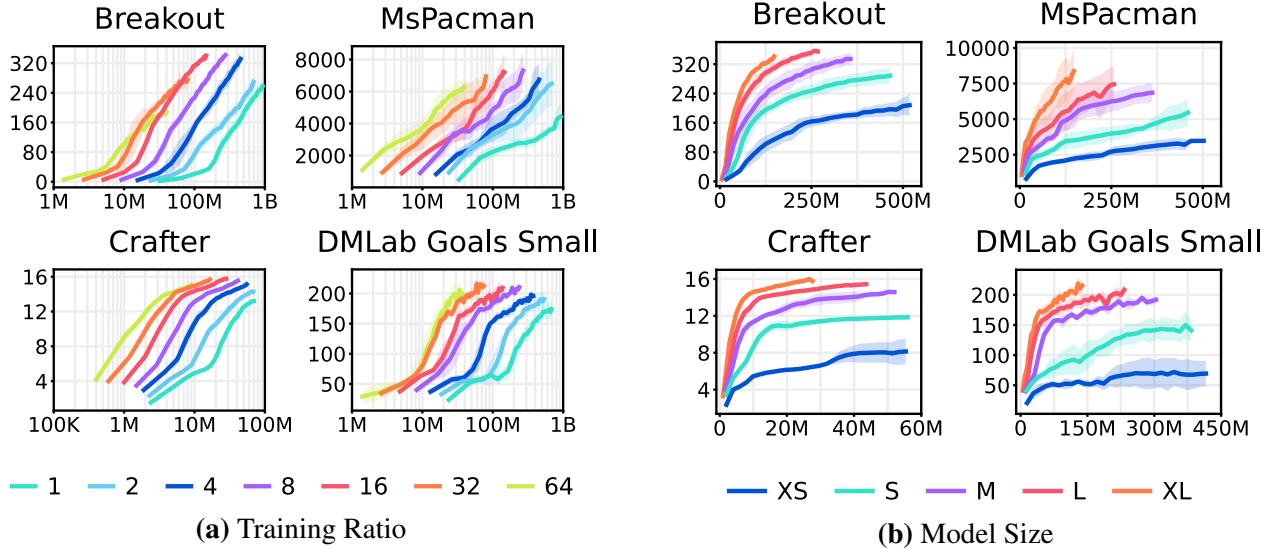


Figure 6: Scaling properties of DreamerV3. The graphs show task performance over environment steps for different training ratios and model sizes reaching from 8M to 200M parameters. The training ratio is the ratio of replayed steps to environment steps. The model sizes are detailed in [Table B.1](#). Higher training ratios result in substantially improved data-efficiency. Notably, larger models achieve not only higher final performance but also higher data-efficiency.

explore. To normalize returns while being robust to such outliers, we scale returns by an exponentially decaying average of the range from their 5th to their 95th batch percentile:

$$S = \text{Per}(R_t^\lambda, 95) - \text{Per}(R_t^\lambda, 5) \quad (12)$$

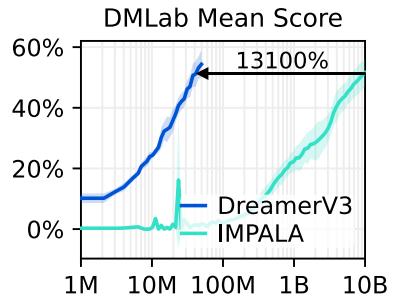
Because a constant return offset does not affect the objective, this is equivalent to an affine transformation that maps these percentiles to 0 and 1, respectively. Compared to advantage normalization¹⁹, scaling returns down accelerates exploration under sparse rewards without sacrificing final performance under dense rewards, while using a fixed entropy scale.

Results

We perform an extensive empirical study to evaluate the generality and scalability of DreamerV3 across diverse domains—with over 150 tasks—under fixed hyperparameters. We designed the experiments to compare DreamerV3 to the best methods in the literature, which are often specifically designed to the benchmark at hand. Moreover, we apply DreamerV3 to the challenging video game Minecraft. Table A.1 gives an overview of the domains. For DreamerV3, we directly report the performance of the stochastic training policy and avoid separate evaluation runs using the deterministic policy, simplifying the setup. All DreamerV3 agents are trained on one Nvidia V100 GPU each, making the algorithm widely usable across research labs. The source code and numerical results are available on the project website: <https://danijar.com/dreamerv3>

Benchmarks To evaluate the generality of DreamerV3, we perform an extensive empirical evaluation across 7 domains that include continuous and discrete actions, visual and low-dimensional inputs, dense and sparse rewards, different reward scales, 2D and 3D worlds, and procedural generation. Figure 1 summarizes the results, with training curves and score tables included in the appendix. DreamerV3 achieves strong performance on all domains and outperforms all previous algorithms on 4 of them, while also using fixed hyperparameters across all benchmarks.

- **Proprio Control Suite** This benchmark contains 18 continuous control tasks with low-dimensional inputs and a budget of 500K environment steps⁴⁰. The tasks range from classical control over locomotion to robot manipulation tasks. DreamerV3 sets a new state-of-the-art on this benchmark, outperforming D4PG⁴¹, DMPO⁴², and MPO⁴³.
- **Visual Control Suite** This benchmark consists of 20 continuous control tasks where the agent receives only high-dimensional images as inputs and a budget of 1M environment steps^{40,27}. DreamerV3 establishes a new state-of-the-art on this benchmark, outperforming DrQ-v2⁴⁴ and CURL⁴⁵ which additionally require data augmentations.
- **Atari 100k** This benchmark includes 26 Atari games and a budget of only 400K environment steps, amounting to 100K steps after action repeat or 2 hours of real time⁴⁶. EfficientZero⁴⁷ holds the state-of-the-art on this benchmark by combining online tree search, prioritized replay, hyperparameter scheduling, and allowing early resets of the games; see Table T.1 for an overview. Without this complexity, DreamerV3 outperforms the remaining previous methods such as the transformer-based IRIS⁴⁸, the model-free SPR⁴⁹, and SimPLe⁴⁶.
- **Atari 200M** This popular benchmark includes 55 Atari video games with simple graphics and a budget of 200M environment steps⁵⁰. We use the sticky action setting⁵¹. DreamerV3 outperforms DreamerV2 with a median score of 302% compared to 219%, as well as the top model-free algorithms Rainbow⁵² and IQN⁵³ that were specifically designed for the Atari benchmark.
- **BSuite** This benchmark includes 23 environments with a total of 468 configurations that are designed to test credit assignment, robustness to reward scale and stochasticity, memory, generalization, and exploration⁵⁴. DreamerV3 establishes a new state-of-the-art on this benchmark, outperforming Bootstrap DQN⁵⁵ as well as Muesli⁵⁶ with comparable amount of training. DreamerV3 improves over previous algorithms the most in the credit assignment category.
- **Crafter** This procedurally generated survival environment with top-down graphics and discrete actions is designed to evaluate a broad range of agent abilities, including wide and deep exploration, long-term reasoning and credit assignment, and generalization⁵⁷. DreamerV3 sets a new state-of-the-art on this benchmark, outperforming PPO with the LSTM-SPCNN architecture⁵⁸, the object-centric OC-SA⁵⁸, DreamerV2²⁷, and Rainbow⁵².
- **DMLab** This domain contains 3D environments that require spatial and temporal reasoning⁵⁹. On 8 challenging tasks, DreamerV3 matches and exceeds the final performance on the scalable IMPALA agent⁶⁰ in only 50M compared to 10B environment steps, amounting to a data-efficiency gain of over 13000%. We note that IMPALA was not designed for data-efficiency but serves as a valuable baseline for the performance achievable by scalable RL algorithms without data constraints.



Scaling properties Solving challenging tasks out of the box not only requires an algorithm that succeeds without adjusting hyperparameters, but also the ability to leverage large models to solve hard tasks. To investigate the scaling properties of DreamerV3, we train 5 model sizes ranging from 8M to 200M parameters. As shown in [Figure 6](#), we discover favorable scaling properties where increasing the model size directly translates to both higher final performance and data-efficiency. Increasing the number of gradient steps further reduces the number of interactions needed to learn successful behaviors. These insights serve as practical guidance for applying DreamerV3 to new tasks and demonstrate the robustness and scalability of the algorithm.

Minecraft Collecting diamonds in the open-world game Minecraft has been a long-standing challenge in artificial intelligence. Every episode in this game is set in a different procedurally generated 3D world, where the player needs to discover a sequence of 12 milestones with sparse rewards by foraging for resources and using them to craft tools. The environment is detailed in [Appendix F](#). We follow prior work¹⁷ and increase the speed at which blocks break because a stochastic policy is unlikely to sample the same action often enough in a row to break blocks without regressing its progress by sampling a different action.

Because of the training time in this complex domain, tuning algorithms specifically for Minecraft would be difficult. Instead, we apply DreamerV3 out of the box with its default hyperparameters. As shown in [Figure 1](#), DreamerV3 is the first algorithm to collect diamonds in Minecraft from scratch without using human data that was required by VPT¹⁶. Across 40 seeds trained for 100M environment steps, DreamerV3 collects diamonds in 50 episodes. It collects the first diamond after 29M steps and the frequency increases as training progresses. A total of 24 of the 40 seeds collect at least one diamond and the most successful agent collects diamonds in 6 episodes. The success rates for all 12 milestones are shown in [Figure G.1](#).

Previous Work

Developing general-purpose algorithms has long been a goal of reinforcement learning research. PPO¹⁹ is one of the most widely used algorithms and requires relatively little tuning but uses large amounts of experience due to its on-policy nature. SAC³⁸ is a popular choice for continuous control and leverages experience replay for higher data-efficiency, but in practice requires tuning, especially for its entropy scale, and struggles with high-dimensional inputs⁶¹. MuZero³⁴ plans using a value prediction model and has achieved high performance at the cost of complex algorithmic components, such as MCTS with UCB exploration and prioritized replay. Gato⁶² fits one large model to expert demonstrations of multiple tasks, but is only applicable to tasks where expert data is available. In comparison, we show that DreamerV3 masters a diverse range of environments trained with fixed hyperparameters and from scratch.

Minecraft has been a focus of recent reinforcement learning research. With MALMO⁶³, Microsoft released a free version of the popular game for research purposes. MineRL¹⁵ offers several competition environments, which we rely on as the basis for our experiments. MineDojo⁶⁴ provides a large catalog of tasks with sparse rewards and language descriptions. The yearly MineRL competition supports agents in exploring and learning meaningful skills through a diverse human dataset¹⁵. VPT¹⁶ trained an agent to play Minecraft through behavioral cloning of expert data collected by contractors and finetuning using reinforcement learning, resulting in a 2.5% success rate of diamonds using 720 V100 GPUs for 9 days. In comparison, DreamerV3 learns to collect diamonds in 17 GPU days from sparse rewards and without human data.

Conclusion

This paper presents DreamerV3, a general and scalable reinforcement learning algorithm that masters a wide range of domains with fixed hyperparameters. To achieve this, we systematically address varying signal magnitudes and instabilities in all of its components. DreamerV3 succeeds across 7 benchmarks and establishes a new state-of-the-art on continuous control from states and images, on BSuite, and on Crafter. Moreover, DreamerV3 learns successfully in 3D environments that require spatial and temporal reasoning, outperforming IMPALA in DMLab tasks using 130 times fewer interactions and being the first algorithm to obtain diamonds in Minecraft end-to-end from sparse rewards. Finally, we demonstrate that the final performance and data-efficiency of DreamerV3 improve monotonically as a function of model size.

Limitations of our work include that DreamerV3 only learns to sometimes collect diamonds in Minecraft within 100M environment steps, rather than during every episode. Despite some procedurally generated worlds being more difficult than others, human experts can typically collect diamonds in all scenarios. Moreover, we increase the speed at which blocks break to allow learning Minecraft with a stochastic policy, which could be addressed through inductive biases in prior work. To show how far the scaling properties of DreamerV3 extrapolate, future implementations at larger scale are necessary. In this work, we trained separate agents for all tasks. World models carry the potential for substantial transfer between tasks. Therefore, we see training larger models to solve multiple tasks across overlapping domains as a promising direction for future investigations.

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A Benchmark Overview

Benchmark	Tasks	Env Steps	Action Repeat	Env Instances	Train Ratio	GPU Days	Model Size
DMC Proprio	18	500K	2	4	512	<1	S
DMC Vision	20	1M	2	4	512	<1	S
Crafter	1	1M	1	1	512	2	XL
BSuite	23	—	1	1	1024	<1	XL
Atari 100K	26	400K	4	1	1024	<1	S
Atari 200M	55	200M	4	8	64	16	XL
DMLab	8	50M	4	8	64	4	XL
Minecraft	1	100M	1	16	16	17	XL

Table A.1: Benchmark overview. The train ratio is the number of replayed steps per policy steps rather than environment steps, and thus unaware of the action repeat. BSuite sets the number of episodes rather than env steps, both of which vary across tasks. BSuite requires multiple configurations per environment and one seed per configuration, resulting in 468 runs. For DMC, the proprioceptive benchmark excludes the quadruped tasks that are present in the visual benchmark because of baseline availability in prior work. All agents were trained on 1 Nvidia V100 GPU each.

B Model Sizes

Dimension	XS	S	M	L	XL
GRU recurrent units	256	512	1024	2048	4096
CNN multiplier	24	32	48	64	96
Dense hidden units	256	512	640	768	1024
MLP layers	1	2	3	4	5
Parameters	8M	18M	37M	77M	200M

Table B.1: Model sizes. The encoder consists of stride 2 convolutions of doubling depth until resolution 4×4 followed by flattening. The decoder starts with a dense layer, followed by reshaping to $4 \times 4 \times C$ and then inverts the encoder architecture. The dynamics are implemented as RSSM with vectors of categorical representations, consisting of a GRU and dense layers.

C Summary of Differences

DreamerV3 builds upon the DreamerV2 algorithm²⁷. This section describes the main changes that we applied in order to master a wide range of domains with fixed hyperparameters and enable robust learning on unseen domains.

- **Symlog predictions** We symlog encode inputs to the world model and use symlog predictions with squared error for reconstructing inputs. The reward predictor and critic use twohot symlog predictions, a simple form of distributional reinforcement learning³³.
- **World model regularizer** We experimented with different approaches for removing the need to tune the KL regularizer, including targeting a fixed KL value. A simple yet effective solution turned out to combine KL balancing that was introduced in DreamerV2²⁷ with free bits²⁸ that were used in the original Dreamer algorithm⁶⁵. GECO⁶⁶ was not useful in our case because what constitutes “good” reconstruction error varies widely across domains.
- **Policy regularizer** Using a fixed entropy regularizer for the actor was challenging when targeting both dense and sparse rewards. Scaling large return ranges down to the $[0, 1]$ interval, without amplifying near-zero returns, overcame this challenge. Using percentiles to ignore outliers in the return range further helped, especially for stochastic environments. We did not experience improvements from regularizing the policy towards its own EMA⁶⁷ or the CMPO regularizer⁵⁶.
- **Unimix categoricals** We parameterize the categorical distributions for the world model representations and dynamics, as well as for the actor network, as mixtures of 1% uniform and 99% neural network output^{68,69} to ensure a minimal amount of probability mass on every class and thus keep log probabilities and KL divergences well behaved.
- **Architecture** We use a similar network architecture but employ layer normalization⁷⁰ and SiLU⁷¹ as the activation function. For better framework support, we use same-padded convolutions with stride 2 and kernel size 3 instead of valid-padded convolutions with larger kernels. The robustness of DreamerV3 allowed us to use large networks that contributed to its performance.
- **Critic EMA regularizer** We compute λ -returns using the fast critic network and regularize the critic outputs towards those of its own weight EMA instead of computing returns using the slow critic. However, both approaches perform similarly in practice.
- **Replay buffer** DreamerV2 used a replay buffer that only replays time steps from completed episodes. To shorten the feedback loop, DreamerV3 uniformly samples from all inserted subsequences of size batch length regardless of episode boundaries.
- **Hyperparameters** The hyperparameters of DreamerV3 were tuned to perform well across both the visual control suite and Atari 200M at the same time. We verified their generality by training on new domains without further adjustment, including Crafter, BSuite, and Minecraft.

Target Regularizers

We also experimented with constrained optimization for the world model and policy objectives, where we set a target value that the regularizer should take on, on average across states. We found combining this approach with limits on the allowed regularizer scales to perform well for the world model, at the cost of additional complexity. For the actor, choosing a target randomness of 40%—where 0% corresponds to the most deterministic and 100% to the most random policy—learns robustly across domains but prevents the policy from converging to top scores in tasks that require speed or precision and slows down exploration under sparse rewards. The solutions in DreamerV3 do not have these issues intrinsic to constrained optimization formulations.

D Ablation Curves

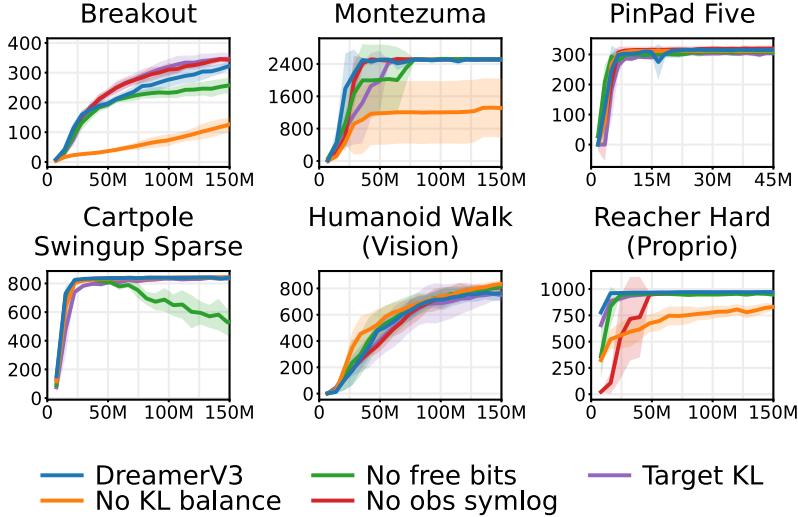


Figure D.1: World Model ablations. KL balancing²⁷ substantially accelerates learning. Free bits^{28,65} avoids overfitting in simple environments. Symlog encoding and predictions for proprioceptive observations speeds up learning. Adjusting the KL scale over the course of training within a reasonable range to target a fixed KL value is a performant but more complicated alternative to free bits.

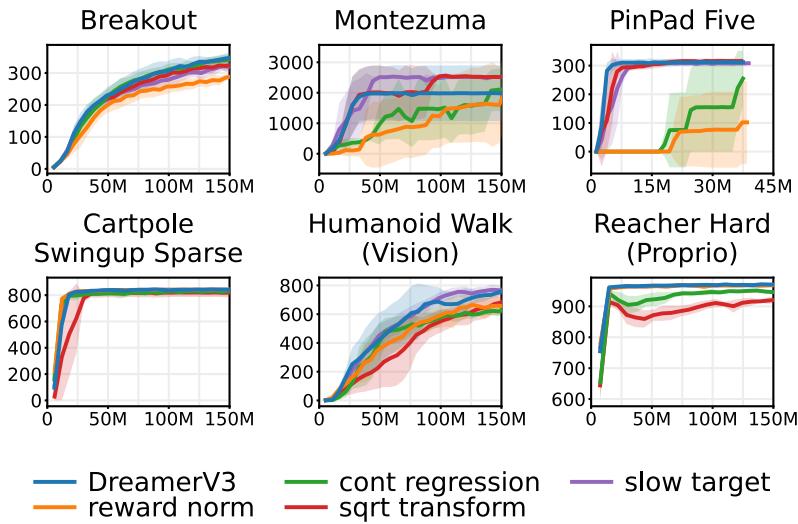


Figure D.2: Critic ablations. The symlog predictions for rewards and values in DreamerV3 outperform non-stationary reward normalization. Discrete regression also contributes significantly³⁴. Symlog transformation slightly outperforms the more complex asymmetric square root transformation of R2D2²¹. Using the slow critic for computing targets offers no benefit over using the fast critic and regularizing it towards its own EMA.

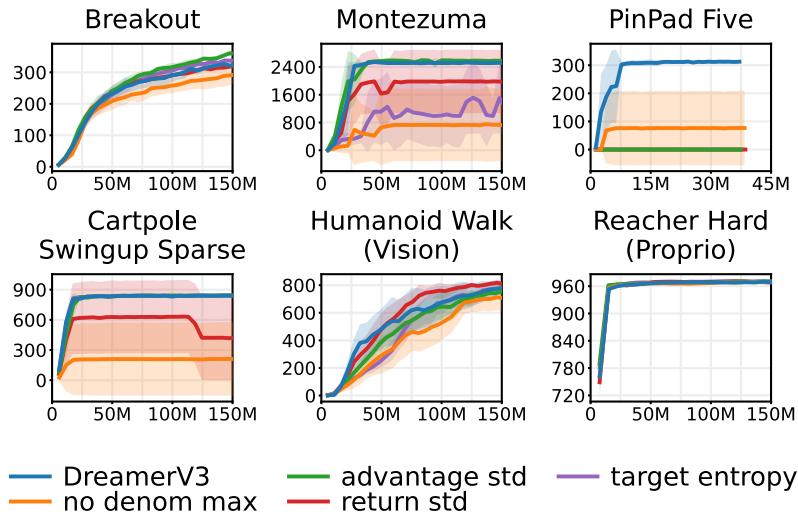


Figure D.3: Actor ablations. The strength of the actor entropy regularizer is important especially under sparse rewards, where the right amount of stochasticity is needed for exploration. The denominator maximum that prevents small returns (often noise) from being amplified is critical. The percentile return normalization of DreamerV3 outperforms normalization based on return std dev or advantage std dev on the sparse reward tasks⁷².

E Ablation Explanation

World Model Ablations

NoFreeBits Use KL balancing but no free bits, equivalent to setting the constants in Equation 4 from 1 to 0. This objective was used in DreamerV2²⁷.

NoKLBalance Use free bits but no KL balancing by setting $\beta_{\text{dyn}} = \beta_{\text{rep}} = 0.5$, which recovers the β -VAE objective⁷³. We found this value to perform well compared to nearby values. This objective was used in the first Dreamer agent⁶⁵.

NoObsSymlog This ablation removes the symlog encoding of inputs to the world model and also changes the symlog MSE loss in the decoder to a simple MSE loss. Because symlog encoding is only used for vector observations, this ablation is equivalent to DreamerV3 on purely image-based environments.

TargetKL Target a KL value of 3.5 nats on average over the replay buffer by increasing or decreasing the KL scale (both β_{pred} and β_{rep}) by 10% when the batch average of the KL value exceeds or falls below the tolerance of 10% around the target value, similar to the KL-penalty variant of PPO¹⁹. The KL scale is limited to the range $[10^{-3}, 1.0]$ for numerical stability.

Critic Ablations

RewardNorm Instead of normalizing rewards, normalize rewards by dividing them by a running standard deviation and clipping them beyond a magnitude of 10.

ContRegression Using MSE symlog predictions for the reward and value heads.

SqrtTransform Using two-hot discrete regression with the asymmetric square root transformation introduced by R2D2²¹ and used in MuZero³⁴.

SlowTarget Instead of using the fast critic for computing returns and training it towards the slow critic, use the slow critic for computing returns¹⁸.

Actor Ablations

NoDenomMax Normalize returns directly based on the range between percentiles 5 to 95 with a small epsilon in the denominator, instead of by the maximum of 1 and the percentile range. This way, not only large returns are scaled down but also small returns are scaled up.

AdvantageStd Advantage normalization as commonly used, for example in PPO¹⁹ and Muesli⁵⁶. However, scaling advantages without also scaling the entropy regularizer changes the trade-off between return and entropy in a way that depends on the scale of advantages, which in turn depends on how well the critic currently predicts the returns.

ReturnStd Instead of normalizing returns by the range between percentiles 5 to 95, normalize them by their standard deviation. When rewards are large but sparse, the standard deviation is small, scaling up the few large returns even further.

TargetEntropy Target a policy randomness of 40% on average across imagined states by increasing or decreasing the entropy scale η by 10% when the batch average of the randomness falls below or exceeds the tolerance of 10% around the target value. The entropy scale is limited to the range $[10^{-3}, 3 \cdot 10^{-2}]$. Policy randomness is the policy entropy mapped to range from 0% (most deterministic allowed by action distribution parameterization) to 100% (most uniform). Multiplicatively, instead of additively, adjusting the regularizer strength allows the scale to quickly move across orders of magnitude, outperforming the target entropy approach of SAC³⁸ in practice. Moreover, targeting a randomness value rather than an entropy value allows sharing the hyperparameter across domains with discrete and continuous actions.

F Minecraft Environment

Minecraft With 100M monthly active users, Minecraft is one of the most popular video games worldwide. Minecraft features a procedurally generated 3D world of different biomes, including plains, forests, jungles, mountains, deserts, taiga, snowy tundra, ice spikes, swamps, savannahs, badlands, beaches, stone shores, rivers, and oceans. The world consists of 1 meter sized blocks that the player can break and place. There are about 30 different creatures that the player can interact and fight with. From gathered resources, the player can use 379 recipes to craft new items and progress through the technology tree, all while ensuring safety and food supply to survive. There are many conceivable tasks in Minecraft and as a first step, the research community has focused on the salient task of obtaining a diamond, a rare item found deep underground and requires progressing through the technology tree.

Environment We built the Minecraft Diamond environment on top of MineRL to define a flat categorical action space and fix issues we discovered with the original environments via human play testing. For example, when breaking diamond ore, the item sometimes jumps into the inventory and sometimes needs to be collected from the ground. The original environment terminates episodes when breaking diamond ore so that many successful episodes end before collecting the item and thus without the reward. We remove this early termination condition and end episodes when the player dies or after 36000 steps, corresponding to 30 minutes at the control frequency of 20Hz. Another issue is that the jump action has to be held for longer than one control step to trigger a jump, which we solve by keeping the key pressed in the background for 200ms. We built the environment on top of MineRL v0.4.4¹⁵, which offers abstract crafting actions. The Minecraft version is 1.11.2.

Rewards We follow the same sparse reward structure of the MineRL competition environment that rewards 12 milestones leading up to the diamond, namely collecting the items log, plank, stick, crafting table, wooden pickaxe, cobblestone, stone pickaxe, iron ore, furnace, iron ingot, iron pickaxe, and diamond. The reward for each item is only given once per episode, and the agent has to learn autonomously that it needs to collect some of the items multiple times to achieve the next milestone. To make the return curves easy to interpret, we give a reward of +1 for each milestone instead of scaling rewards based on how valuable each item is. Additionally, we give a small reward of -0.01 for each lost heart and +0.01 for each restored heart, but we did not investigate whether this was helpful.

Inputs The sensory inputs include the $64 \times 64 \times 3$ RGB first-person camera image, the inventory counts as a vector with one entry for each of the game’s over 400 items, the vector of maximum inventory counts since episode begin to tell the agent which milestones it has already achieved, a one-hot vector indicating the equipped item, and scalar inputs for the health, hunger, and breath levels.

Actions The MineRL environment provides a dictionary action space and delegates choosing a simple action space to the user. We use a flat categorical action space with 25 actions for walking in four directions, turning the camera in four directions, attacking, jumping, placing items, crafting items near a placed crafting table, smelting items near a placed furnace, and equipping crafted tools. Looking up and down is restricted to the range -60 to $+60$ degrees. The action space is specific to the diamond task and does not allow the agent to craft all of the 379 recipes. For multi-task learning, a larger factorized action space as available in MineDojo⁶⁴ would likely be beneficial.

Break Speed Multiplier We follow Kanitscheider et al.¹⁷ in allowing the agent to break blocks in fewer time steps. Breaking blocks in Minecraft requires holding the same key pressed for sometimes hundreds of time steps. Briefly switching to a different key will reset this progress. Without an inductive bias, stochastic policies will almost never sample the same action this often during exploration under this parameterization. To circumvent this issue, we set the break speed multiplier option of MineRL to 100. In the future, inductive biases such as learning action repeat as part of the agent⁷⁴ could overcome this caveat.

G Minecraft Item Rates

Across 40 seeds trained for 100M steps, DreamerV3 obtained the maximum episode score—that includes collecting at least one diamond—50 times. It achieves this score the first time at 29.3M steps and as expected the frequency increases over time. Diamonds can also rarely be found by breaking village chests, but those episodes do not achieve the maximum score and thus are not included in this statistic. A total of 24 out of 40 seeds achieve the maximum episode score at least once, and the most successful seed achieved the maximum score 6 times. Across all seeds, the median number of environment steps until collecting the first diamond is 74M, corresponding to 42 days of play time at 20 Hz.

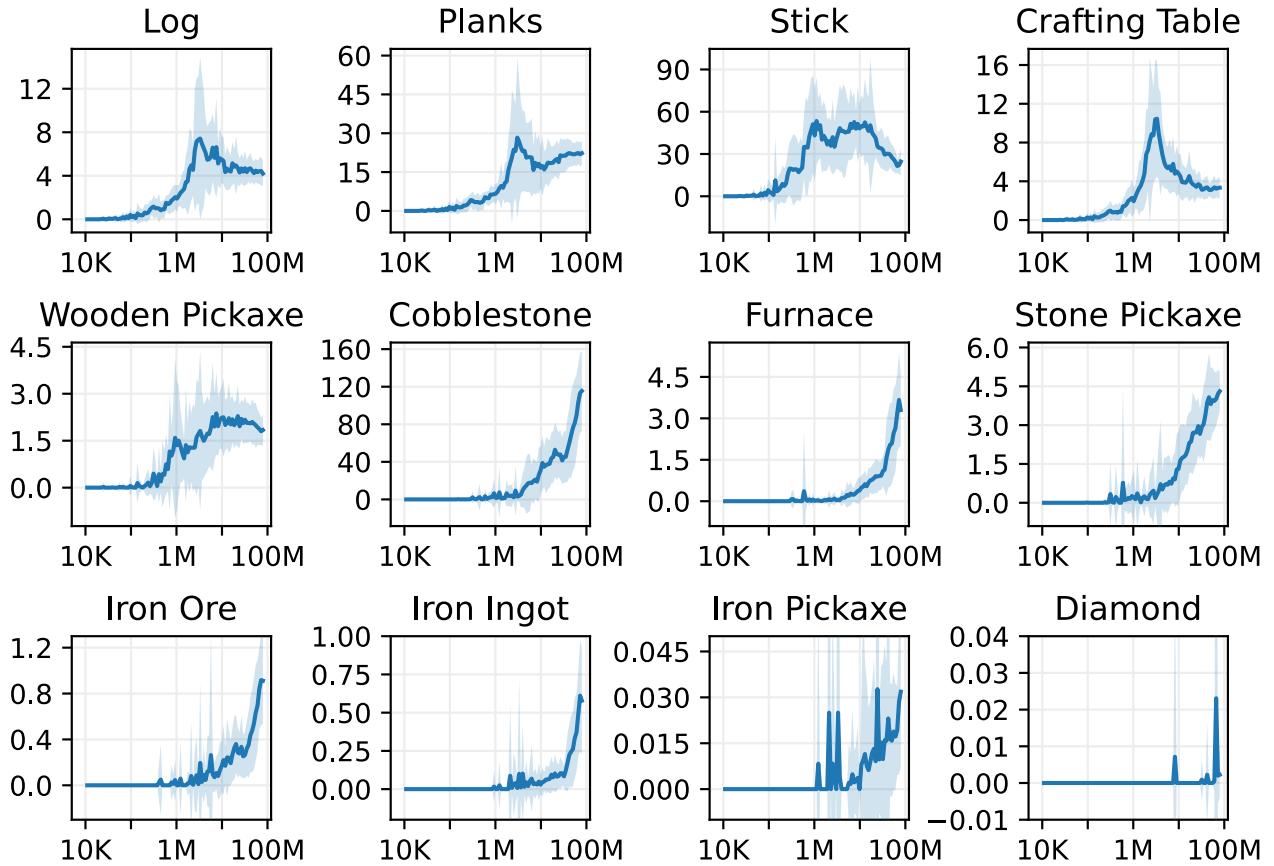


Figure G.1: Minecraft episode counts of rewarded items. Despite receiving only one sparse reward per item within the same episode, the agent learns that some items require multiple times to unlock later milestones. Later during training, the agent becomes more efficient and creates fewer additional items. Across all 40 seeds, DreamerV3 discovers a total of 116 unique items in Minecraft.

H Minecraft Video Predictions

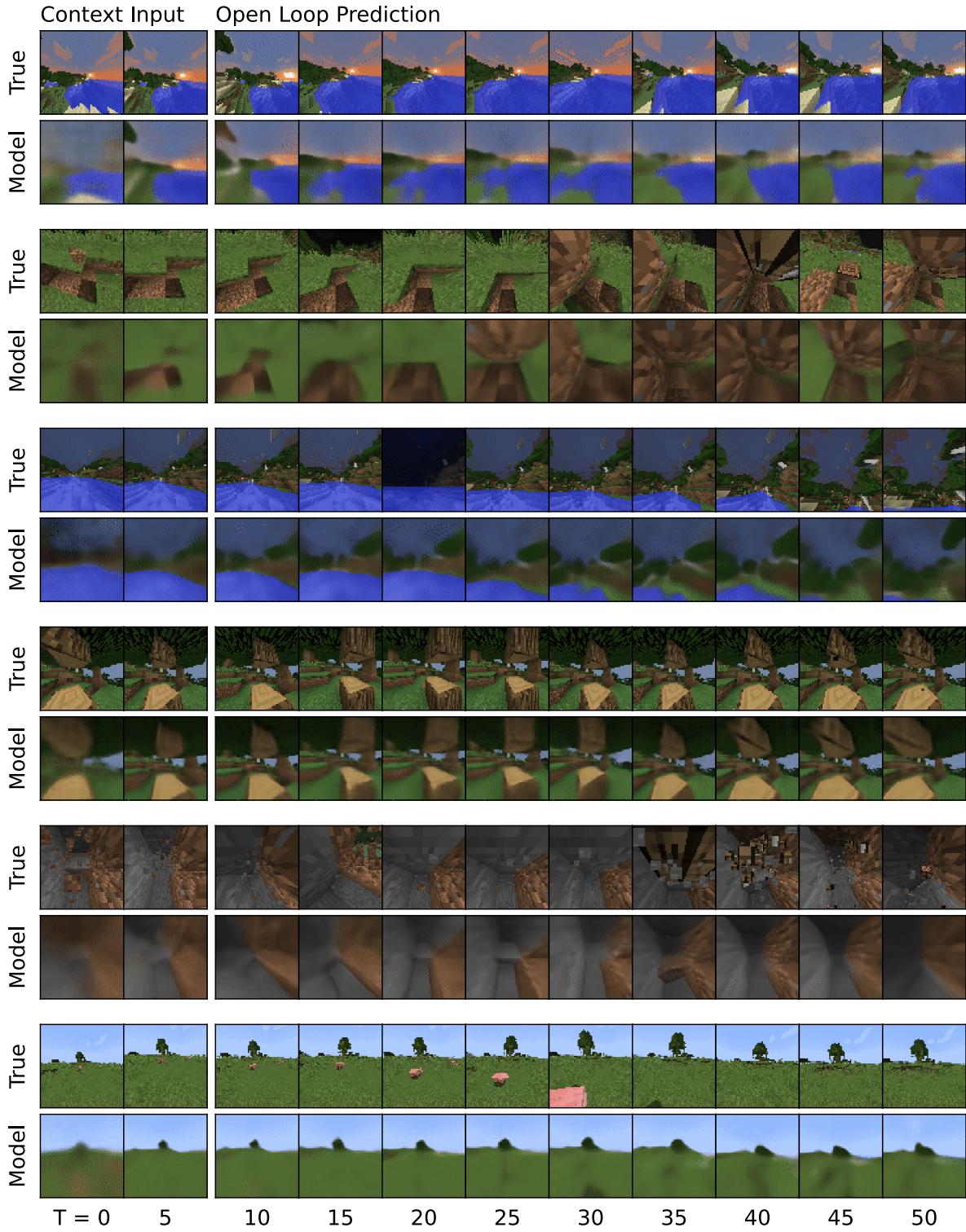


Figure H.1: Multi-step predictions on Minecraft. The model receives the first 5 frames as context input and the predicts 45 steps into the future given the action sequence and without access to intermediate images.

I DMLab Curves

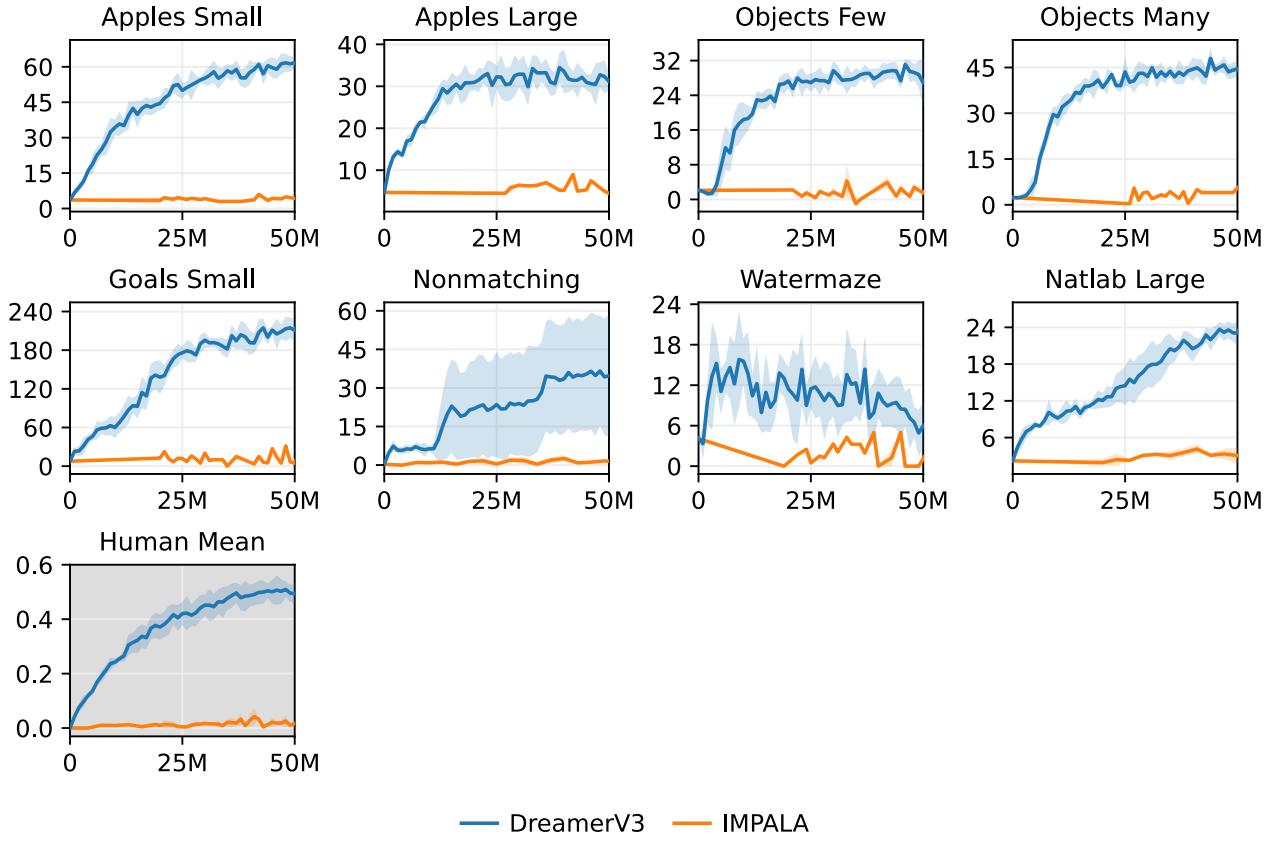


Figure I.1: DMLab scores with a budget of 50M frames. Separate agents were trained for each task, corresponding to the IMPALA Experts method in Espeholt et al.⁶⁰. Data efficiency is not the goal of IMPALA and it might be possible to tune it for improved data efficiency. Longer training curves and asymptotic performance of IMPALA are included in Appendix K.

J DMLab Scores

Task	Random	Human	IMPALA	DreamerV3	IMPALA
Environment Steps	—	—	50M	50M	10B
Goals Small	7.7	267.5	5.7	214.7	209.4
Goals Large	3.1	194.5	3.7	68.1	83.1
Apples Small	3.6	74.5	3.7	61.3	57.8
Apples Large	4.7	65.7	5.0	32.3	37.0
Deferred Effects	8.5	85.7	11.4	34.5	15.6
Keys Doors Puzzle	4.1	53.8	5.1	27.6	28.0
Nonmatching	0.3	65.9	1.8	34.3	7.3
Natlab Large	2.2	36.9	2.4	23.1	34.7
Normalized Mean	0.0%	100.0%	1.1%	54.2%	51.3%

Table J.1: DMLab scores. DreamerV3 achieves a human-normalized mean score of 54.2% that exceeds IMPALA at 51.3% while using 200 times fewer environment steps.

K DMLab Data Efficiency

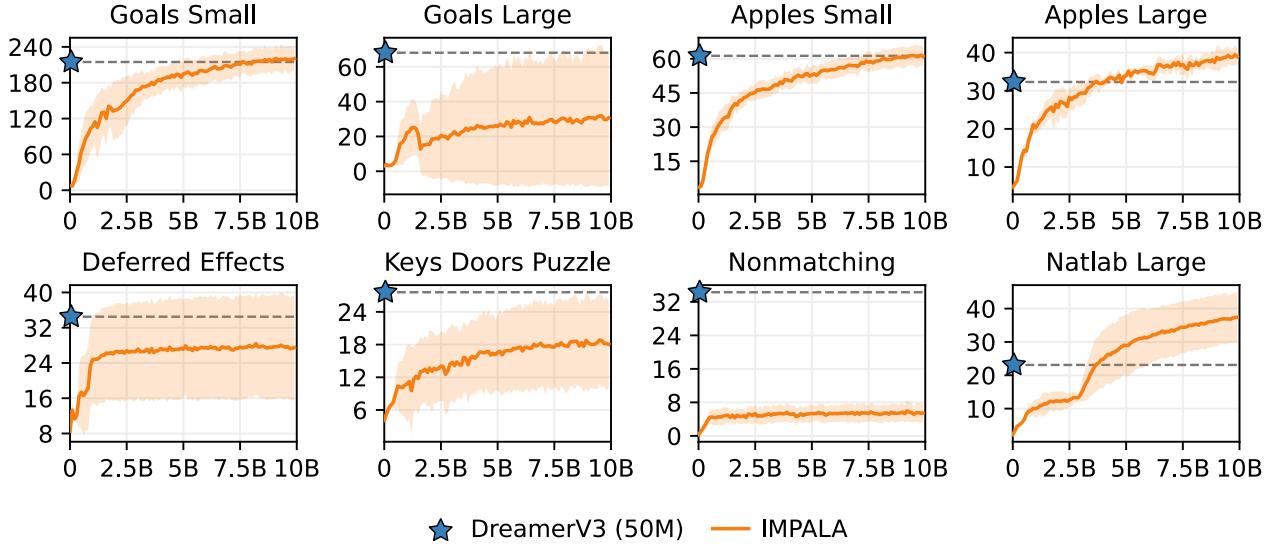


Figure K.1: IMPALA training curves on DMLab for 10 billion frames compared to DreamerV3 score. DreamerV3 uses $100\times$ fewer frames, which is almost at the left edge of the plot, as shown by the markers. Note that data efficiency was not the goal of IMPALA. Instead, it serves as a valuable baseline for the performance achievable by top RL algorithms without data constraints.

Task	DreamerV3	IMPALA Steps	Ratio
Goals Small	214.7	8.0B	$80\times$
Goals Large	68.1	—	$>200\times$
Apples Small	61.3	9.7B	$97\times$
Apples Large	32.3	4.1B	$41\times$
Deferred Effects	34.5	—	$>200\times$
Keys Doors Puzzle	27.6	—	$>200\times$
Nonmatching	34.3	—	$>200\times$
Natlab Large	23.1	3.7B	$37\times$

Table K.1: Data-efficiency comparison of DreamerV3 and IMPALA. The columns shows the score of DreamerV3 after 50M frames, how many steps IMPALA takes to reach the same score, and the resulting data-efficiency gain of DreamerV3 over IMPALA. The nonmatching task is excluded because DreamerV3 outperforms the final score of IMPALA here. The average efficiency gain across tasks is over $131.87\times$

L BSuite Scores

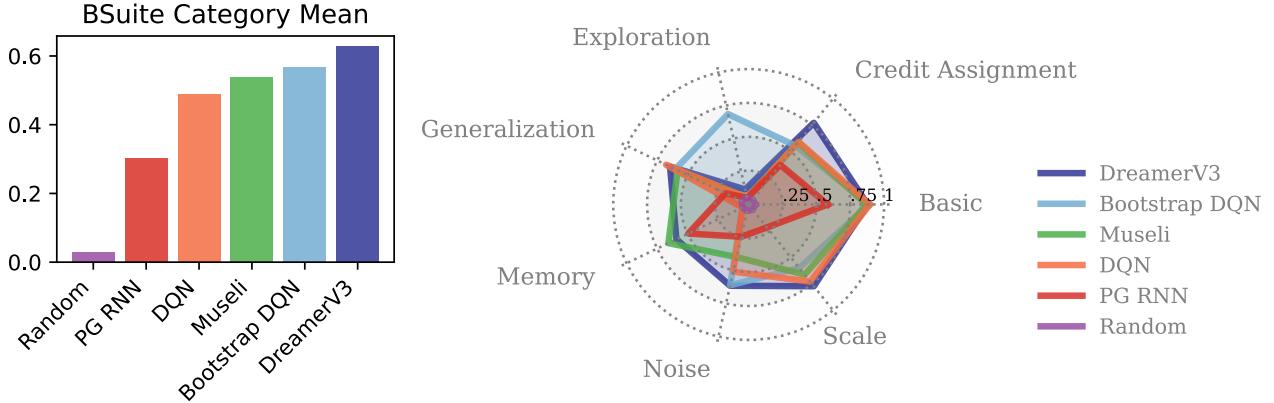


Figure L.1: BSuite scores averaged over categories and per category. The benchmark aggregates a total of 468 task configurations. The comparably high score of BootDQN is due to its ability to solve the exploration tasks in BSuite.

Task	Categories	Muesli	DreamerV3
bandit	basic	0.908	0.859
bandit_noise	noise	0.721	0.602
bandit_scale	scale	0.674	0.680
cartpole	basic, credit., generalization	0.906	0.853
cartpole_noise	noise, generalization	0.841	0.664
cartpole_scale	scale, generalization	0.701	0.779
cartpole_swingup	exploration, generalization	0.000	0.000
catch	basic, credit assignment	0.955	0.970
catch_noise	noise, credit assignment	0.464	0.571
catch_scale	scale, credit assignment	0.929	0.977
deep_sea	exploration	0.000	0.000
deep_sea_stochastic	exploration, noise	0.000	0.341
discounting_chain	credit assignment	0.453	0.290
memory_len	memory	0.609	0.478
memory_size	memory	0.706	0.706
mnist	basic, generalization	0.790	0.762
mnist_noise	noise, generalization	0.334	0.416
mnist_scale	scale, generalization	0.615	0.477
mountain_car	basic, generalization	0.797	0.949
mountain_car_noise	noise, generalization	0.441	0.590
mountain_car_scale	scale, generalization	0.400	0.948
umbrella_distract	credit assignment, noise	0.217	0.957
umbrella_length	credit assignment, noise	0.173	0.783
Category mean		0.537	0.627

Table L.1: BSuite scores per environment averaged over environment configurations.

M Crafter Scores

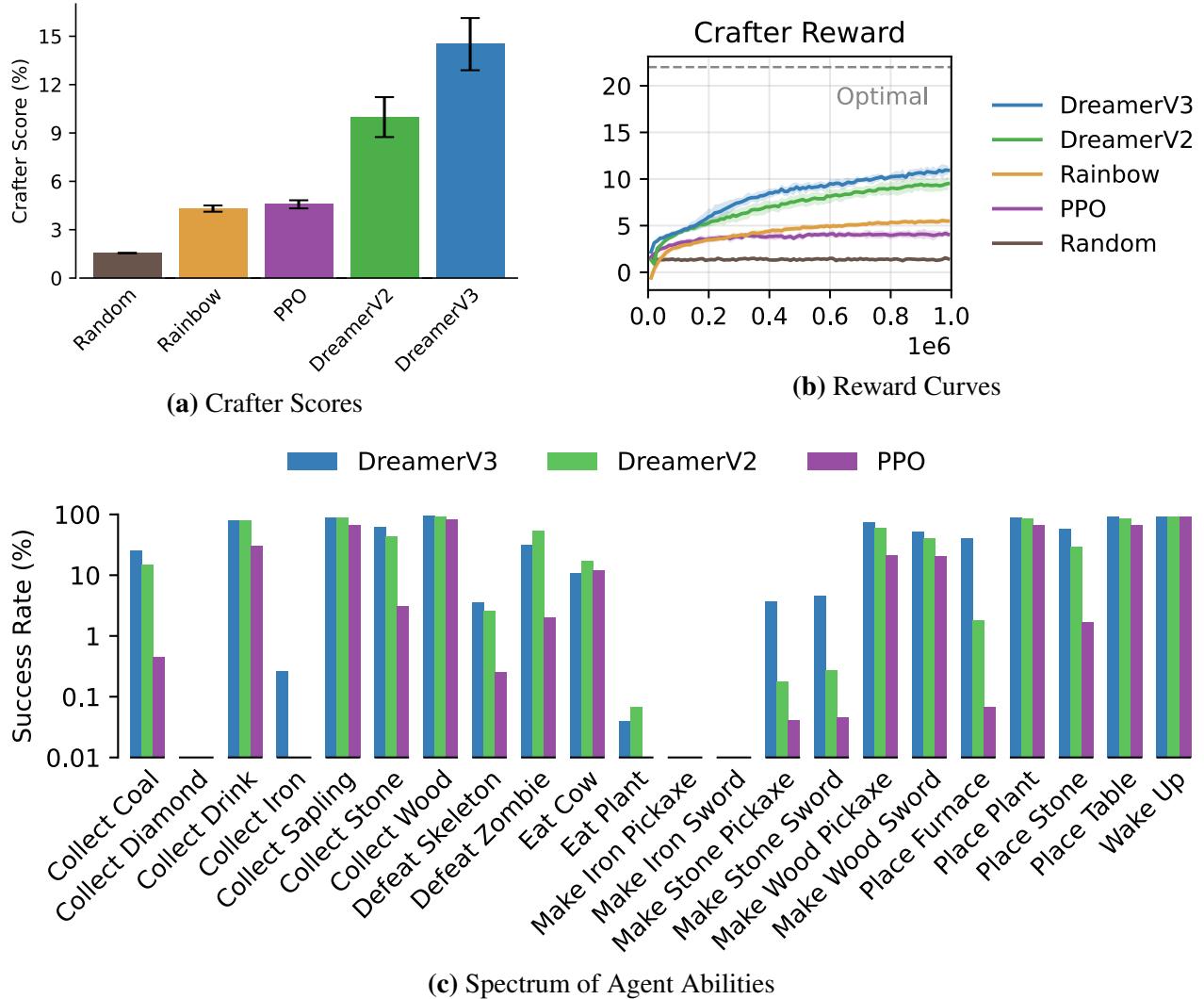


Figure M.1: Training curves, success rates, and aggregate scores on Crafter.

Method	Score	Reward
Human Experts	$50.5 \pm 6.8\%$	14.3 ± 2.3
DreamerV3	$14.5 \pm 1.6\%$	11.7 ± 1.9
LSTM-SPCNN	$12.1 \pm 0.8\%$	—
OC-SA	$11.1 \pm 0.7\%$	—
DreamerV2	$10.0 \pm 1.2\%$	9.0 ± 1.7
PPO	$4.6 \pm 0.3\%$	4.2 ± 1.2
Rainbow	$4.3 \pm 0.2\%$	6.0 ± 1.3
Plan2Explore (Unsup)	$2.1 \pm 0.1\%$	2.1 ± 1.5
RND (Unsup)	$2.0 \pm 0.1\%$	0.7 ± 1.3
Random	$1.6 \pm 0.0\%$	2.1 ± 1.3

Table M.1: Crafter scores compared to previous algorithms and human performance.

N Proprioceptive Control Curves

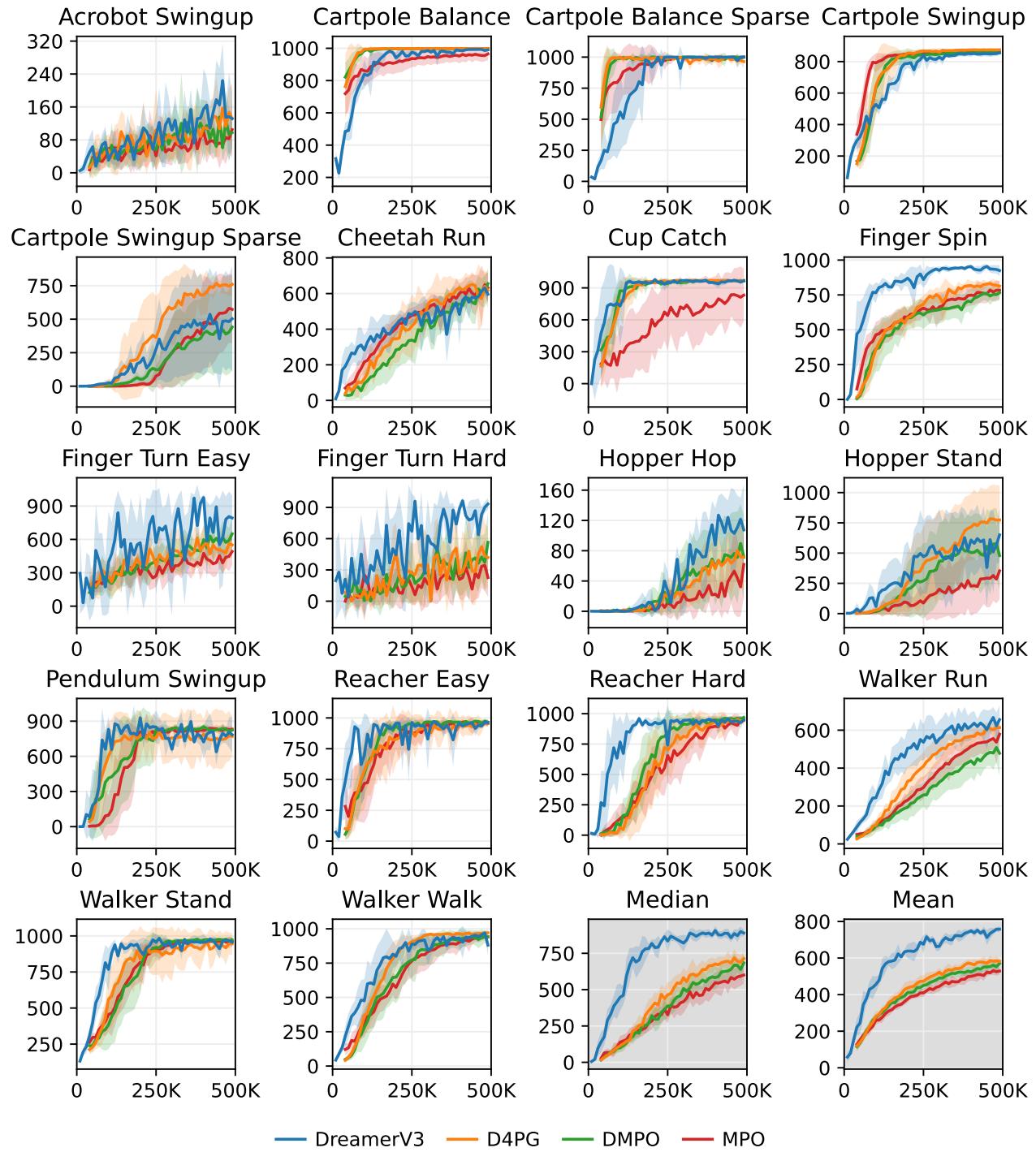


Figure N.1: DMC scores for proprioceptive inputs with a budget of 500K frames.

O Proprioceptive Control Scores

Task	DDPG	MPO	DMPO	D4PG	DreamerV3
Environment Steps	500K	500K	500K	500K	500K
Acrobot Swingup	92.7	80.6	98.5	125.5	154.5
Cartpole Balance	996.2	958.4	998.5	998.8	990.5
Cartpole Balance Sparse	985.3	998.0	994.0	979.6	996.8
Cartpole Swingup	863.9	857.7	857.8	874.6	850.0
Cartpole Swingup Sparse	627.5	519.9	404.0	739.6	468.1
Cheetah Run	576.9	612.3	581.6	623.5	575.9
Cup Catch	905.5	800.6	965.8	968.3	958.2
Finger Spin	753.6	766.9	744.3	818.4	937.2
Finger Turn Easy	462.2	430.4	593.8	524.5	745.4
Finger Turn Hard	286.3	250.8	384.5	379.2	841.0
Hopper Hop	24.6	37.5	71.5	67.5	111.0
Hopper Stand	388.1	279.3	519.5	755.4	573.2
Pendulum Swingup	748.3	829.8	829.5	756.0	766.0
Reacher Easy	921.8	954.4	965.1	941.5	947.1
Reacher Hard	944.2	914.1	956.8	932.0	936.2
Walker Run	530.0	539.5	462.9	593.1	632.7
Walker Stand	967.4	960.4	971.6	935.2	956.9
Walker Walk	948.7	924.9	933.1	965.1	935.7
Median	751.0	783.7	786.9	787.2	845.5
Mean	667.9	650.9	685.2	721.0	743.1

Table O.1: DMC scores for proprioceptive inputs at 500K frames.

P Visual Control Curves

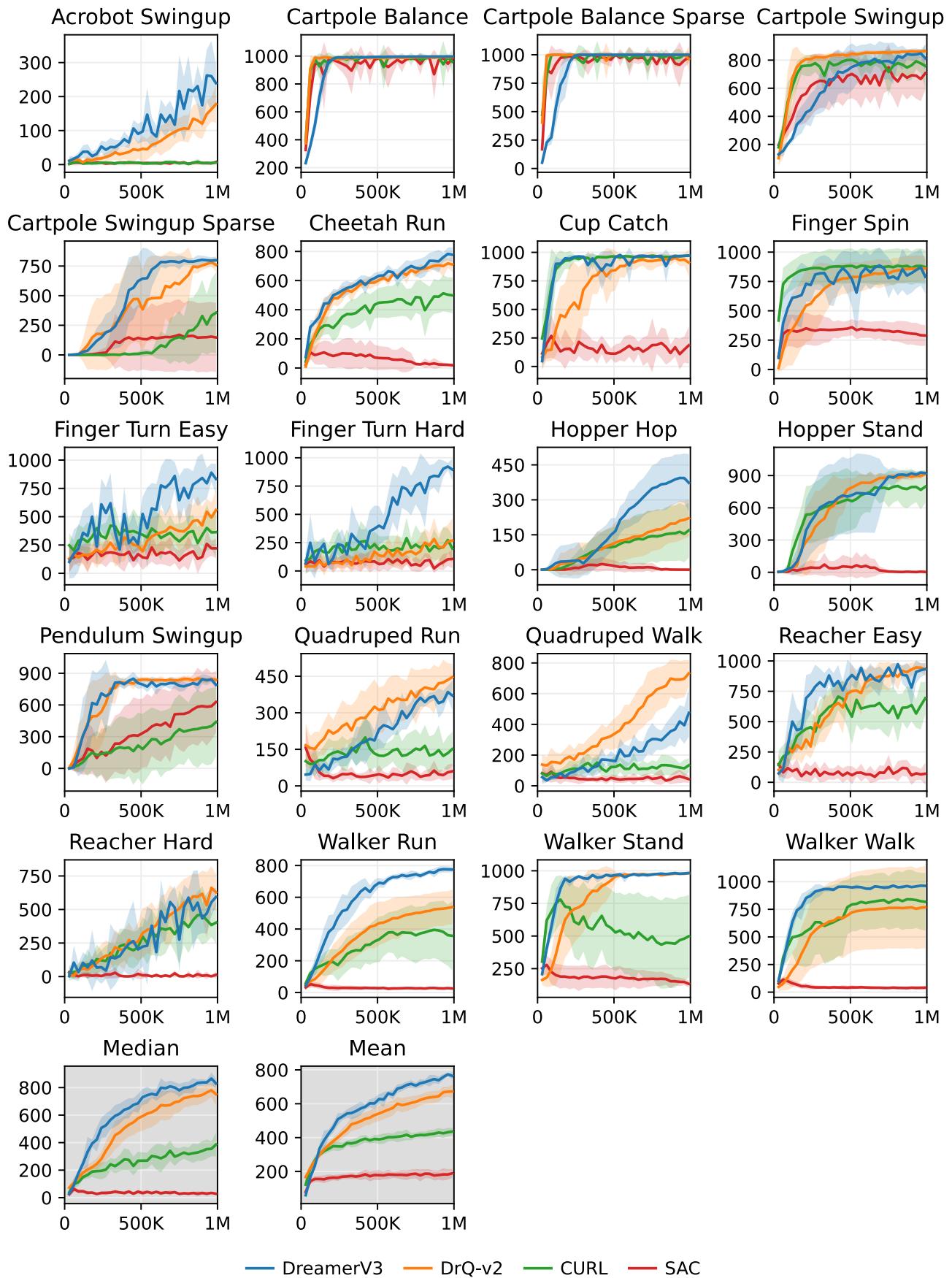


Figure P.1: DMC scores for image inputs with a budget of 1M frames.

Q Visual Control Scores

Task	SAC	CURL	DrQ-v2	DreamerV3
Environment Steps	1M	1M	1M	1M
Acrobot Swingup	5.1	5.1	128.4	210.0
Cartpole Balance	963.1	979.0	991.5	996.4
Cartpole Balance Sparse	950.8	981.0	996.2	1000.0
Cartpole Swingup	692.1	762.7	858.9	819.1
Cartpole Swingup Sparse	154.6	236.2	706.9	792.9
Cheetah Run	27.2	474.3	691.0	728.7
Cup Catch	163.9	965.5	931.8	957.1
Finger Spin	312.2	877.1	846.7	818.5
Finger Turn Easy	176.7	338.0	448.4	787.7
Finger Turn Hard	70.5	215.6	220.0	810.8
Hopper Hop	3.1	152.5	189.9	369.6
Hopper Stand	5.2	786.8	893.0	900.6
Pendulum Swingup	560.1	376.4	839.7	806.3
Quadruped Run	50.5	141.5	407.0	352.3
Quadruped Walk	49.7	123.7	660.3	352.6
Reacher Easy	86.5	609.3	910.2	898.9
Reacher Hard	9.1	400.2	572.9	499.2
Walker Run	26.9	376.2	517.1	757.8
Walker Stand	159.3	463.5	974.1	976.7
Walker Walk	38.9	828.8	762.9	955.8
Median	78.5	431.8	734.9	808.5
Mean	225.3	504.7	677.4	739.6

Table Q.1: DMC scores for visual inputs at 1M frames.

R Atari 100K Curves

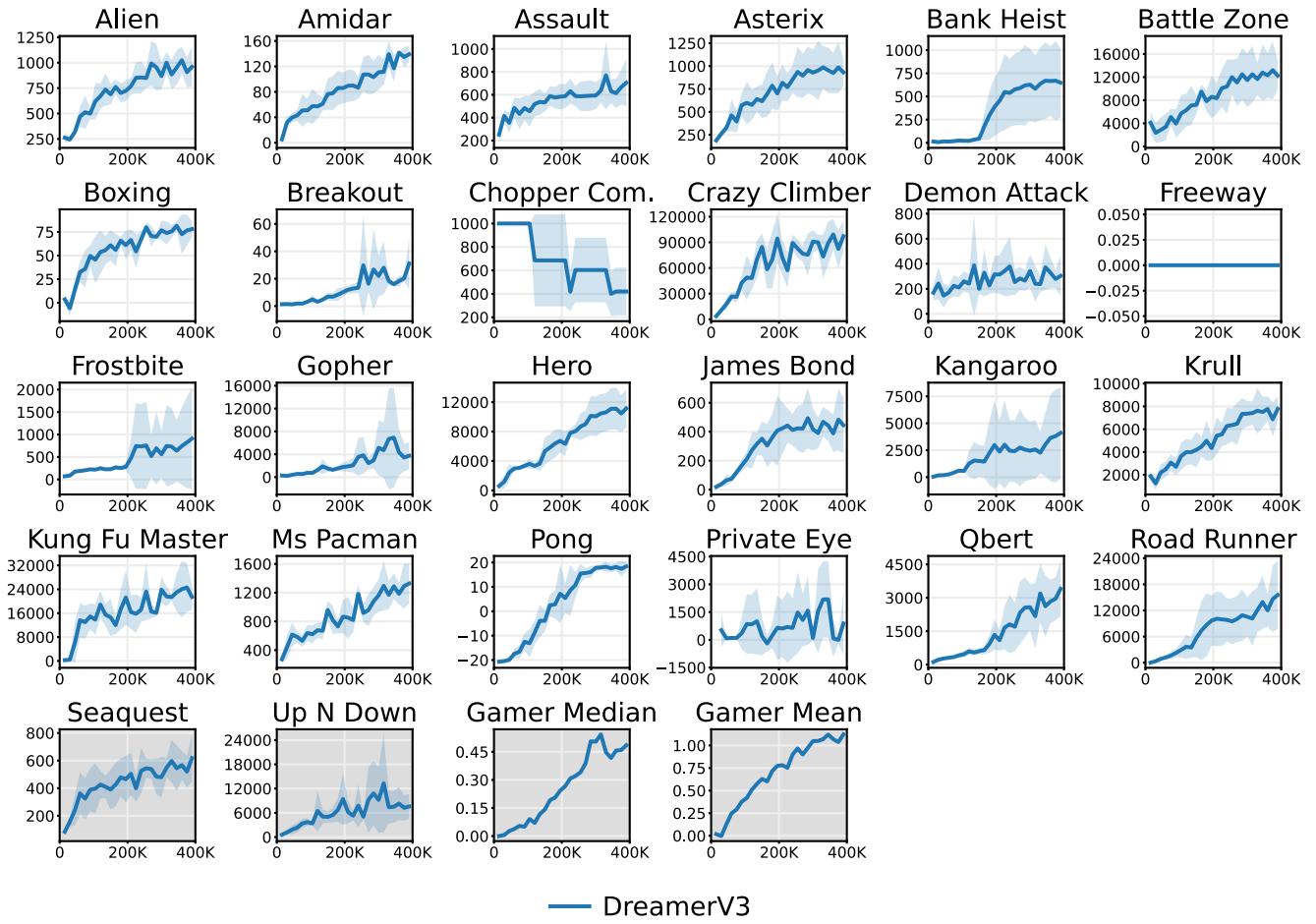


Figure R.1: Atari training curves with a budget of 400K frames, amounting to 100K policy steps.

S Atari 100K Scores

Task	Random	Human	SimPLe	CURL	SPR	IRIS	DreamerV3
Env Steps	—	—	—	400K	400K	400K	400K
Alien	228	7128	617	711	842	420	959
Amidar	6	1720	74	114	180	143	139
Assault	222	742	527	501	566	1524	706
Asterix	210	8503	1128	567	962	854	932
Bank Heist	14	753	34	65	345	53	649
Battle Zone	2360	37188	4031	8998	14834	13074	12250
Boxing	0	12	8	1	36	70	78
Breakout	2	30	16	3	20	84	31
Chopper Com.	811	7388	979	784	946	1565	420
Crazy Climber	10780	35829	62584	9154	36700	59324	97190
Demon Attack	152	1971	208	646	518	2034	303
Freeway	0	30	17	28	19	31	0
Frostbite	65	4335	237	1226	1171	259	909
Gopher	258	2412	597	401	661	2236	3730
Hero	1027	30826	2657	4988	5859	7037	11161
James Bond	29	303	100	331	366	463	445
Kangaroo	52	3035	51	740	3617	838	4098
Krull	1598	2666	2205	3049	3682	6616	7782
Kung Fu Master	258	22736	14862	8156	14783	21760	21420
Ms Pacman	307	6952	1480	1064	1318	999	1327
Pong	-21	15	13	-18	-5	15	18
Private Eye	25	69571	35	82	86	100	882
Qbert	164	13455	1289	727	866	746	3405
Road Runner	12	7845	5641	5006	12213	9615	15565
Seaquest	68	42055	683	315	558	661	618
Human Median	0%	100%	13%	9%	40%	29%	49%
Human Mean	0%	100%	33%	26%	62%	105%	112%

Table S.1: Atari scores at 400K environment frames, corresponding to 100k agent frames.

T Atari 100K Settings

Setting	SimPLe	EfficientZero	SPR	IRIS	TWM	DreamerV3
Mean score	33	190	70	104	95	112
Median score	13	109	41	29	50	49
GPU days	10	1.2	0.2	7	0.8	0.5
Online planning	—	X	—	—	—	—
Data augmentation	—	—	X	—	—	—
Non-uniform replay	—	X	X	—	X	—
Separate hparams	—	—	—	X	—	—
Increased resolution	—	X	X	—	—	—
Uses life information	—	X	X	X	X	—
Uses early resets	—	X	—	X	—	—
Separate eval episodes	X	X	X	X	X	—

Table T.1: Algorithmic components, algorithmic components, and environment settings for the Atari 100k benchmark. GPU days are converted to V100 days by assuming P100 is twice as slow and A100 is twice as fast. EfficientZero achieves the highest scores but at the cost of complexity and changing the environment configuration. IRIS uses a separate exploration strength for Freeway.

U Atari 200M Curves

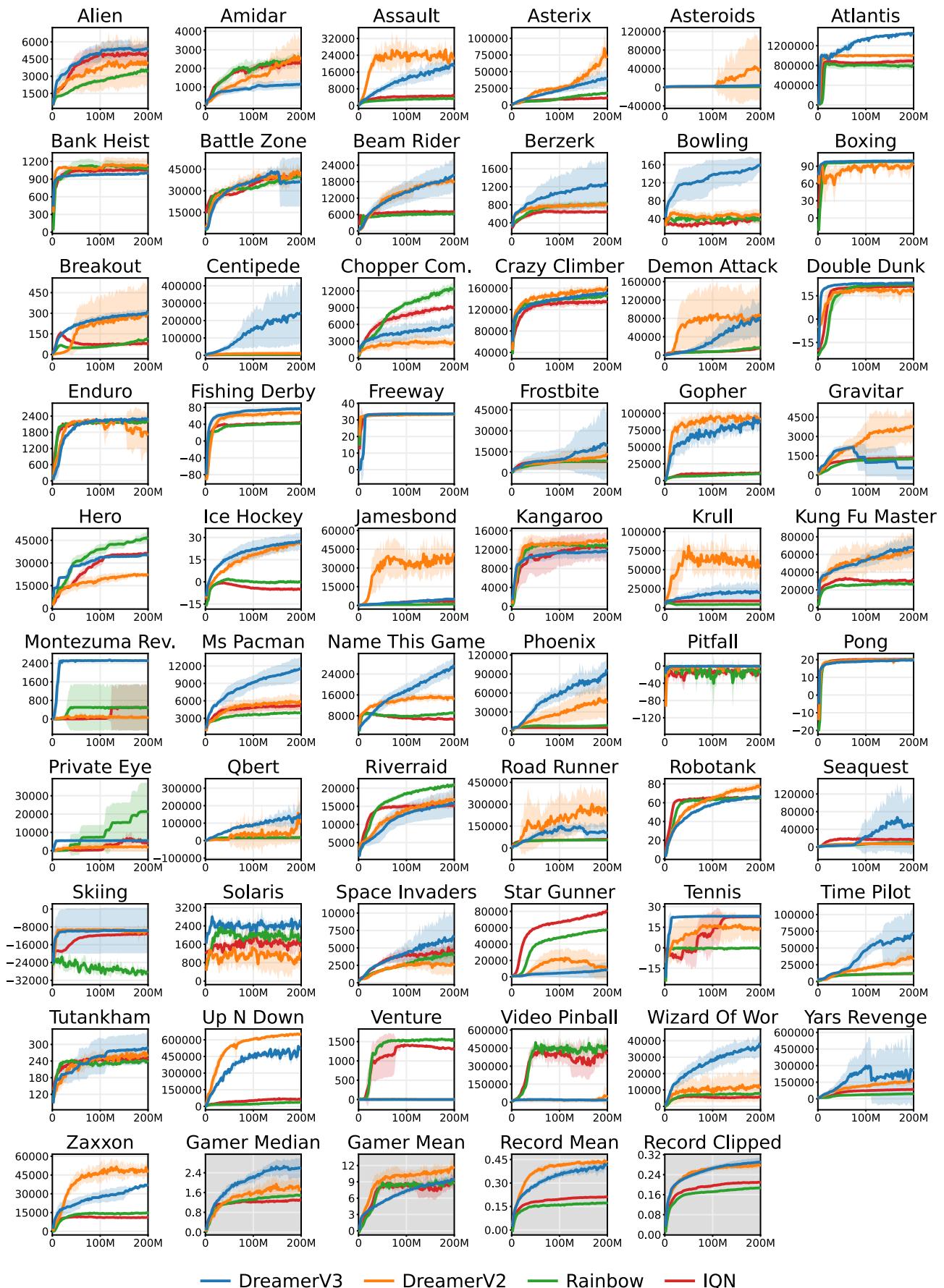


Figure U.1: Atari training curves with a budget of 200M frames.

V Atari 200M Scores

Task	Random	Gamer	Record	IQN	Rainbow	DreamerV2	DreamerV3
Environment Steps	—	—	—	200M	200M	200M	200M
Alien	229	7128	251916	4926	3488	4083	5404
Amidar	6	1720	104159	2315	2530	2531	1141
Assault	222	742	8647	4639	3302	23504	18876
Asterix	210	8503	1000000	10293	17534	75598	39643
Asteroids	719	47389	10506650	1578	1468	40120	3829
Atlantis	12850	29028	10604840	890427	790051	996300	1439392
Bank Heist	14	753	82058	1056	1079	1127	1000
Battle Zone	2360	37188	801000	40784	40194	42210	35912
Beam Rider	364	16926	999999	7042	6232	18157	20051
Berzerk	124	2630	1057940	644	822	807	1245
Bowling	23	161	300	39	39	49	158
Boxing	0	12	100	98	98	91	99
Breakout	2	30	864	80	109	293	300
Centipede	2091	12017	1301709	3735	6538	11816	240525
Chopper Com.	811	7388	999999	9106	12388	2647	5853
Crazy Climber	10780	35829	219900	134761	145889	158278	149986
Demon Attack	152	1971	1556345	14558	16049	84408	77084
Double Dunk	-19	-16	22	21	22	18	23
Enduro	0	860	9500	2207	2181	1775	2289
Fishing Derby	-92	-39	71	44	42	66	77
Freeway	0	30	38	34	34	33	34
Frostbite	65	4335	454830	7866	8351	12091	19991
Gopher	258	2412	355040	11469	10272	91249	86759
Gravitar	173	3351	162850	1332	1263	3769	560
Hero	1027	30826	1000000	36216	46417	22003	35359
Ice Hockey	-11	1	36	-5	-0	26	27
Jamesbond	7	303	45550	3294	1035	38514	5123
Kangaroo	52	3035	1424600	12562	12812	13899	11597
Krull	1598	2666	104100	8771	4238	55217	20123
Kung Fu Master	258	22736	1000000	30431	26489	63614	68166
Montezuma Rev.	0	4753	1219200	495	487	79	2512
Ms Pacman	307	6952	290090	5153	3913	5693	11397
Name This Game	2292	8049	25220	6718	9073	14879	26439
Phoenix	761	7243	4014440	5098	8355	47024	90037
Pitfall	-229	6464	114000	-17	-12	-2	-0
Pong	-21	15	21	20	20	20	20
Private Eye	25	69571	101800	4286	21341	2073	5538
Qbert	164	13455	2400000	16464	17625	114114	137224
Riverraid	1338	17118	1000000	15250	20766	16791	15758
Road Runner	12	7845	2038100	58813	54704	249230	78005
Robotank	2	12	76	66	65	77	66
Seaquest	68	42055	999999	16819	9966	7341	49547
Skiing	-17098	-4337	-3272	-11156	-28322	-9813	-9623
Solaris	1236	12327	111420	1659	1829	1016	2453
Space Invaders	148	1669	621535	4562	4112	2615	6269
Star Gunner	664	10250	77400	79330	57289	10908	8423
Tennis	-24	-8	21	23	-0	14	23
Time Pilot	3568	5229	65300	11619	12041	36059	68980
Tutankham	11	168	5384	248	240	265	285
Up N Down	533	11693	82840	63430	35440	651439	502213
Venture	0	1188	38900	1314	1539	0	0
Video Pinball	16257	17668	89218328	420509	450968	46282	17416
Wizard Of Wor	564	4756	395300	5595	7869	12396	36537
Yars Revenge	3093	54577	15000105	83990	45059	157285	235402
Zaxxon	32	9173	83700	11047	14606	48620	36626
Gamer Median	0%	100%	3716%	126%	147%	219%	302%
Gamer Mean	0%	100%	126759%	890%	888%	1149%	920%
Record Mean	0%	12%	100%	21%	17%	44%	41%
Clip Record Mean	0%	12%	100%	21%	17%	28%	29%

Table V.1: Atari scores at 200M frames.

W Hyperparameters

Name	Symbol	Value
General		
Replay capacity (FIFO)	—	10^6
Batch size	B	16
Batch length	T	64
Activation	—	LayerNorm + SiLU
World Model		
Number of latents	—	32
Classes per latent	—	32
Reconstruction loss scale	β_{pred}	1.0
Dynamics loss scale	β_{dyn}	0.5
Representation loss scale	β_{rep}	0.1
Learning rate	—	10^{-4}
Adam epsilon	ϵ	10^{-8}
Gradient clipping	—	1000
Actor Critic		
Imagination horizon	H	15
Discount horizon	$1/(1 - \gamma)$	333
Return lambda	λ	0.95
Critic EMA decay	—	0.98
Critic EMA regularizer	—	1
Return normalization scale	S	$\text{Per}(R, 95) - \text{Per}(R, 5)$
Return normalization limit	L	1
Return normalization decay	—	0.99
Actor entropy scale	η	$3 \cdot 10^{-4}$
Learning rate	—	$3 \cdot 10^{-5}$
Adam epsilon	ϵ	10^{-5}
Gradient clipping	—	100

Table W.1: DreamerV3 hyper parameters. The same values are used across all benchmark suites, including proprioceptive and visual inputs, continuous and discrete actions, and 2D and 3D domains. We do not use any hyperparameter annealing, weight decay, or dropout.