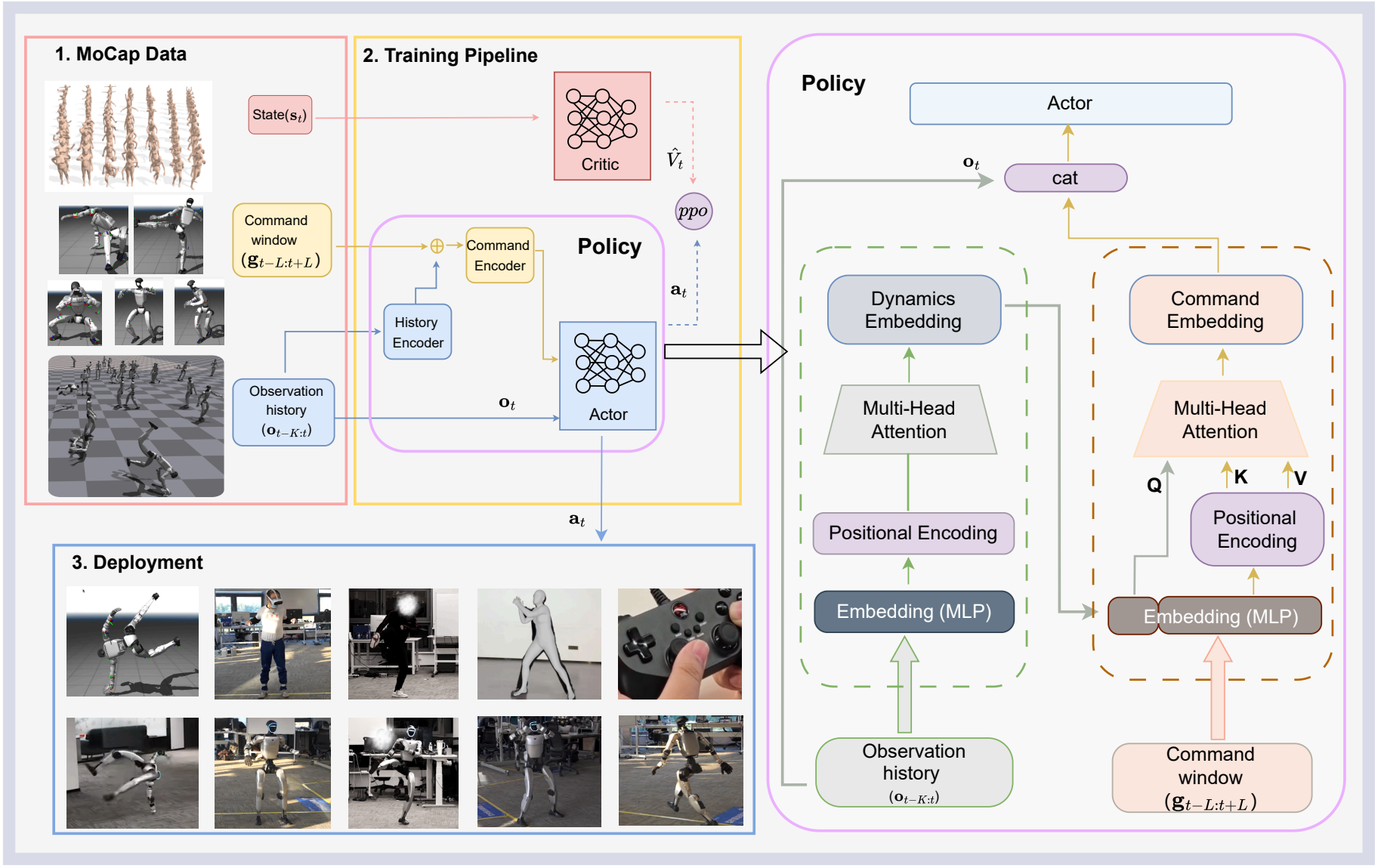
1. MoCap Data
State($\mathbf{s}_t$)
Command window ($\mathbf{g}_{t-L:t+L}$)
Observation history ($\mathbf{o}_{t-K:t}$)
2. Training Pipeline
Critic
$\hat{V}_t$
ppo
Command Encoder
Policy
History Encoder
$\mathbf{a}_t$
$\mathbf{o}_t$
Actor
$\mathbf{a}_t$
3. Deployment
Policy
Actor
$\mathbf{o}_t$
cat
Dynamics Embedding
Multi-Head Attention
Positional Encoding
Embedding (MLP)
Observation history ($\mathbf{o}_{t-K:t}$)
Command Embedding
Multi-Head Attention
Q
K
V
Positional Encoding
Embedding (MLP)
Command window ($\mathbf{g}_{t-L:t+L}$)