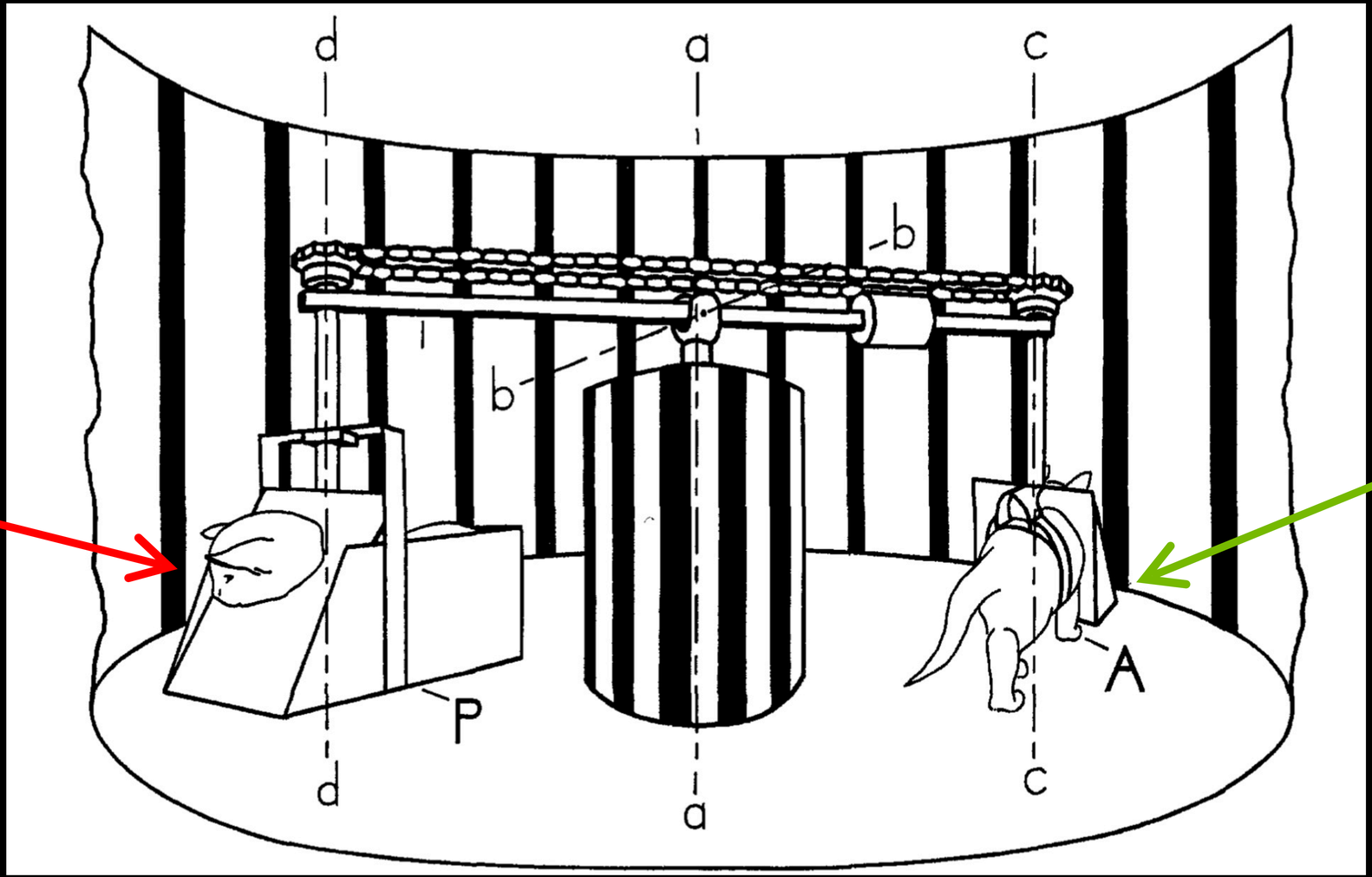
# A Tale of Two Kittens

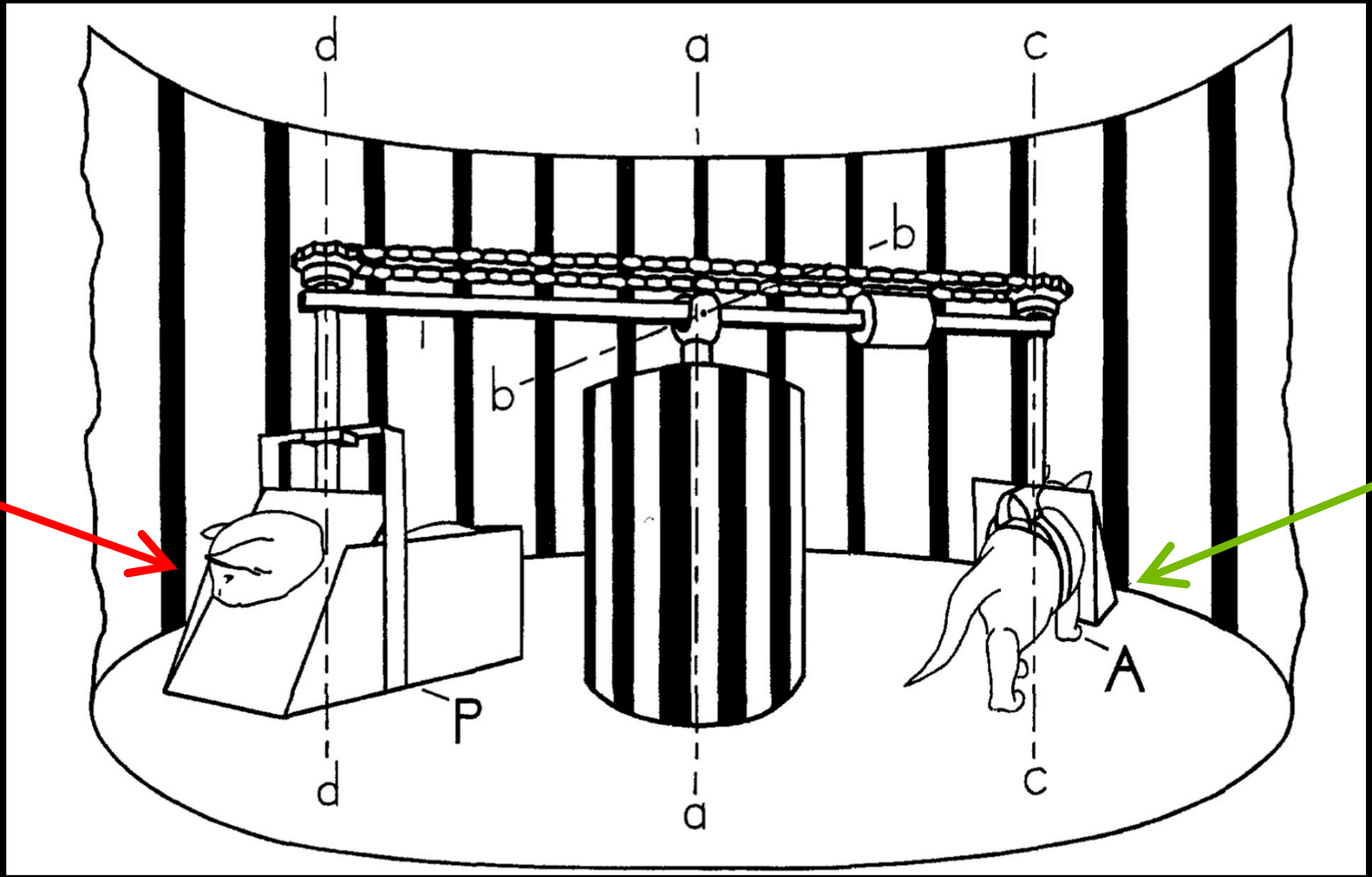
Passive Kitten




Active Kitten

Held & Hein, 1963.

ChatGPT

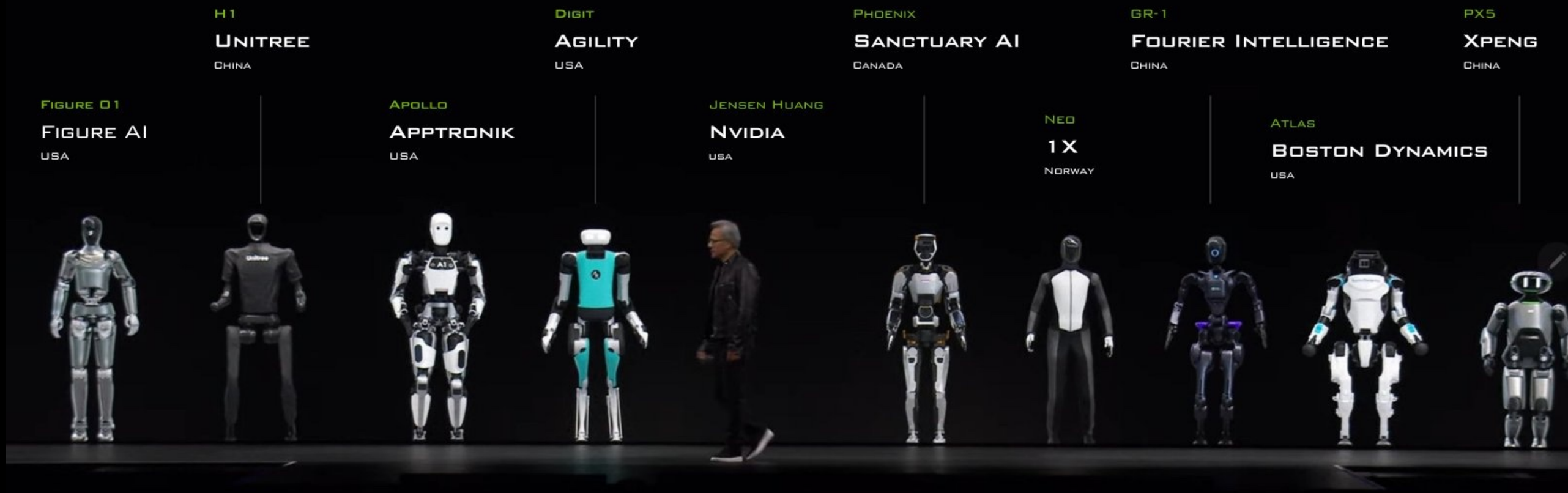



Embodied AI

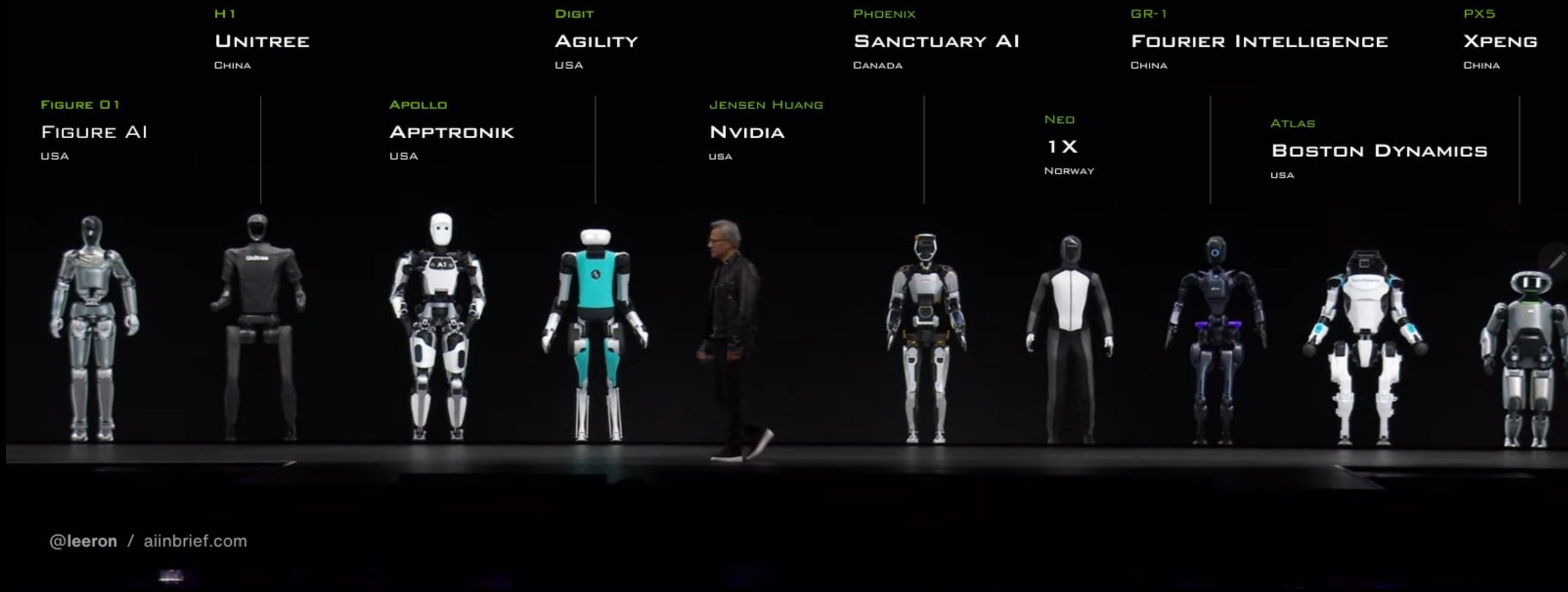
Held & Hein, 1963.

# Project GR00T

Dr. Jim Fan, NVIDIA Research




@leeron / aiinbrief.com

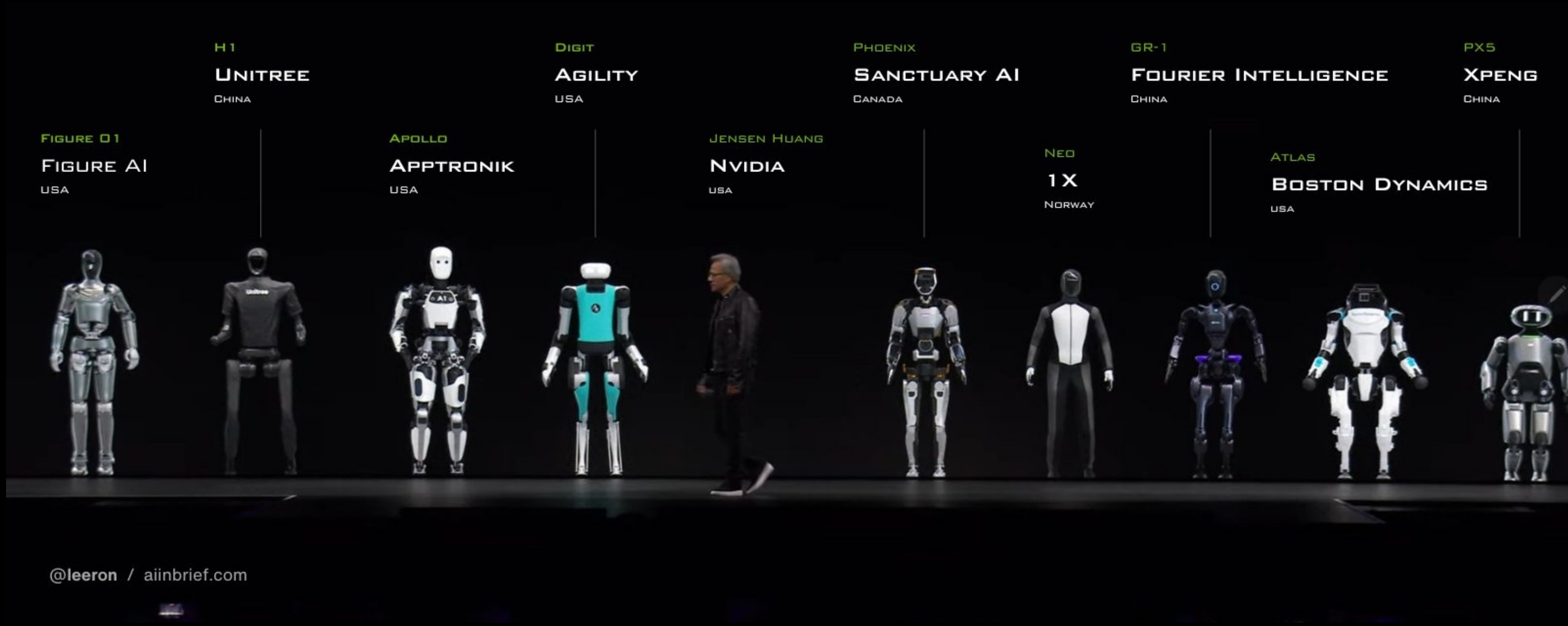



# Why Humanoid?

BREAD

ADULT
stryker

BOAR'S HEAD
EST.
1905
PREMIUM MEATS & CHEESES
Mustard
WE ARE
OPEN
Order your Sandwiches or by the pound Meats & Cheeses for pickup
Boar's Head


H1
Unitree
China
Digit
Agility
USA
Phoenix
Sanctuary AI
Canada
GR-1
Fourier Intelligence
China
PX5
Xpeng
China
Figure 01
Figure AI
USA
Apollo
Apptronik
USA
Jensen Huang
Nvidia
USA
Neo
1X
Norway
Atlas
Boston Dynamics
USA
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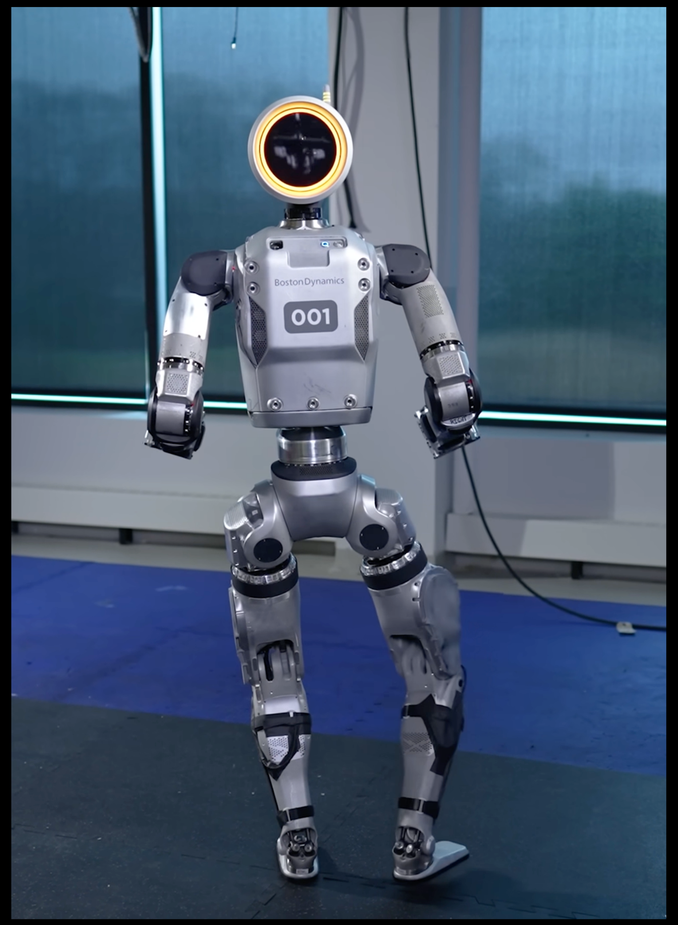
# Why Now?

Tesla Optimus




Boston Dynamics e-Atlas

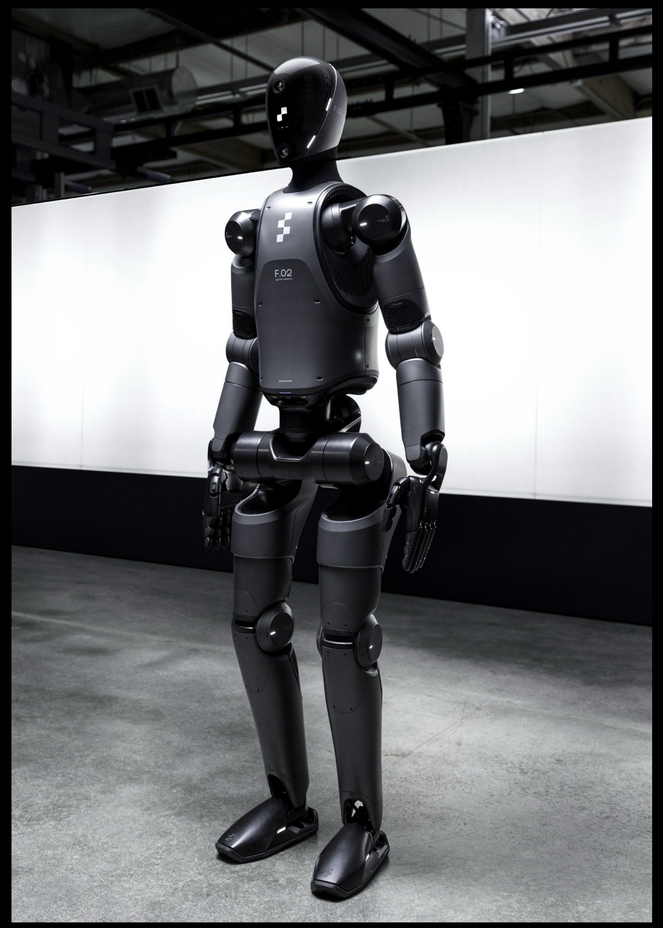
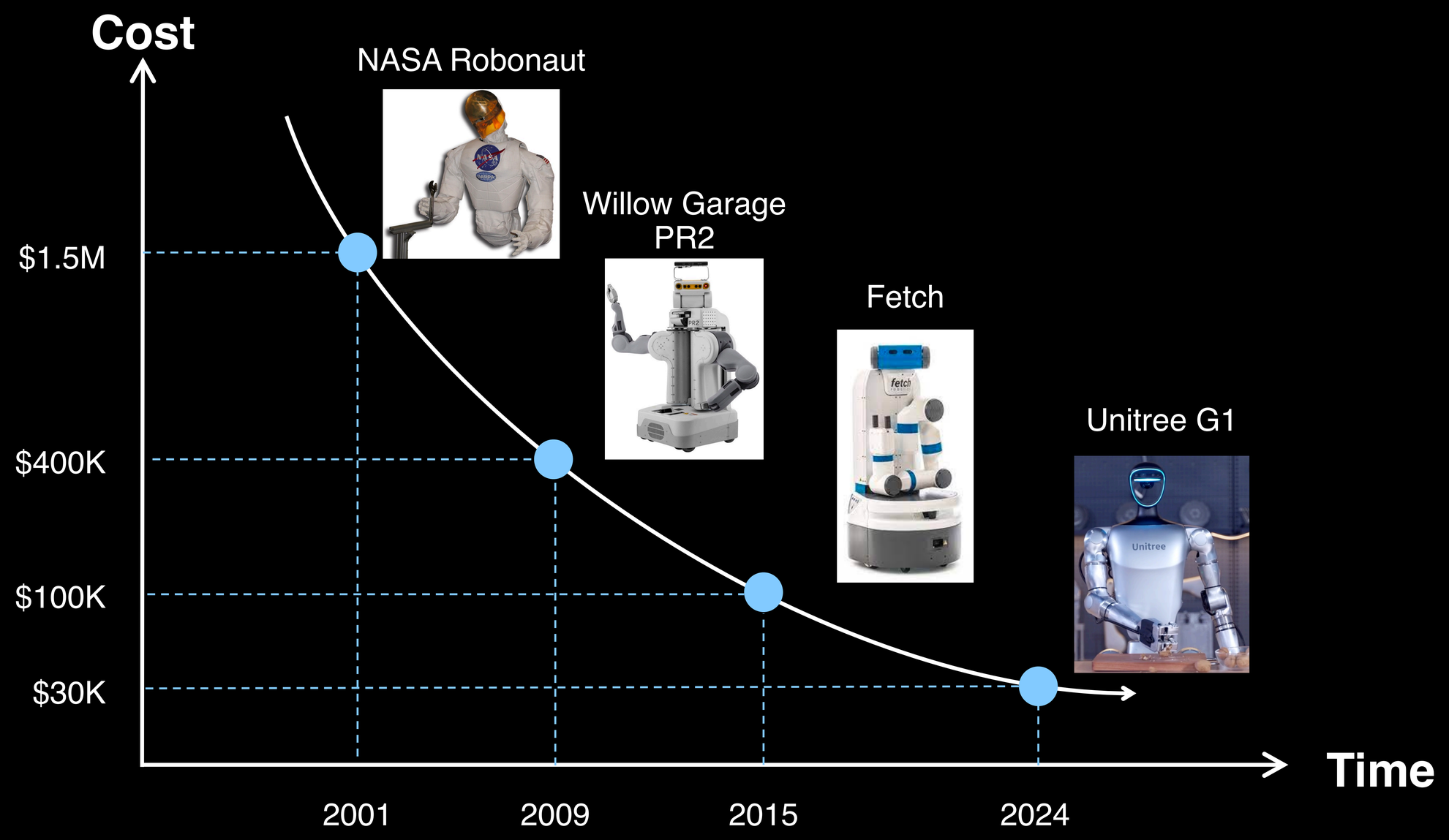
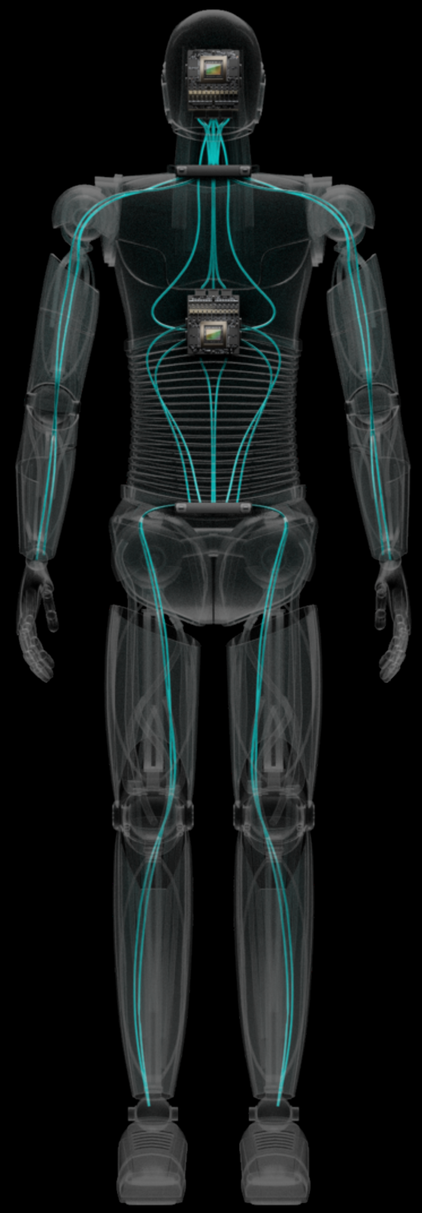


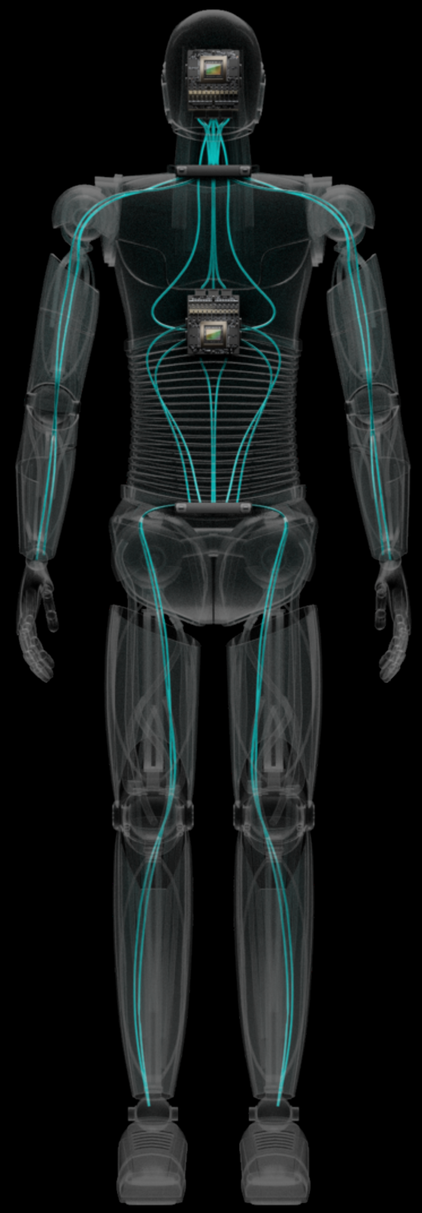

Figure F.02


Cost
NASA Robonaut
Willow Garage
PR2
Fetch
Unitree G1
$1.5M
$400K
$100K
$30K
Time
2001
2009
2015
2024



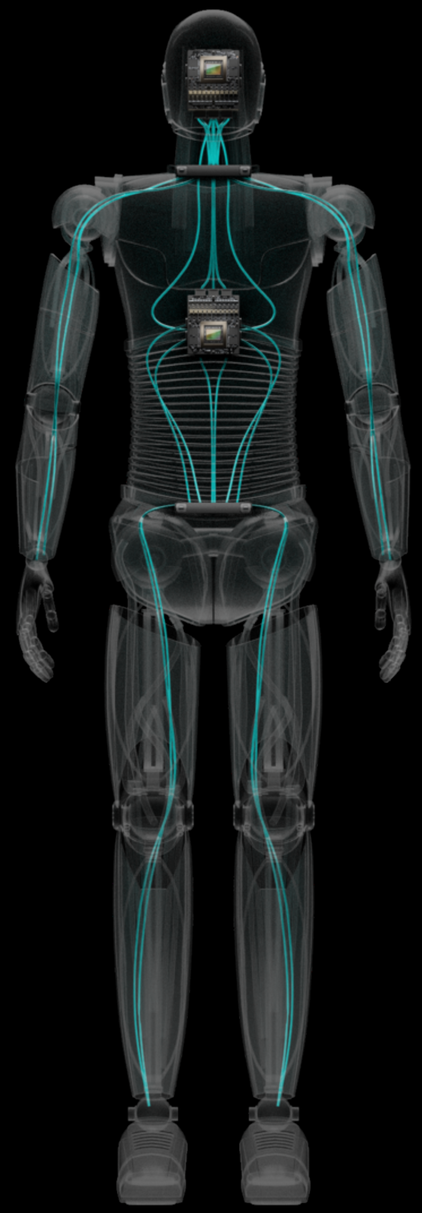
# Project **GR00T**

## AI Brain for Humanoid Robots



# Project **GR00T**

## Generalist Robot 0 0 Technology



# Project **GR00T**

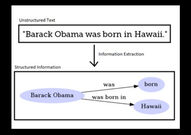
**Generalist** Robot 0 0 Technology

## Specialist

Semantic Parsing

Sentiment Analysis

Summarization




Information Retrieval

## Generalist

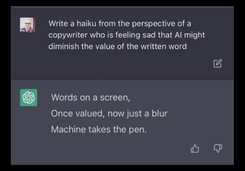
ChatGPT

Meta

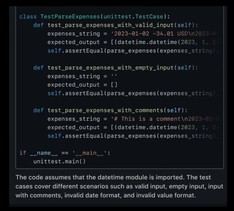
PaLM 2

ANTHROPIC CLAUDE 2

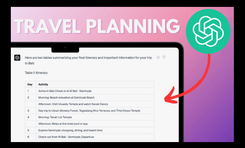
## Specialized Generalist




Creative Writing




Coding

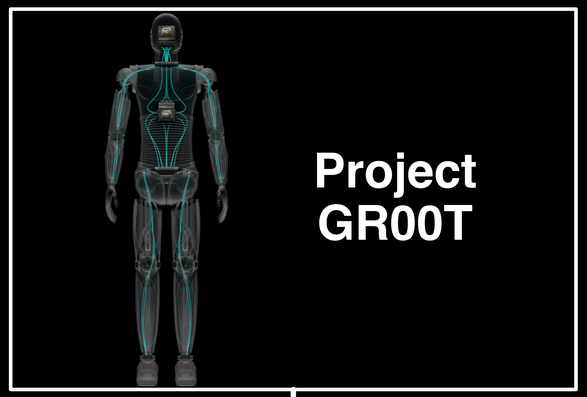



Travel Planning

Apple Intelligence

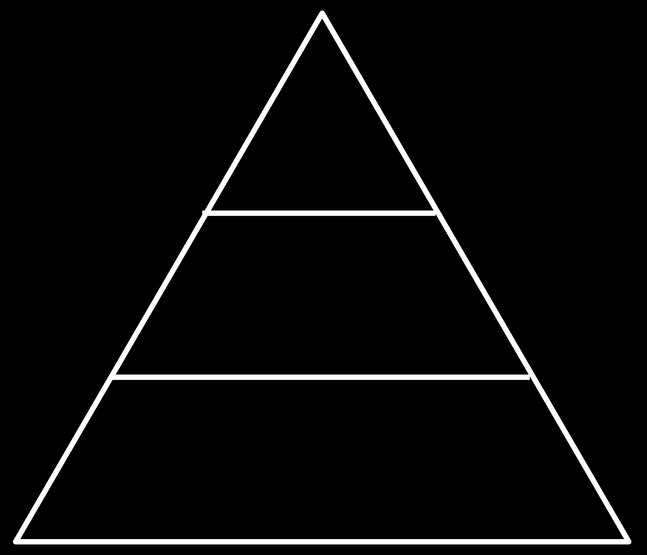
Specialized Generalist

Generalist

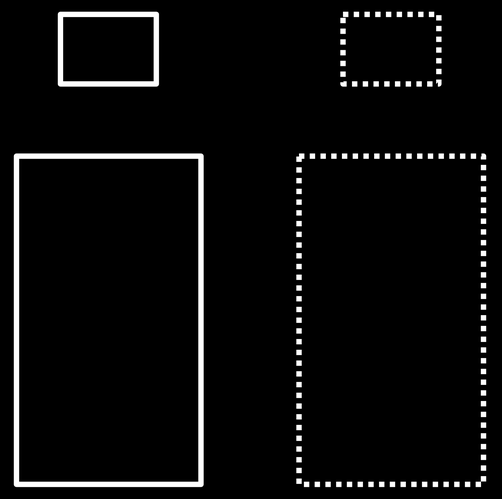



Specialist

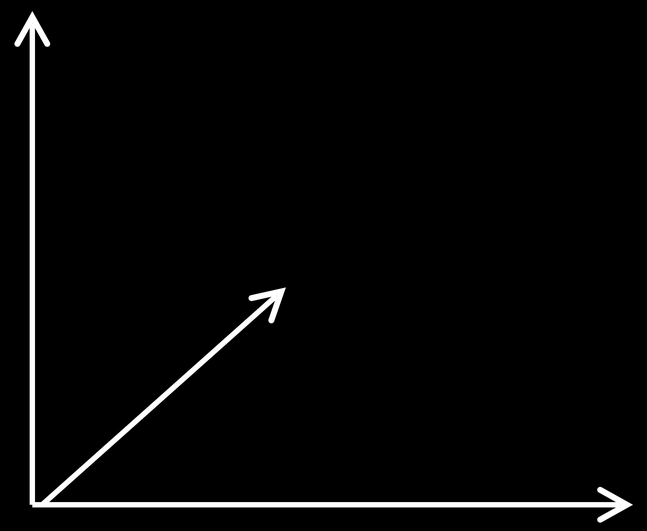
# 3 Principles



Data Pyramid

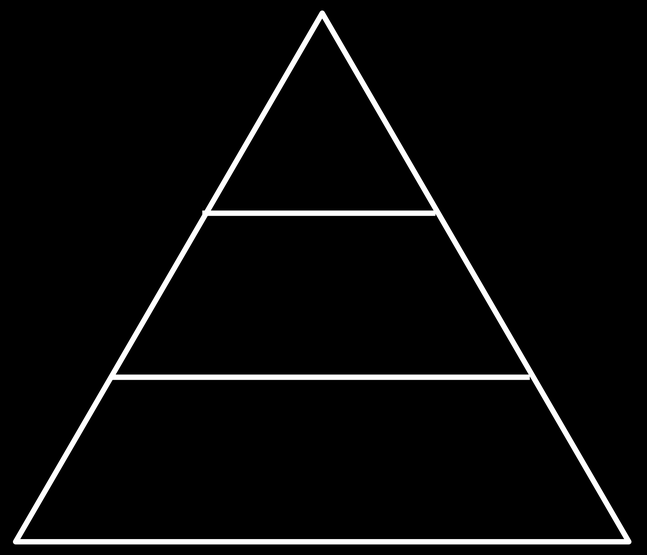


*“The Matrix”*

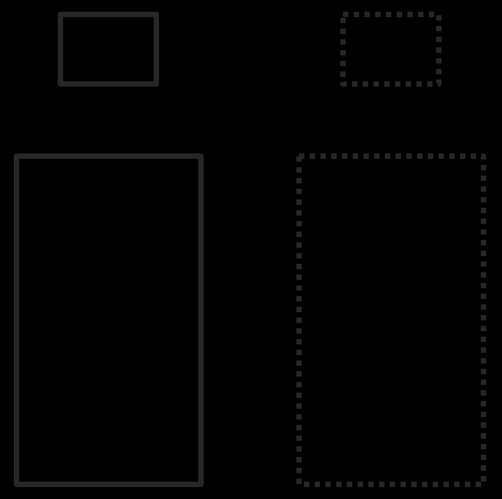


Foundation Agent

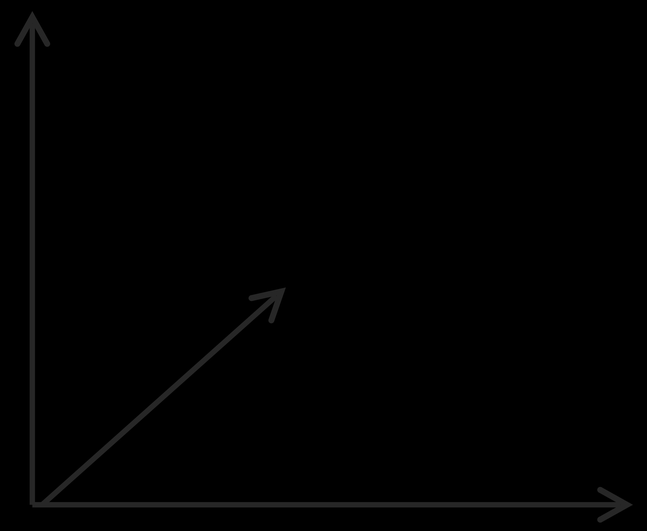
# 3 Principles



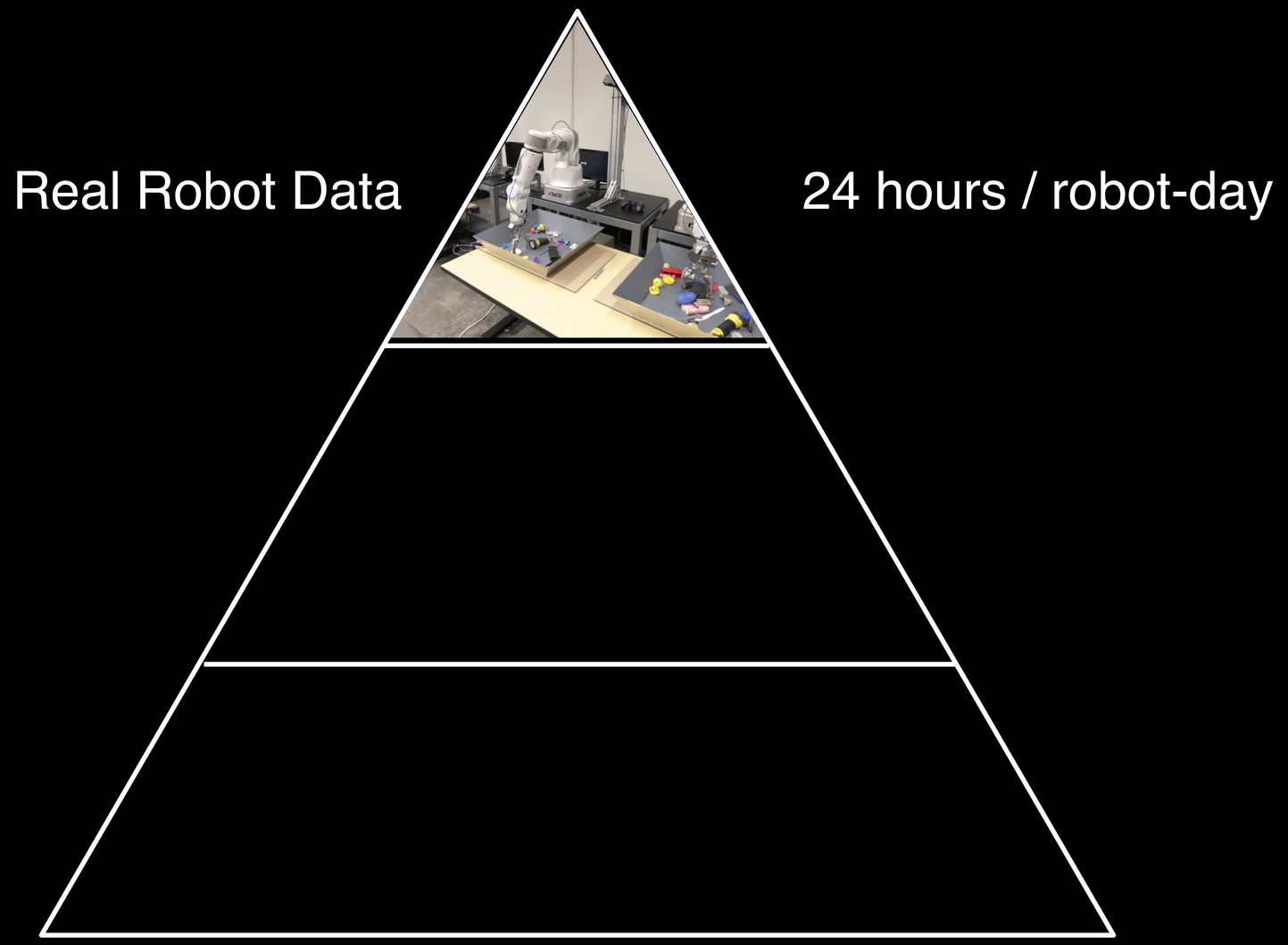
Data Pyramid



*“The Matrix”*



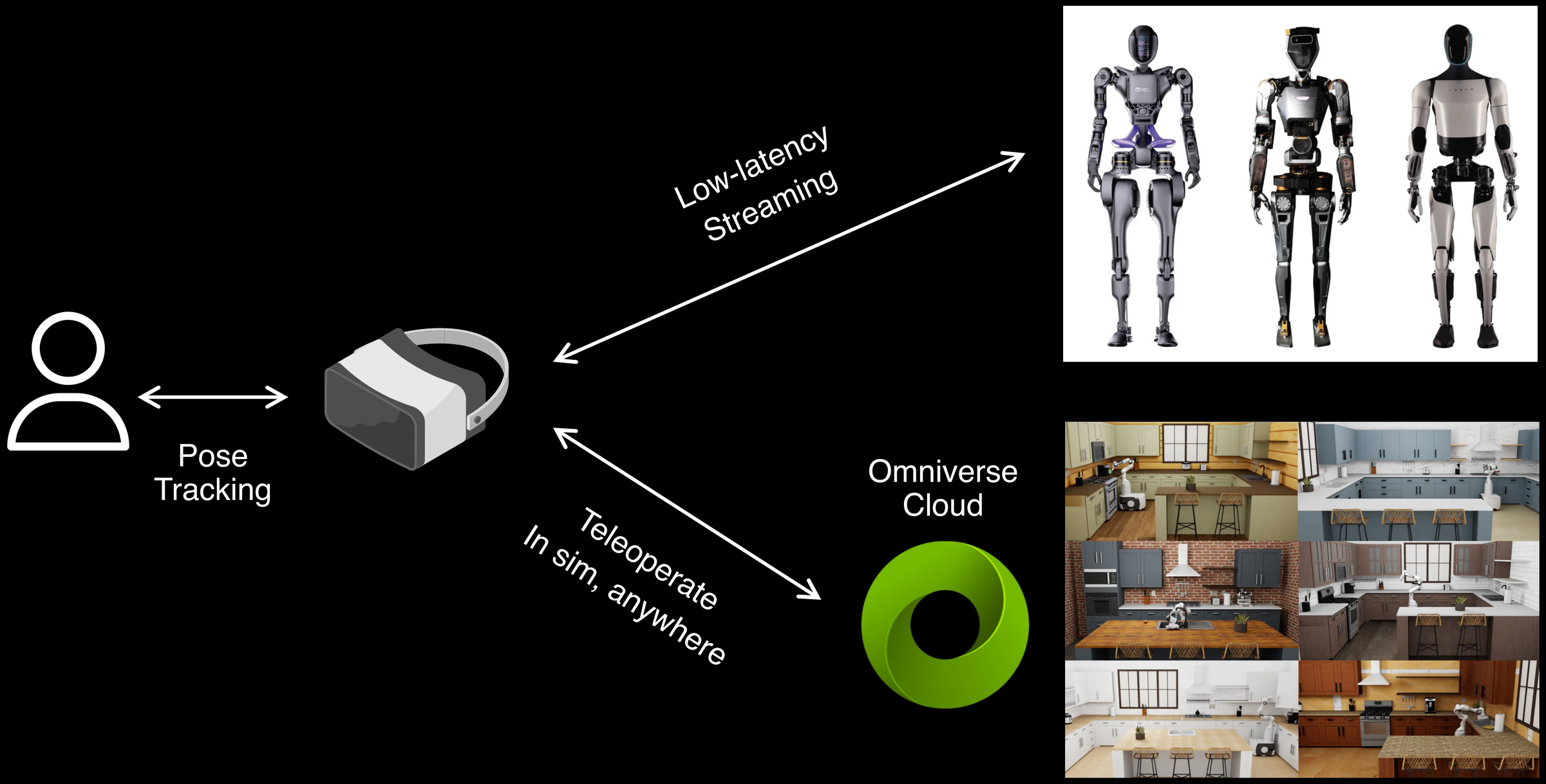
Foundation Agent




**Data Pyramid**

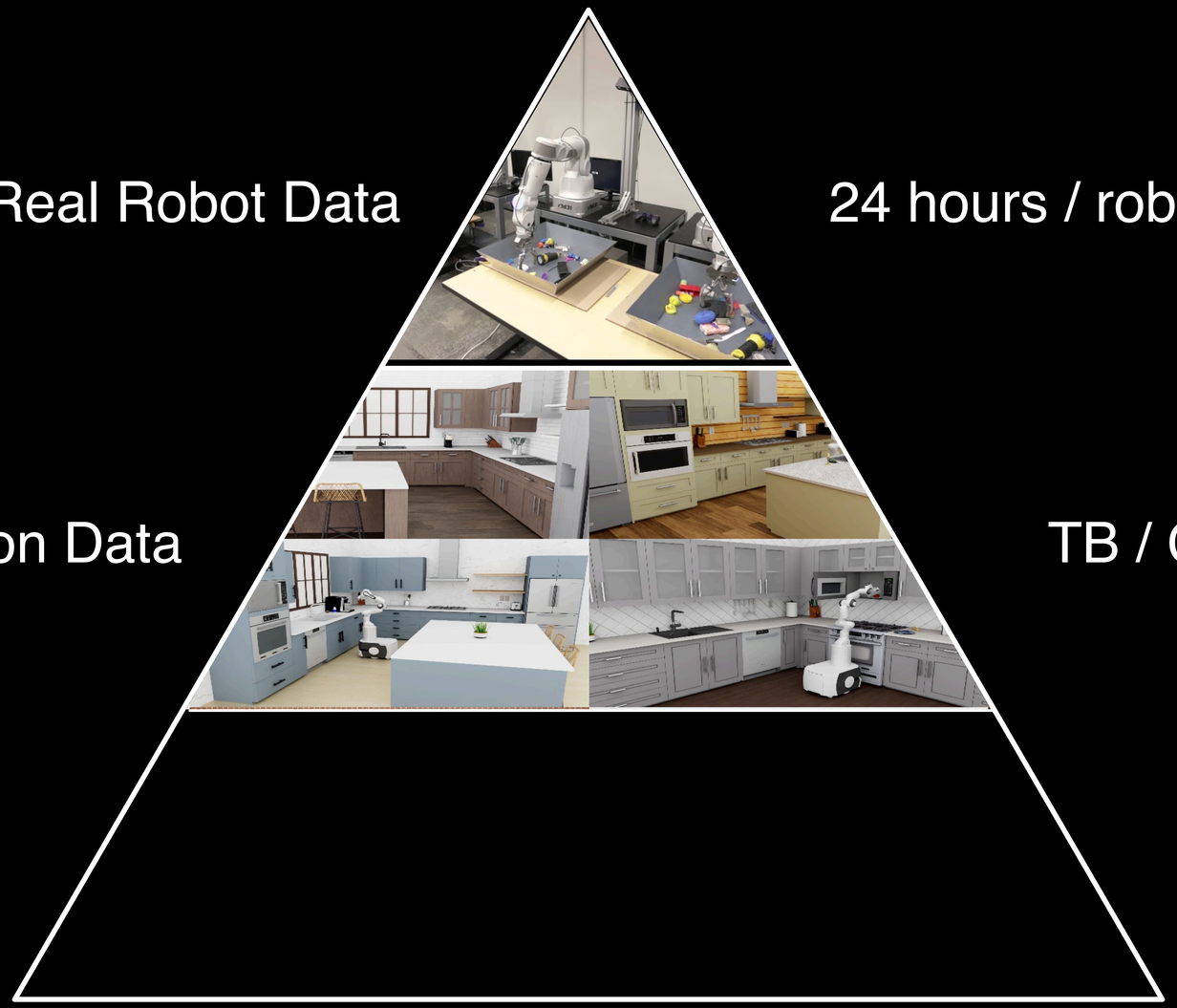
NVIDIA

DELL
Activities
Visual Studio Code
Jul 22 19:50


Pose
Tracking
Low-latency
Streaming
Teleoperate
In sim, anywhere
Omniverse
Cloud

Real Robot Data

24 hours / robot-day



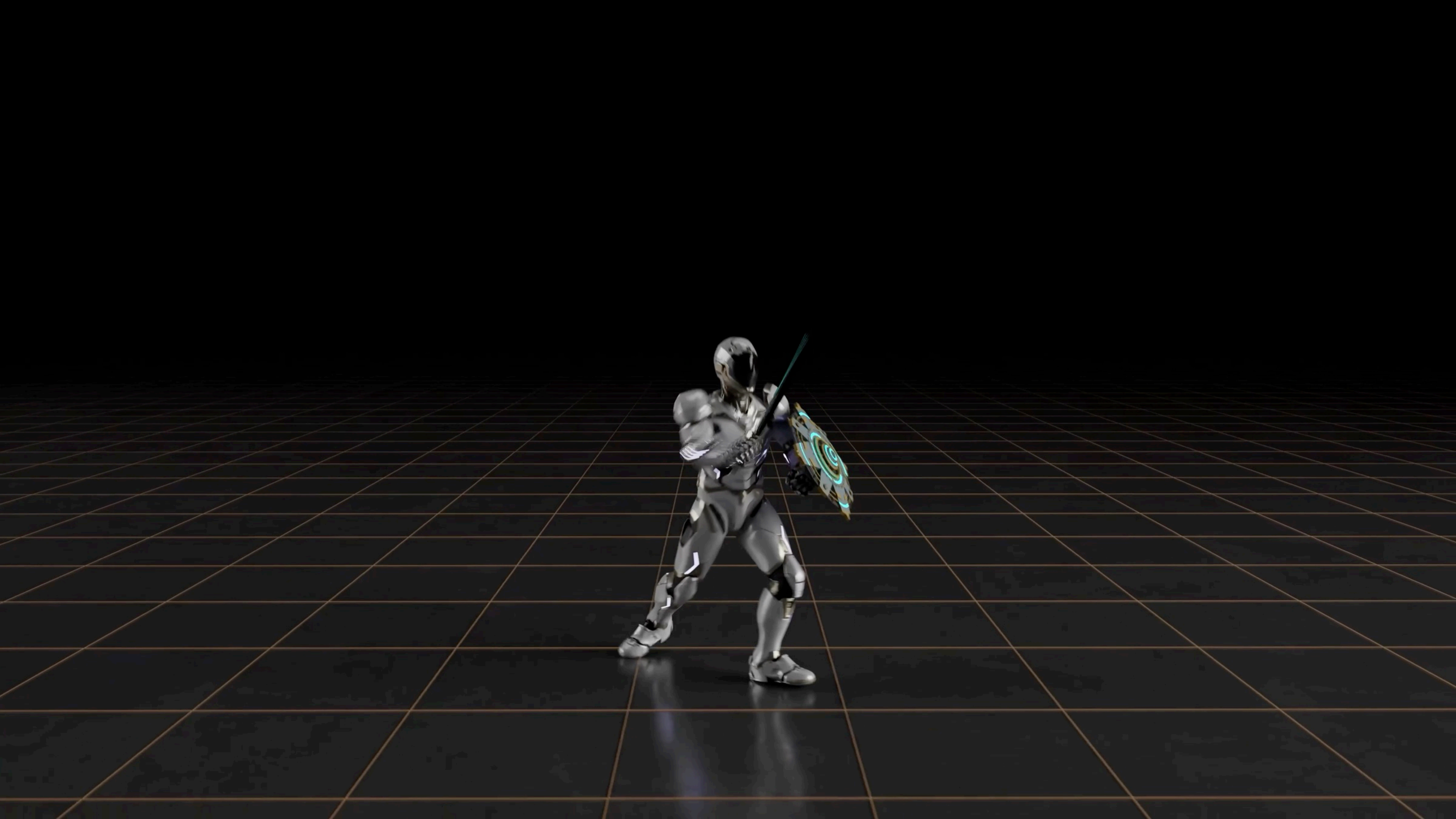
Simulation Data

TB / GPU-day

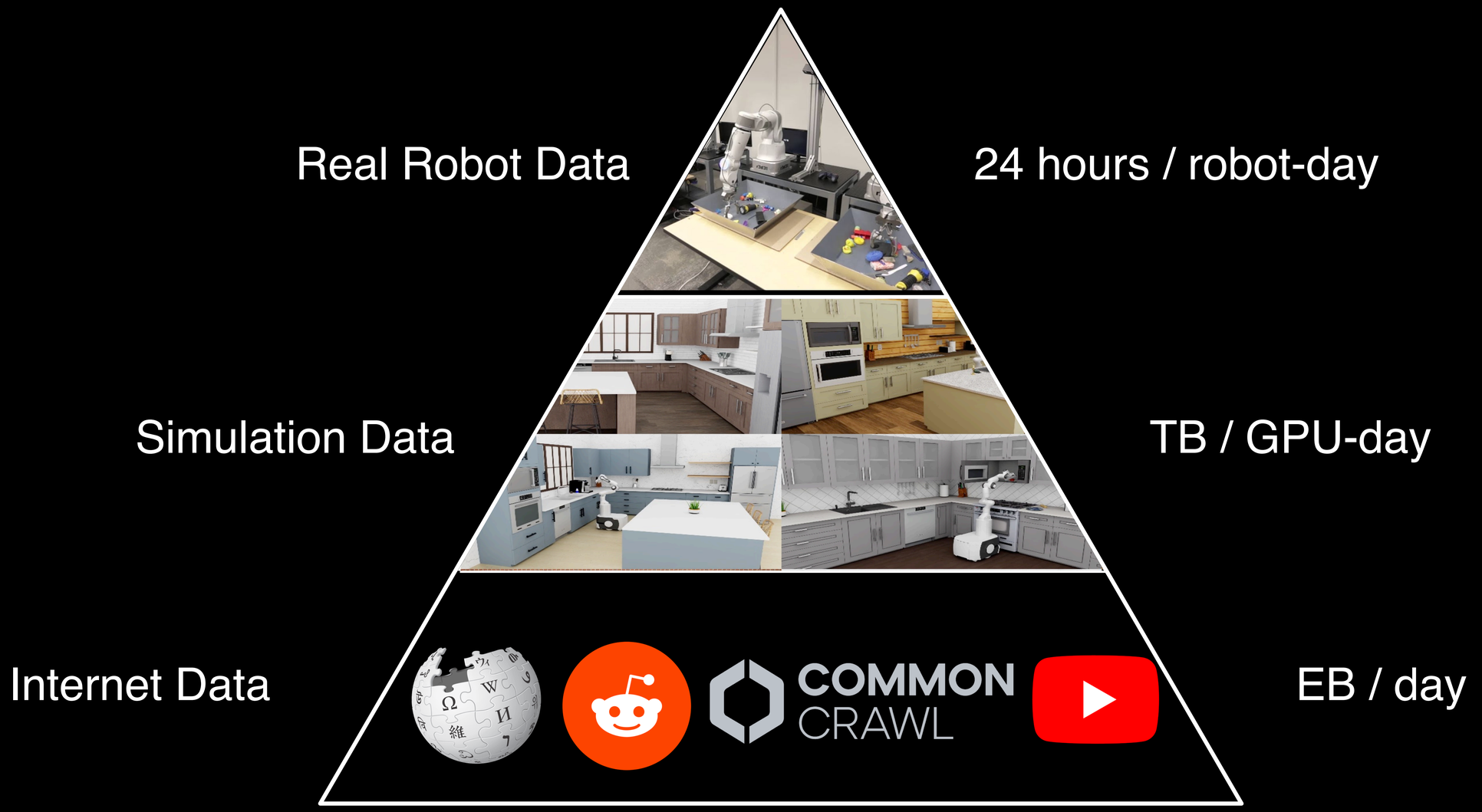
**Data Pyramid**

NVIDIA

Isaac Lab

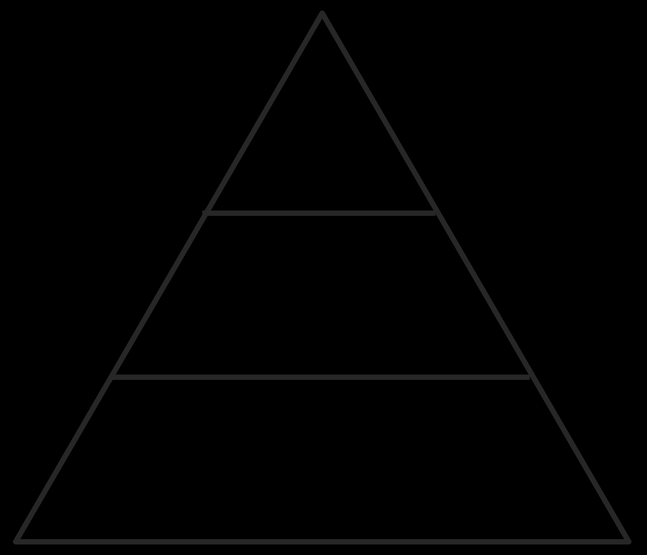


Omniverse

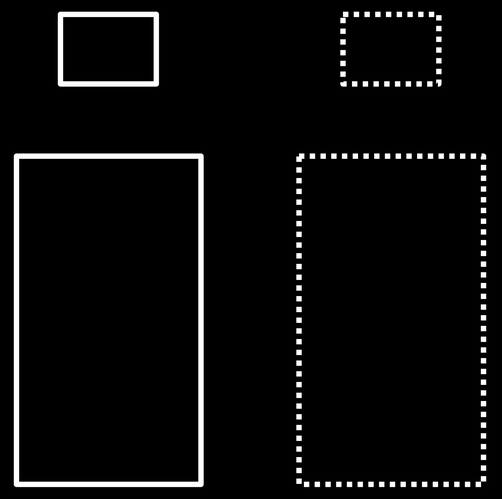



**Data Pyramid**

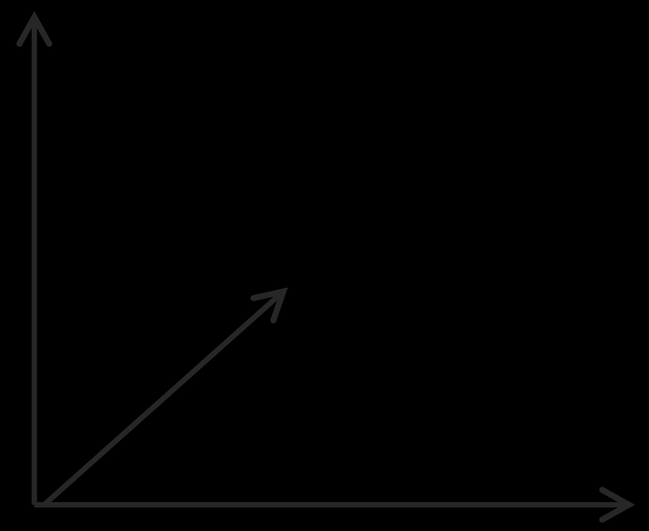
# Principle No. 2



Data Pyramid



*“The Matrix”*



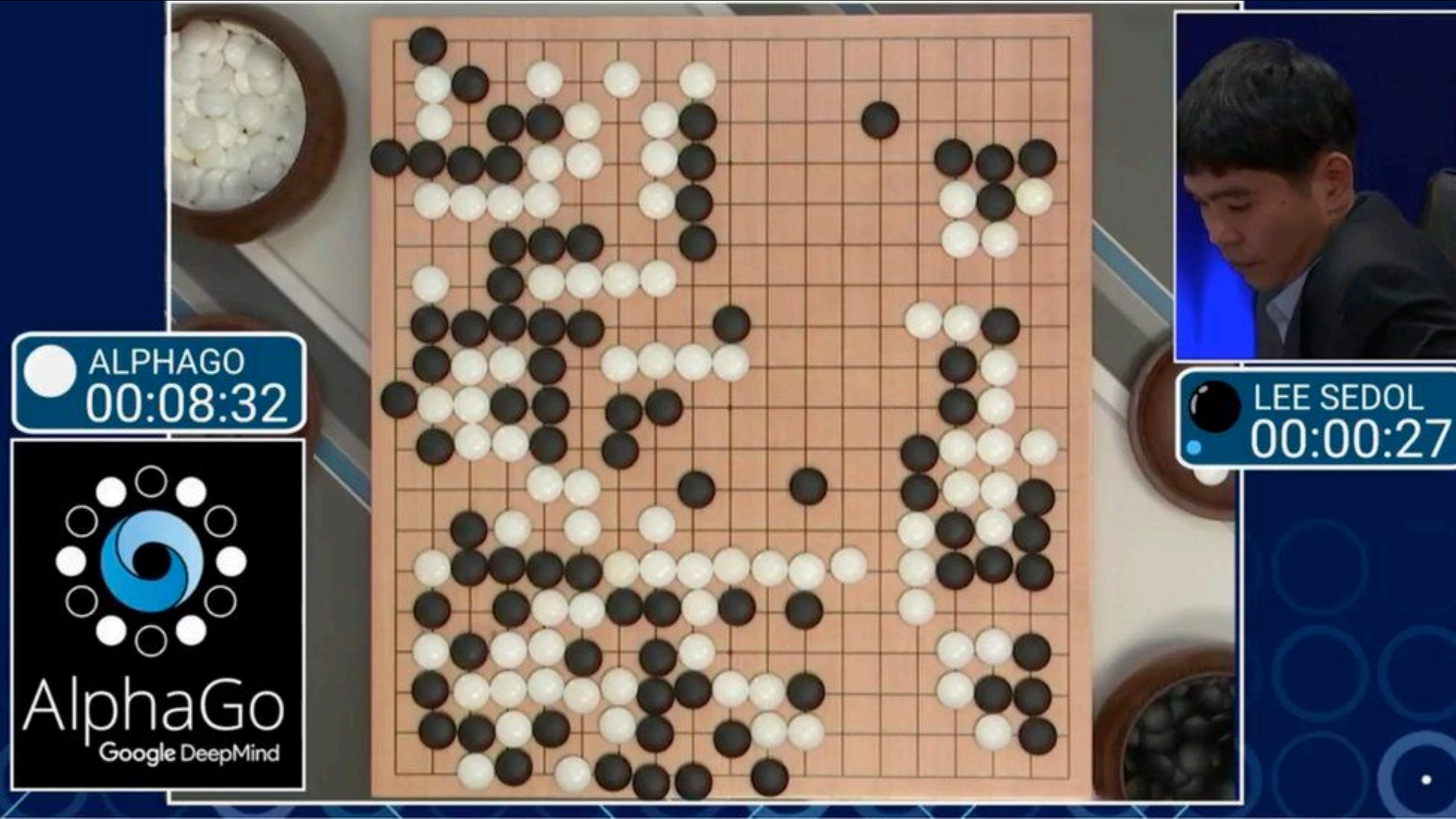
Foundation Agent

Do we live in a simulation?

Do robots live in a simulation?

*Why does simulation work for training robots?*

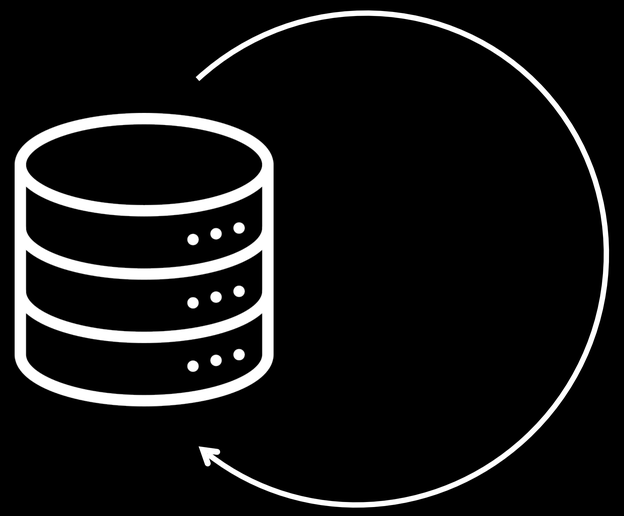
It’s easier to simulate a problem than to solve it.


ALPHAGO
00:08:32
AlphaGo
Google DeepMind
LEE SEDOL
00:00:27

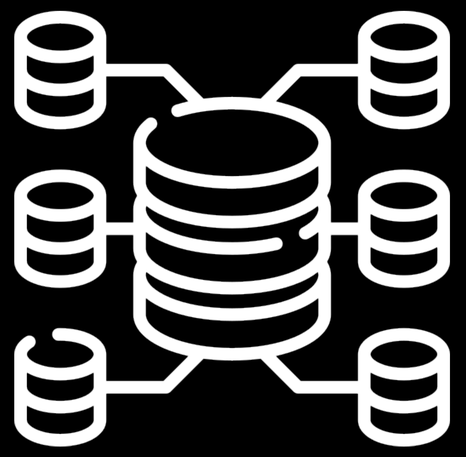
MINECRAFT

# MINEDOJO

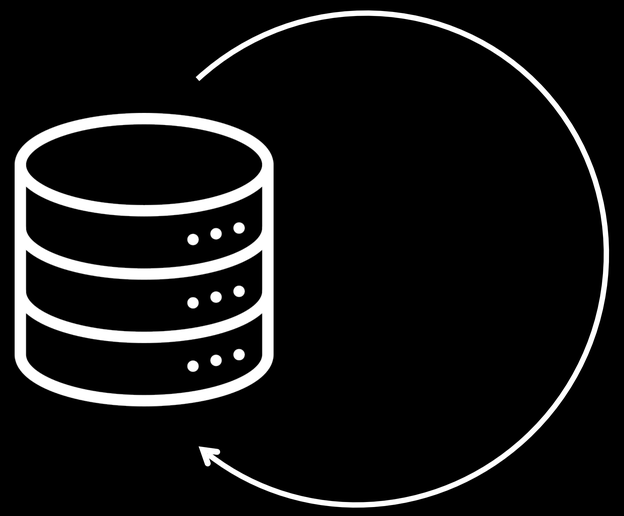
## Framework for Generally Capable Agents



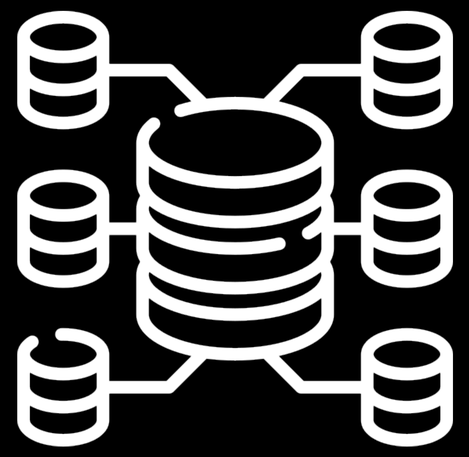
Self-Generated Data



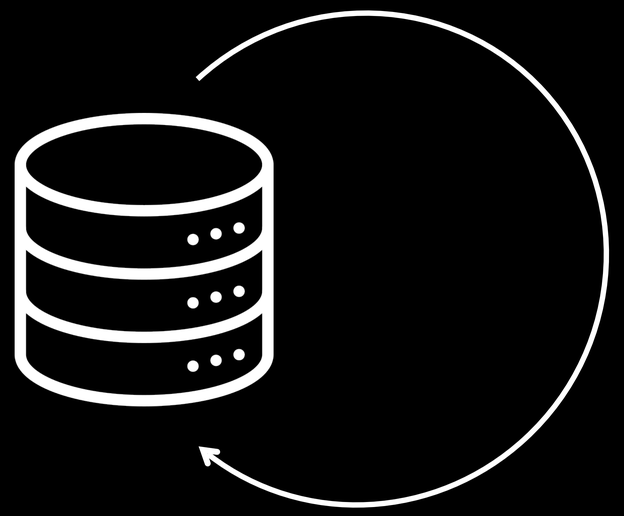
Multiply Data



Reinforcement Learning

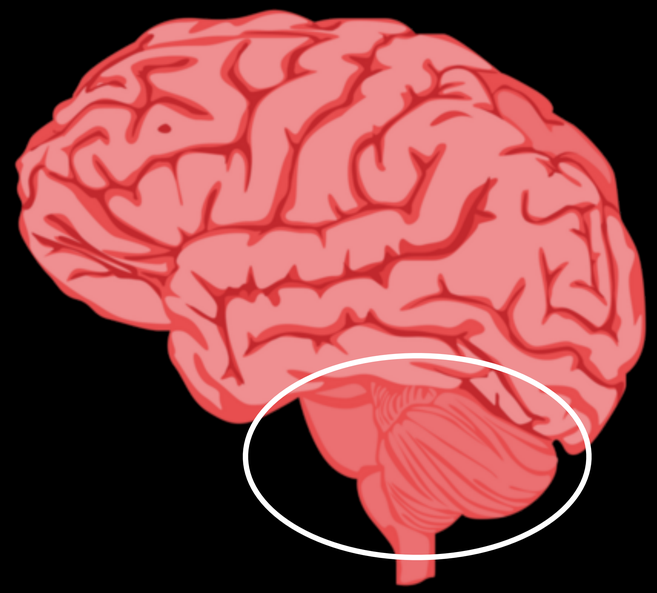


Imitation Learning



Reinforcement Learning

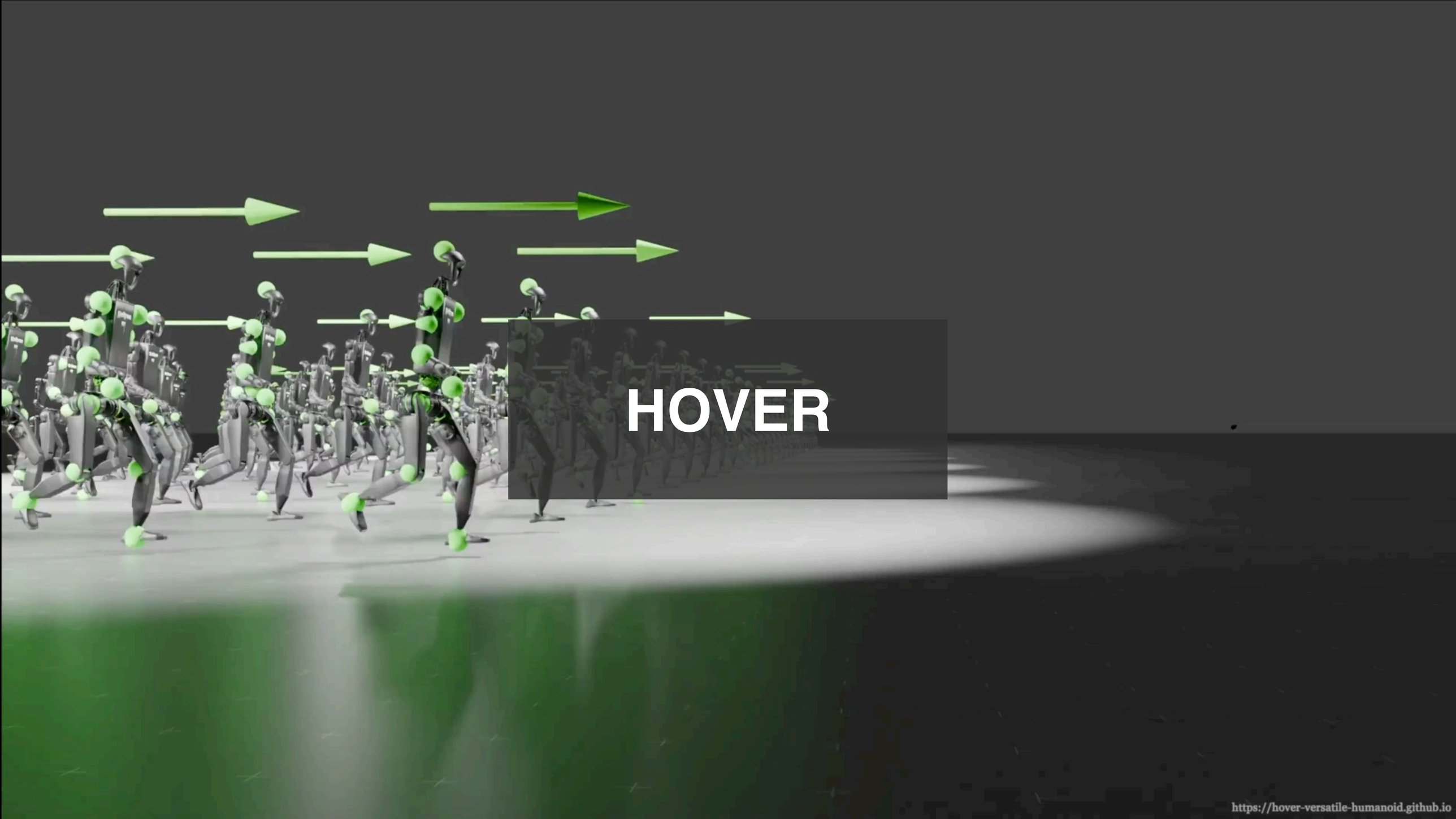
How many parameters needed to build a Cerebellum?

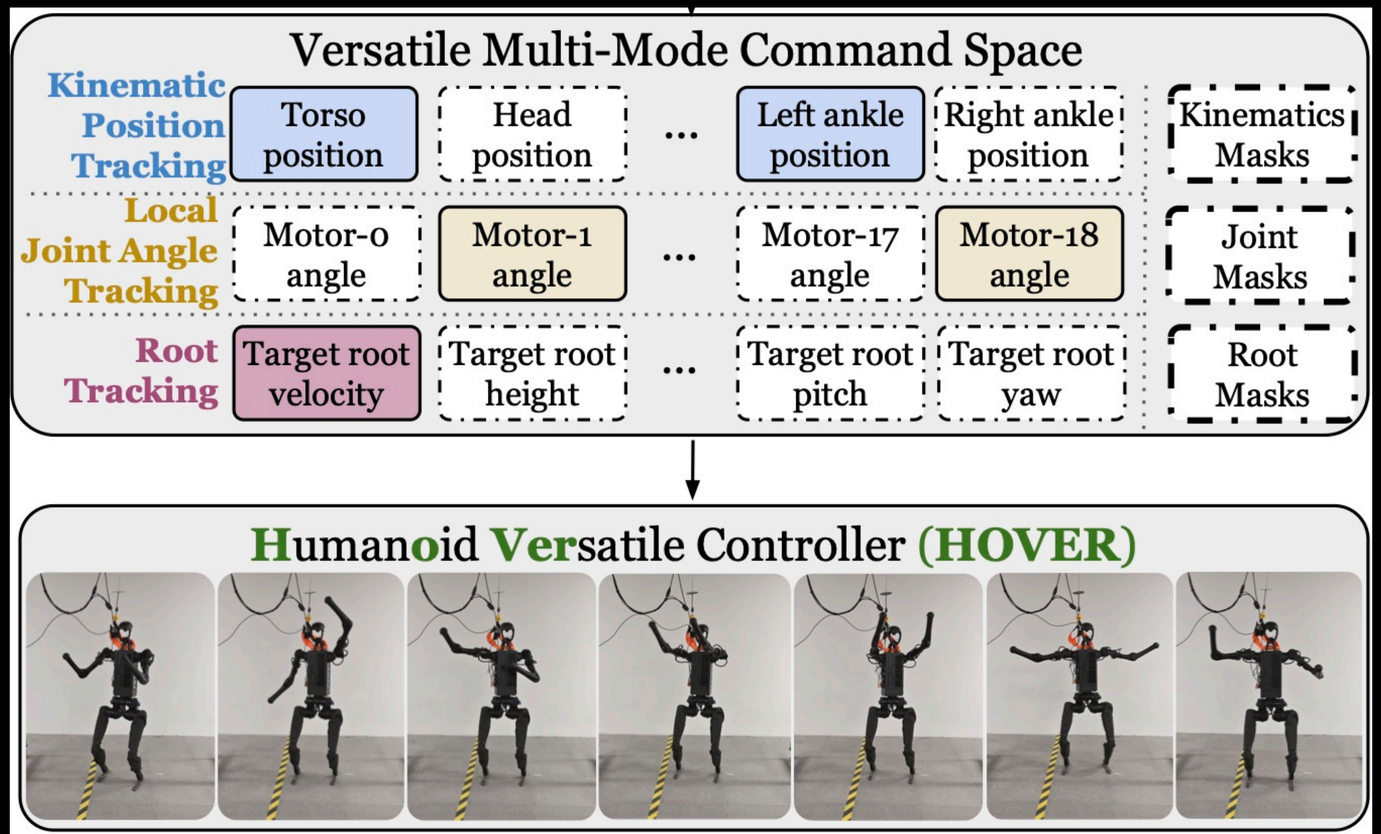


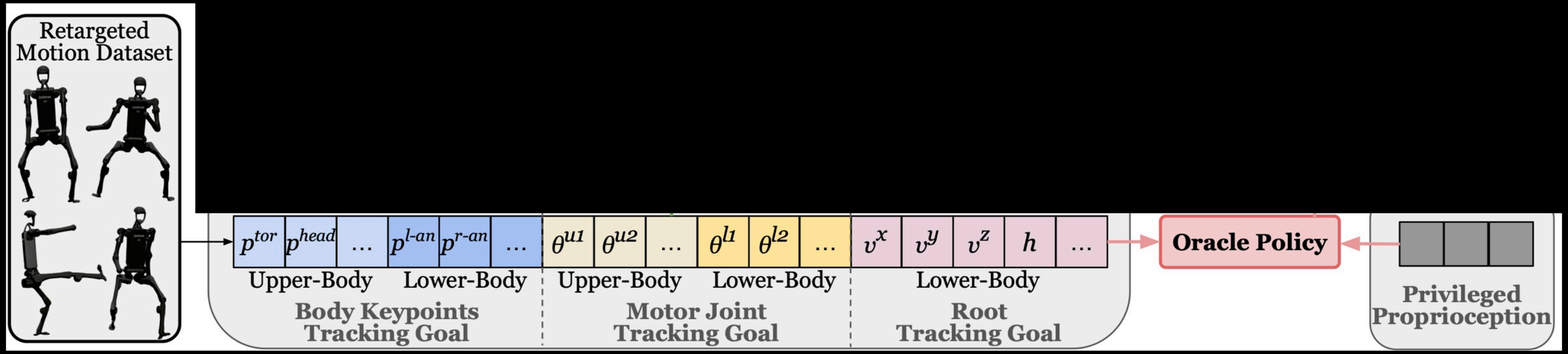
DANGER

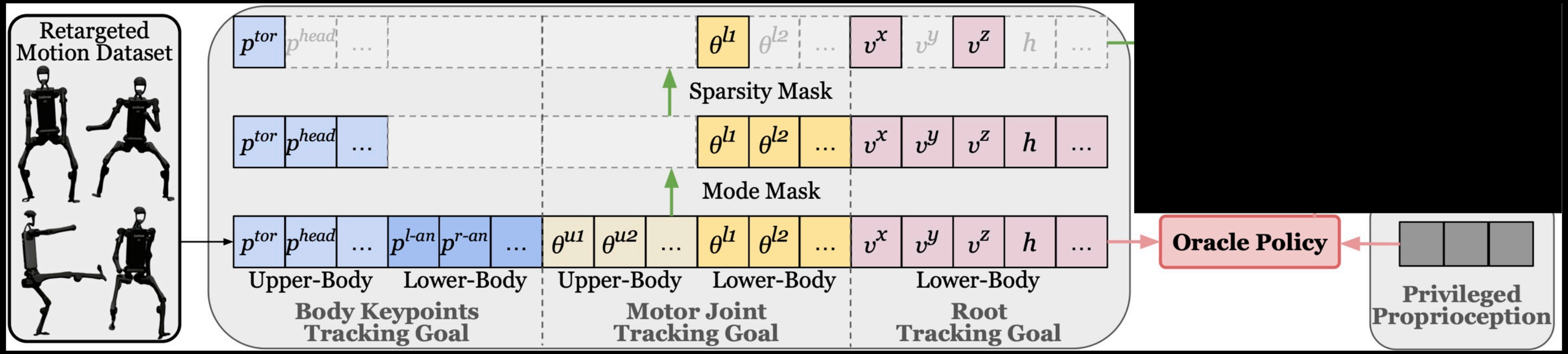
GAME CHANGE

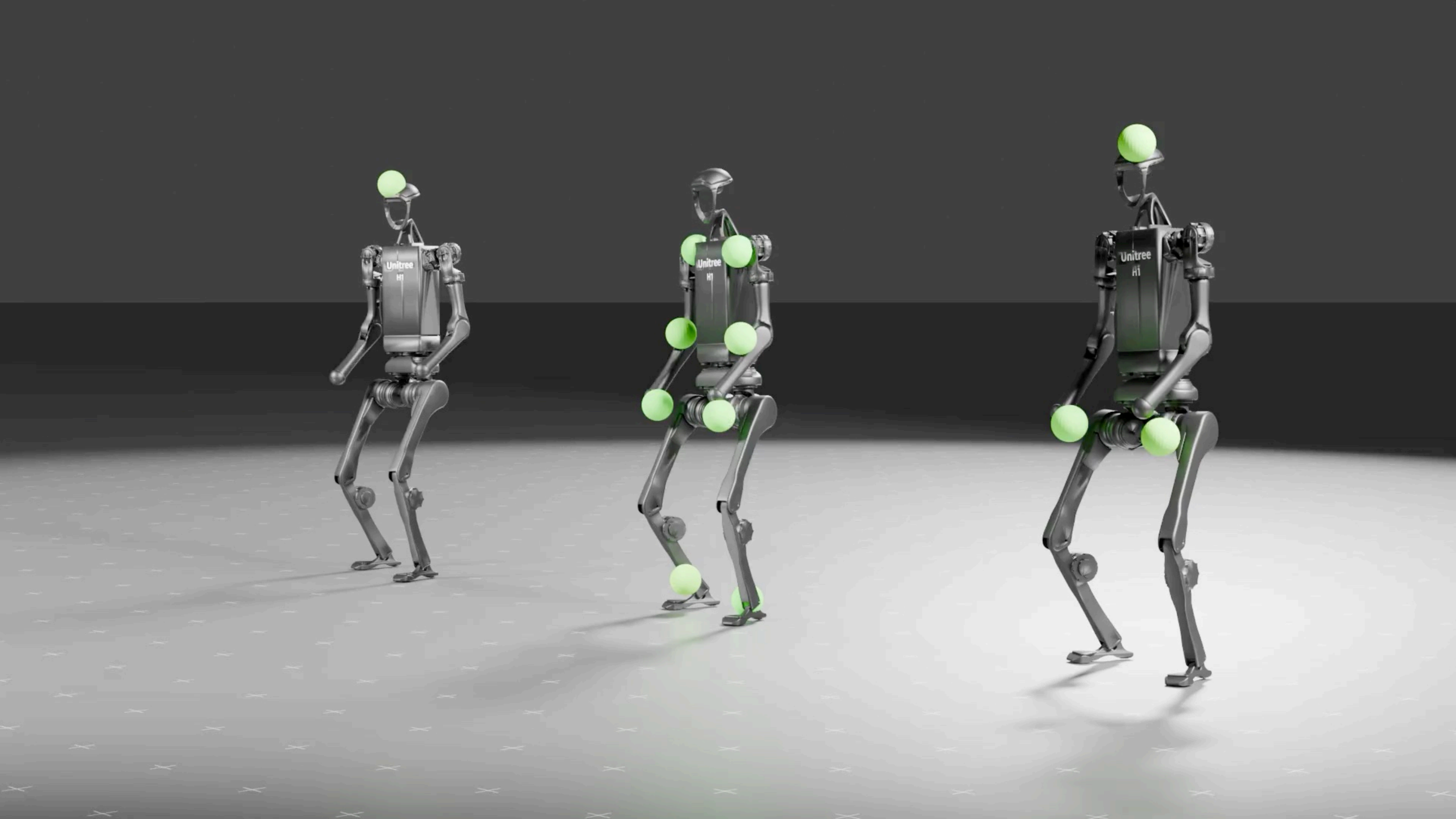
ENGINE COVER
RETURN TO SCA
Fully Autonomous

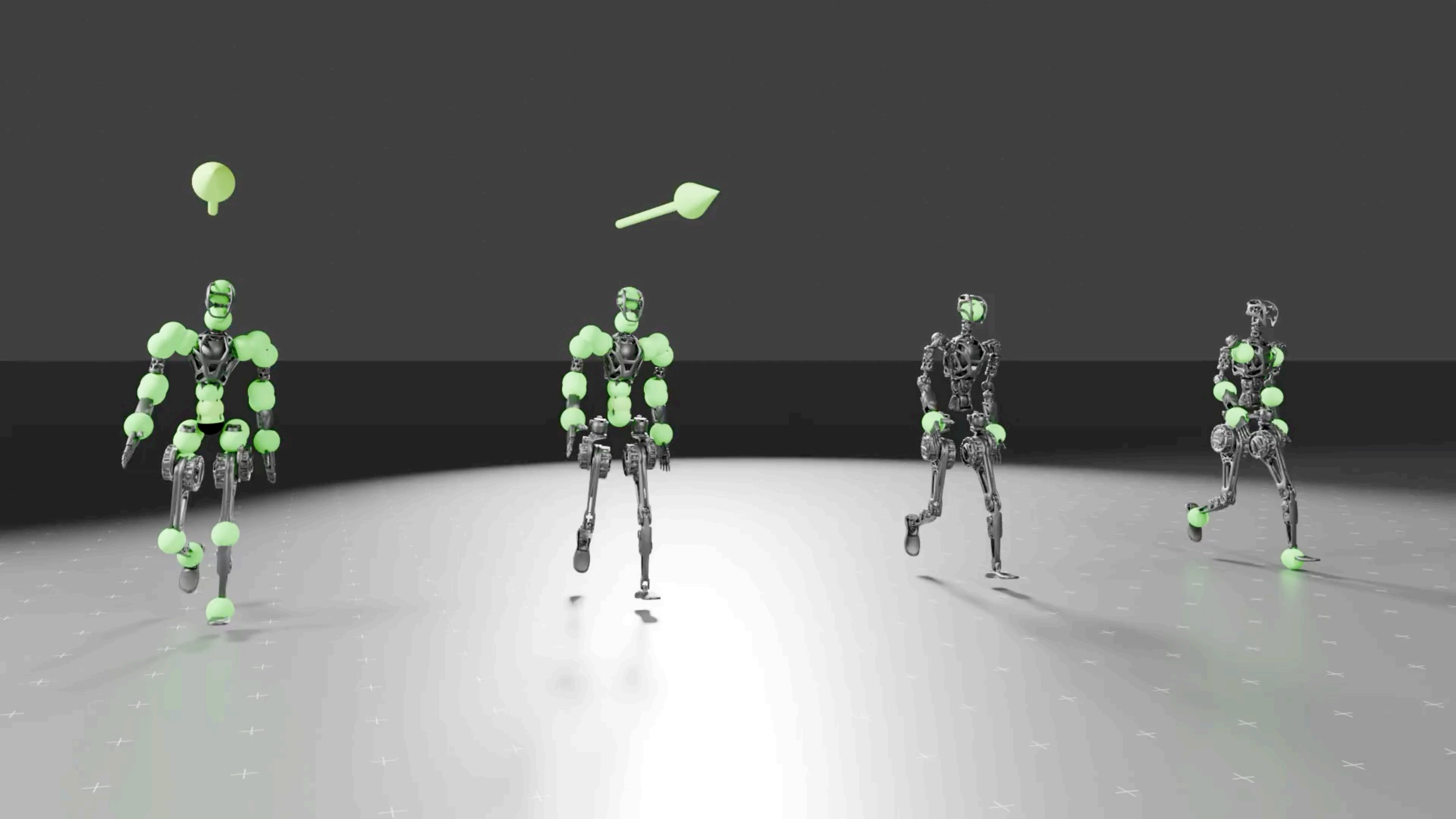

HOVER
https://hover-versatile-humanoid.github.io


Versatile Multi-Mode Command Space
Kinematic Position Tracking
Torso position
Head position
...
Left ankle position
Right ankle position
Kinematics Masks
Local Joint Angle Tracking
Motor-0 angle
Motor-1 angle
...
Motor-17 angle
Motor-18 angle
Joint Masks
Root Tracking
Target root velocity
Target root height
...
Target root pitch
Target root yaw
Root Masks
Humanoid Versatile Controller (HOVER)


Retargeted Motion Dataset
$p^{tor}$
$p^{head}$
…
$p^{l\text{-}an}$
$p^{r\text{-}an}$
…
$\theta^{u1}$
$\theta^{u2}$
…
$\theta^{l1}$
$\theta^{l2}$
…
$v^x$
$v^y$
$v^z$
$h$
…
Upper-Body
Lower-Body
Upper-Body
Lower-Body
Lower-Body
Body Keypoints Tracking Goal
Motor Joint Tracking Goal
Root Tracking Goal
Oracle Policy
Privileged Proprioception

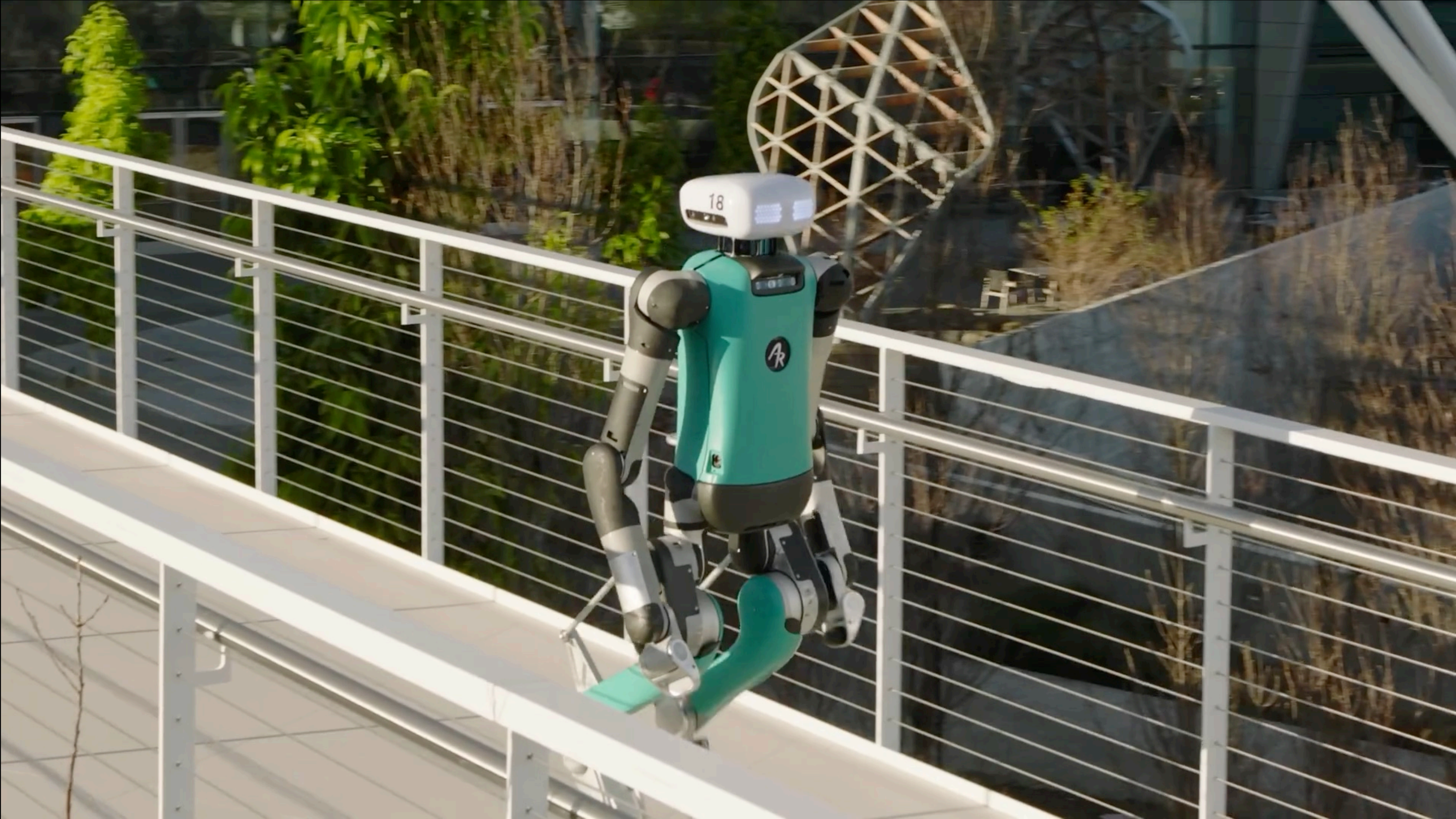

Retargeted Motion Dataset
$p^{tor}$ $p^{head}$ … $\theta^{l1}$ $\theta^{l2}$ … $v^x$ $v^y$ $v^z$ $h$ …
Sparsity Mask
$p^{tor}$ $p^{head}$ … $\theta^{l1}$ $\theta^{l2}$ … $v^x$ $v^y$ $v^z$ $h$ …
Mode Mask
$p^{tor}$ $p^{head}$ … $p^{l\text{-}an}$ $p^{r\text{-}an}$ … $\theta^{u1}$ $\theta^{u2}$ … $\theta^{l1}$ $\theta^{l2}$ … $v^x$ $v^y$ $v^z$ $h$ …
Upper-Body
Lower-Body
Upper-Body
Lower-Body
Lower-Body
Body Keypoints Tracking Goal
Motor Joint Tracking Goal
Root Tracking Goal
Oracle Policy
Privileged Proprioception


Unitree
H1
Unitree
H1
Unitree
H1



Training Iteration 500

Motion Description: *Walk forward and give a high-five.*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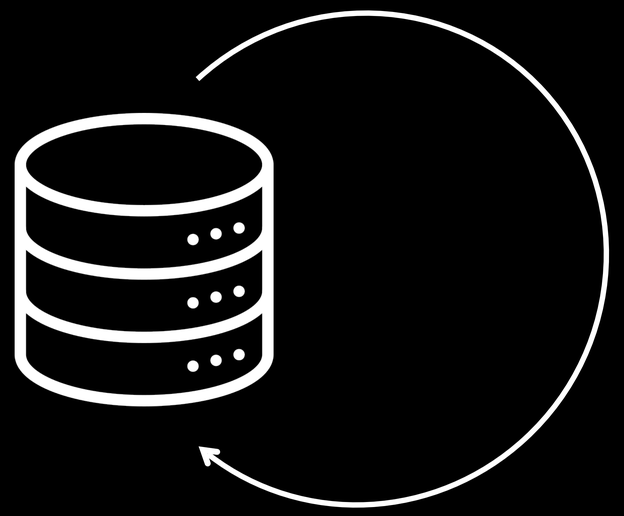
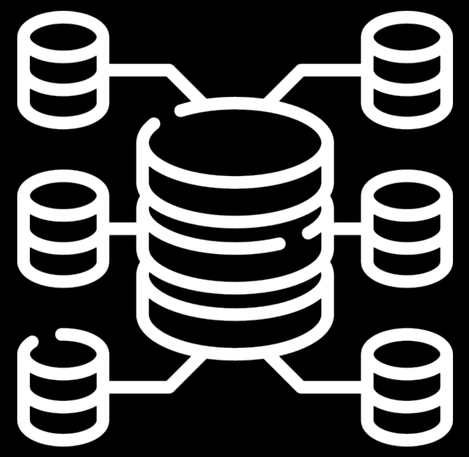
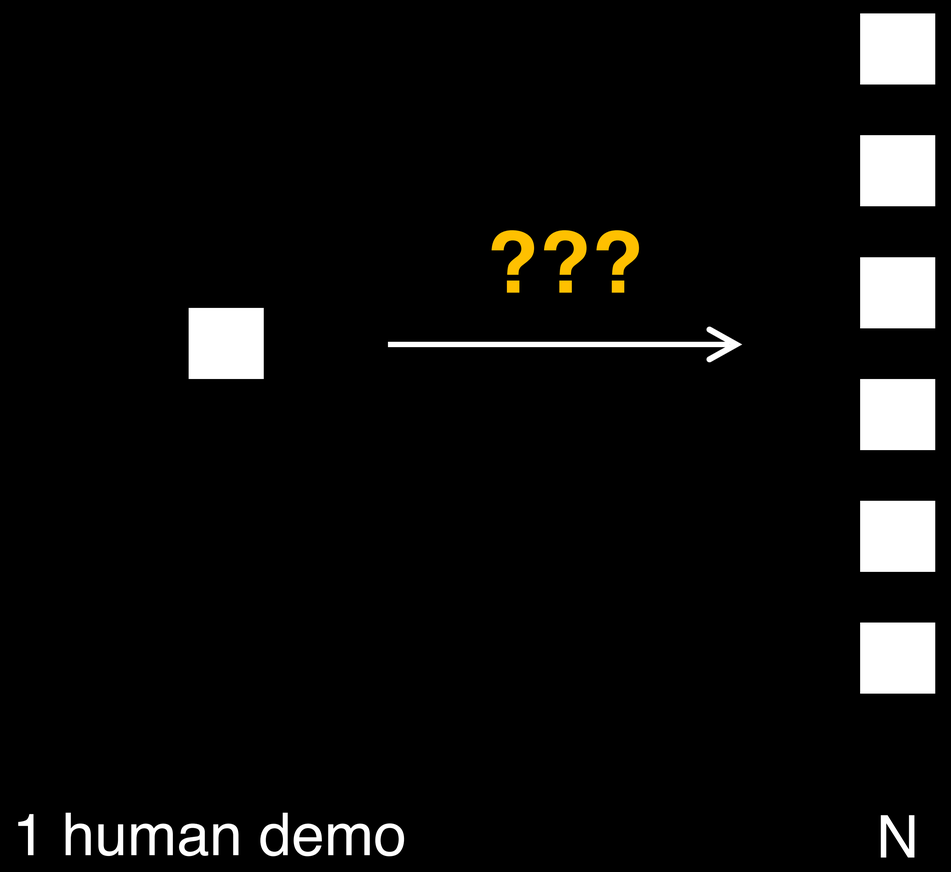


Reinforcement Learning



Imitation Learning

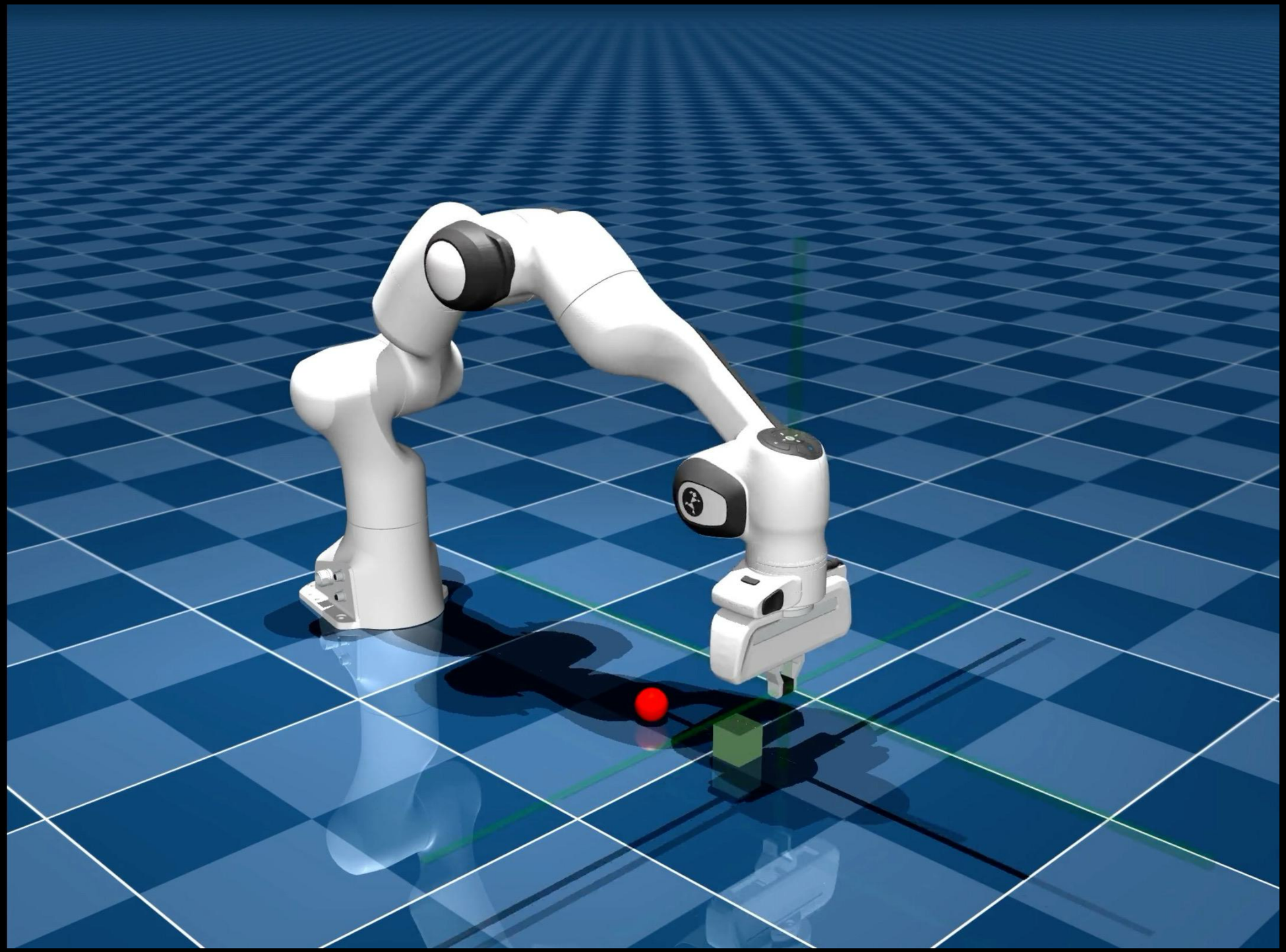

???
1 human demo
N

# What’s in a Robot Simulation?

Hand-made Objects

Hand-crafted Scenes

Hand-designed Tasks



Xu et al. 2023

# What's in a Robot Simulation?

Hand-made
Objects

↓

Generate 3D

**Text-to-3D models**

BEKO

# What's in a Robot Simulation?

Hand-made Objects

↓

Generate 3D

Text-to-3D models

Hand-crafted Scenes

↓

Generate USD

**Stable Diffusion**

# What's in a Robot Simulation?

Hand-made Objects

↓

Generate 3D

Text-to-3D models

Hand-crafted Scenes

↓

Generate USD

Stable Diffusion

**ChatUSD**

# What's in a Robot Simulation?

| Hand-made Objects | Hand-crafted Scenes | Hand-designed Tasks |
|---|---|---|
| ↓ | ↓ | ↓ |
| Generate 3D | Generate USD | Generate Code |
| Text-to-3D models | Stable Diffusion, ChatUSD | **GPT-4o**, **Claude-3.5** |

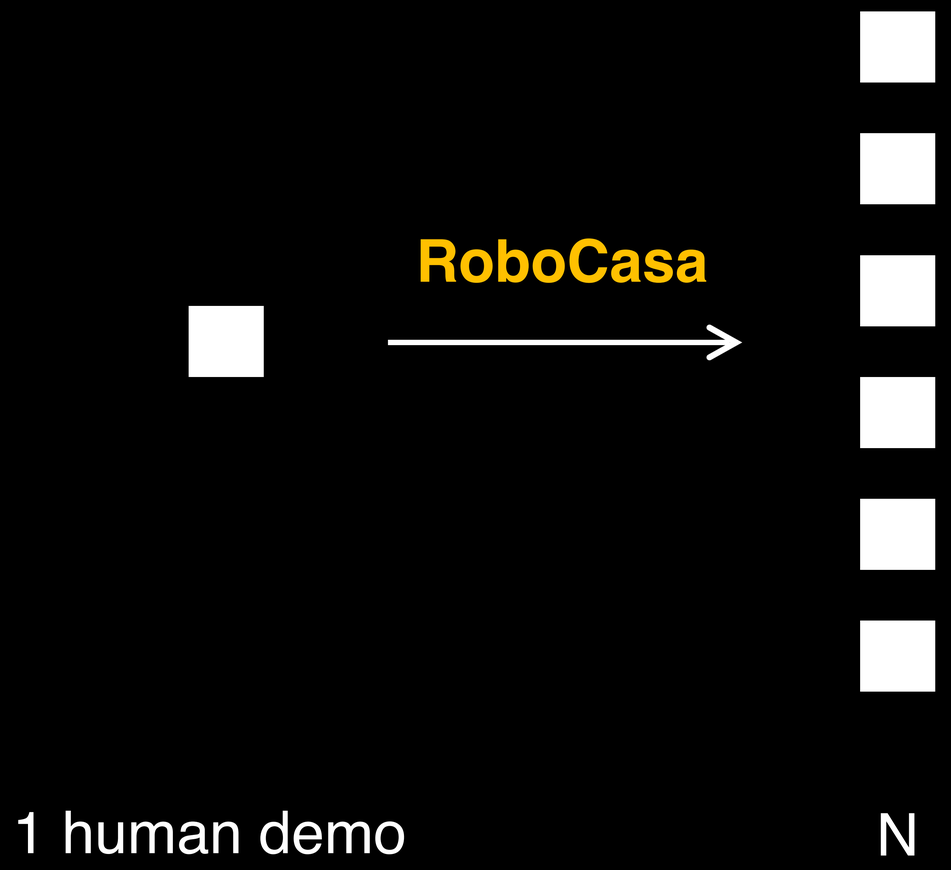
FRIGIDAIRE

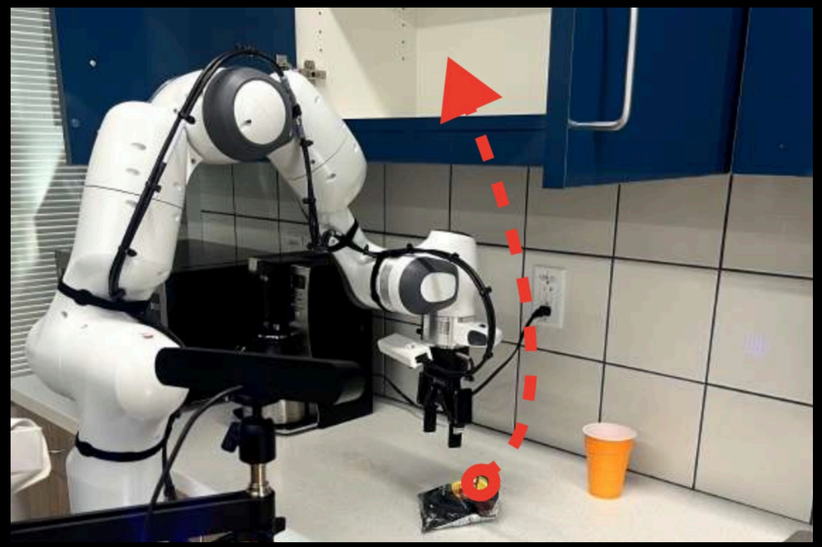
RoboCasa

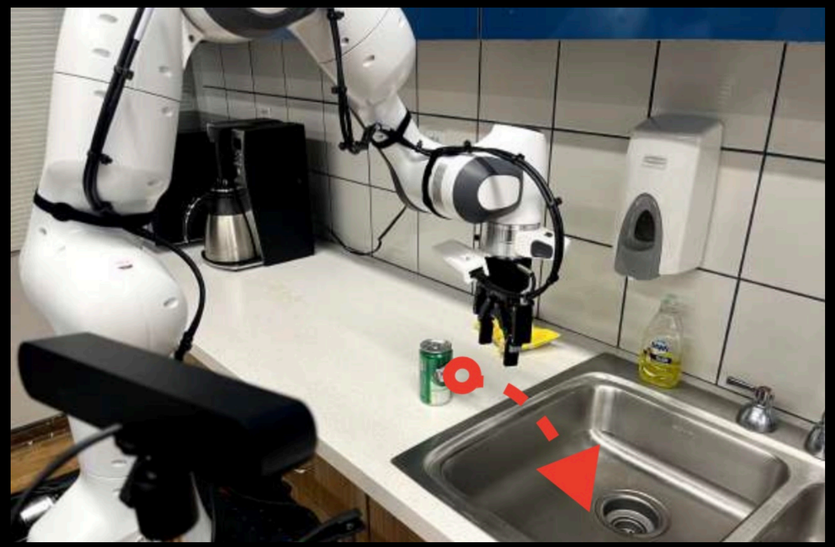
# **RoboCasa**: Generative Simulation Framework

| Hand-made Objects | Hand-crafted Scenes | Hand-designed Tasks |
|---|---|---|
| ↓ | ↓ | ↓ |
| Generate 3D | Generate USD | Generate Code |
| Text-to-3D models | Stable Diffusion, ChatUSD | GPT-4o, Claude-3.5 |

Nasiriany et al. RSS 2024.


RoboCasa
1 human demo
N

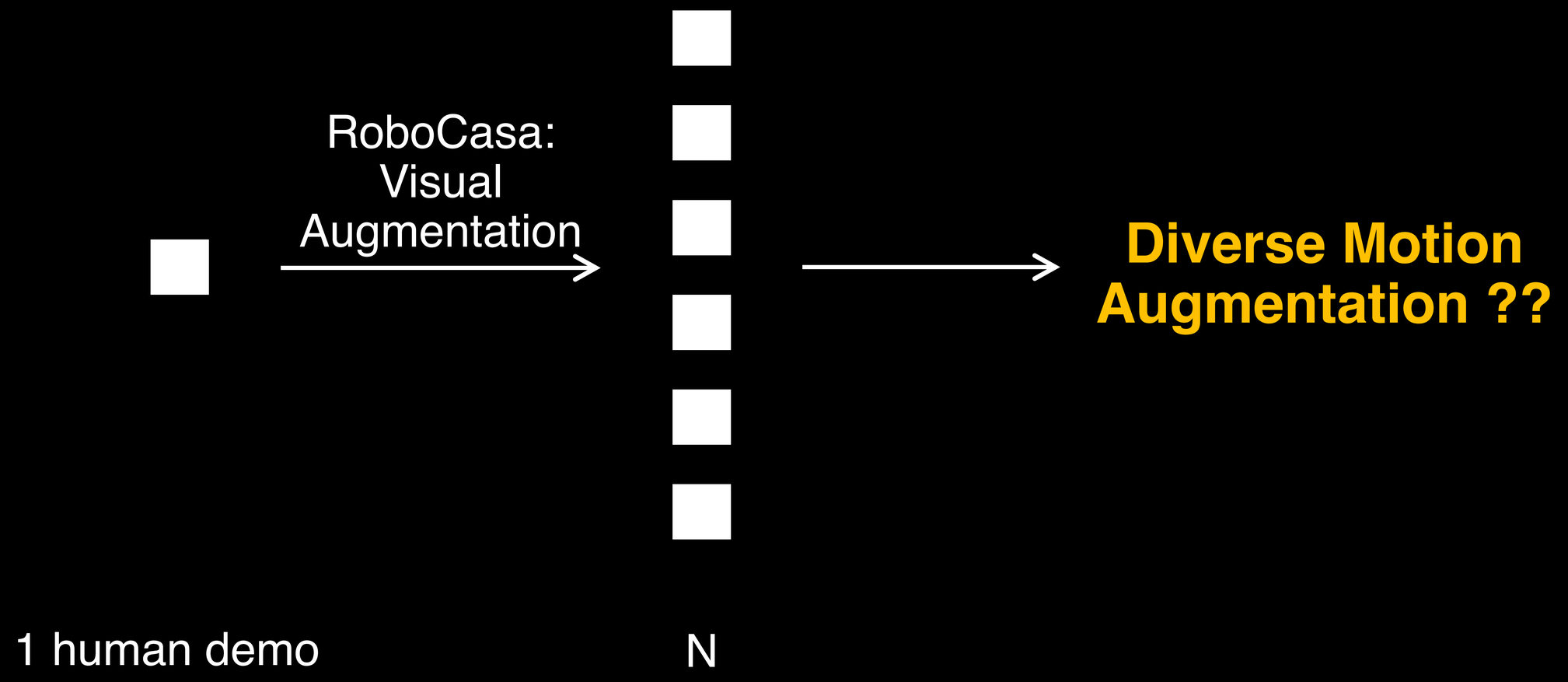


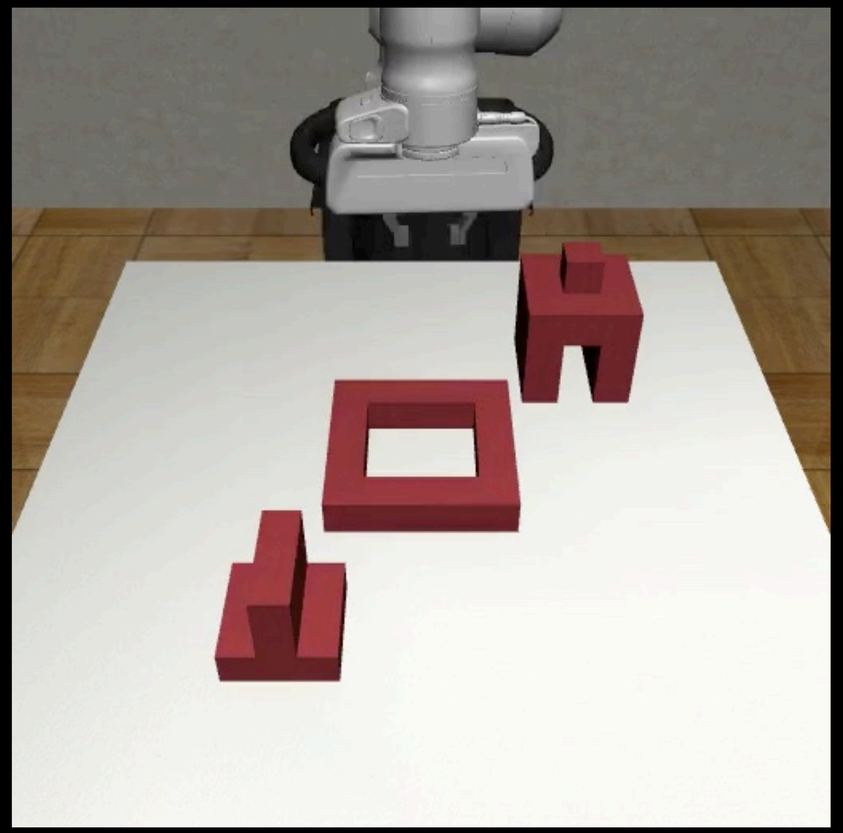


| Setting | Task | Real only | Real + Sim (Ours) |
|---|---|---|---|
| Seen Obj | Counter to sink | 12.7 ± 2.5 | **22.0 ± 2.8** |
| | Sink to counter | 20.0 ± 5.9 | **29.3 ± 4.1** |
| | Counter to cabinet | 8.0 ± 1.6 | **22.0 ± 5.8** |
| | Task average | 13.6 | **24.4** |
| Unseen Obj | Counter to sink | 3.3 ± 4.7 | **8.9 ± 7.9** |
| | Sink to counter | 1.1 ± 1.6 | **7.8 ± 4.2** |
| | Counter to cabinet | 3.3 ± 4.7 | **11.1 ± 11.0** |
| | Task average | 2.6 | **9.3** |

Nasiriany et al. RSS 2024.

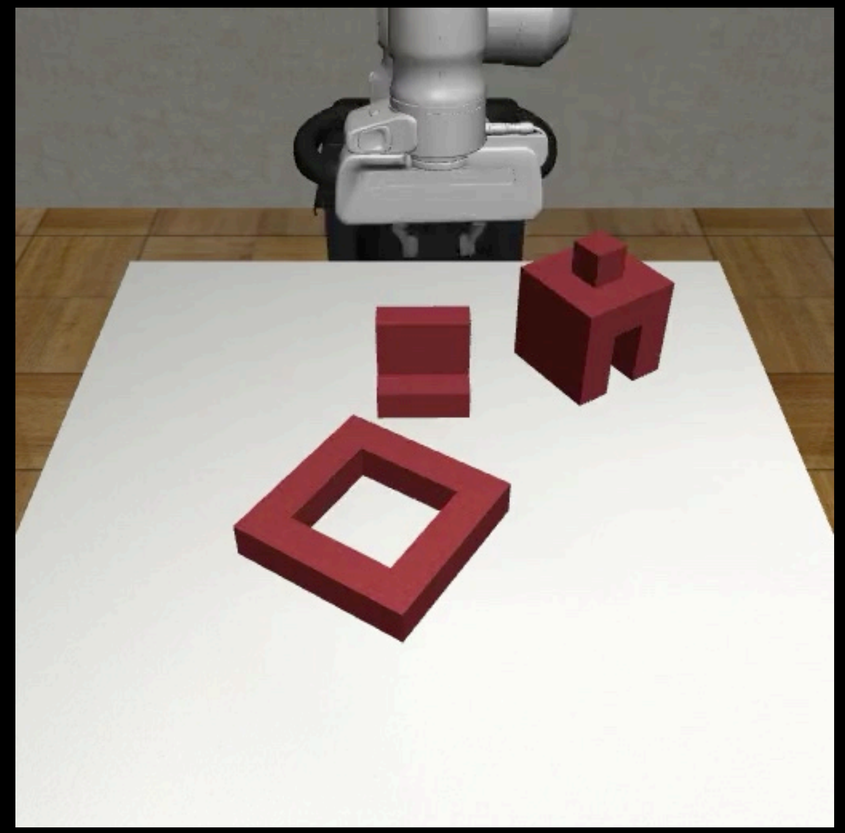
Omniverse


RoboCasa:
Visual
Augmentation
Diverse Motion
Augmentation ??
1 human demo
N



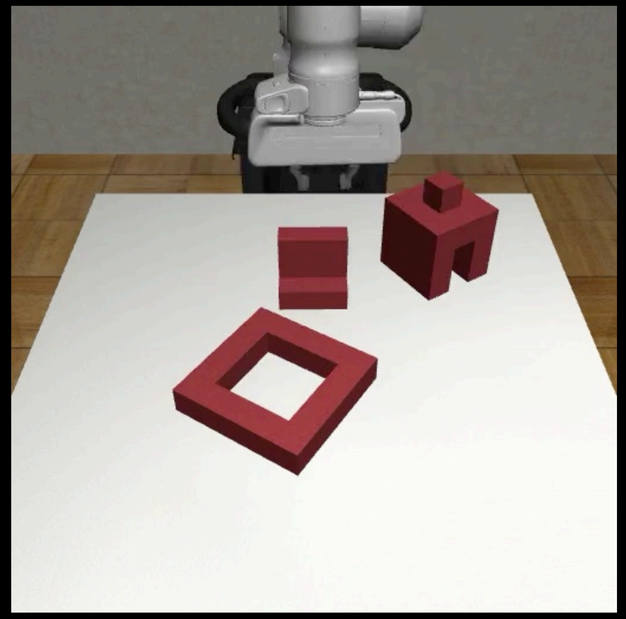
1 human demo (seed)

**MimicGen**

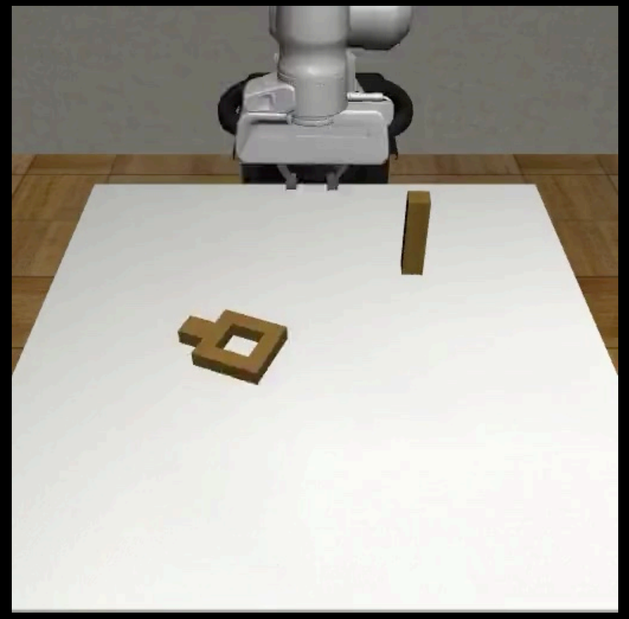


Machine-generated demos

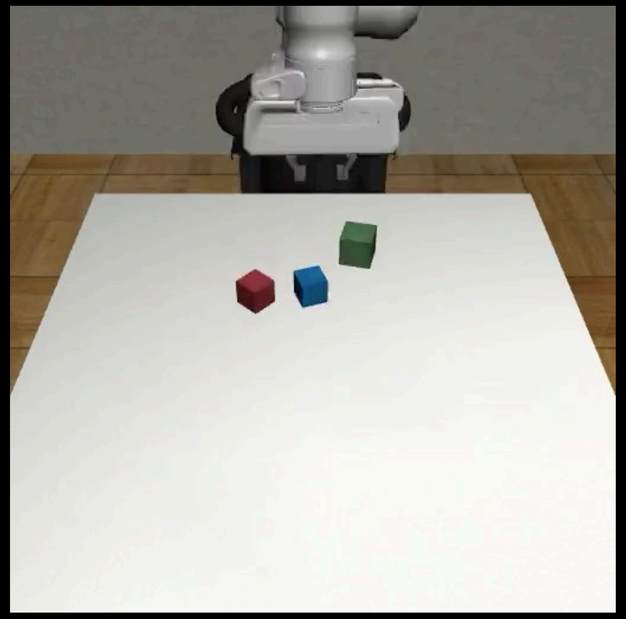
Mandlekar et al. CoRL 2023.



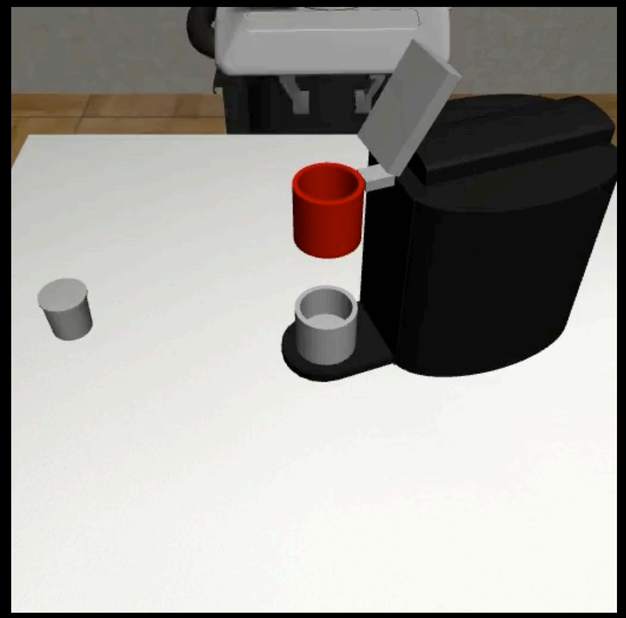
3-Piece Assembly



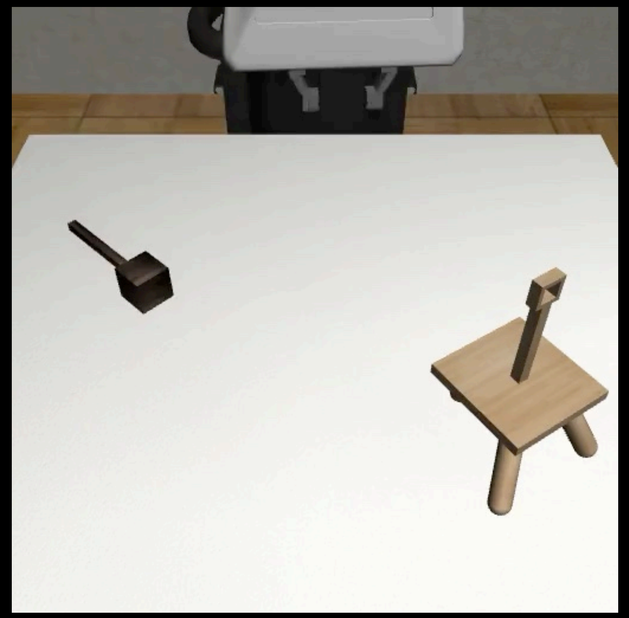
Square Insertion



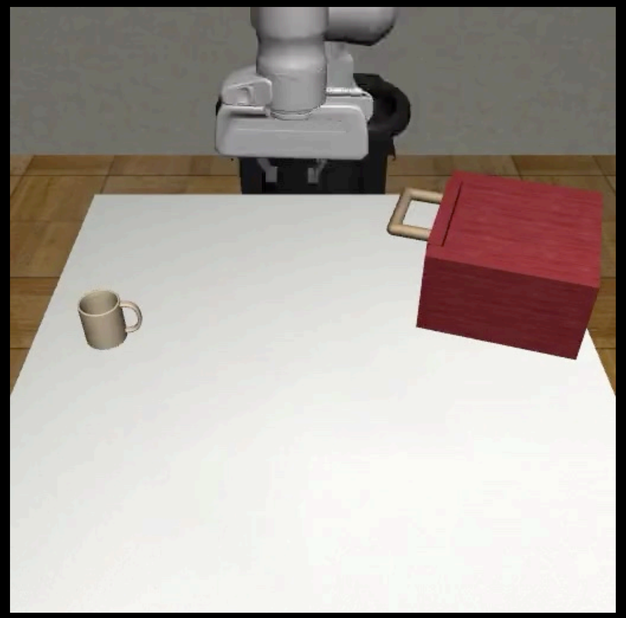
3-Cube Stacking



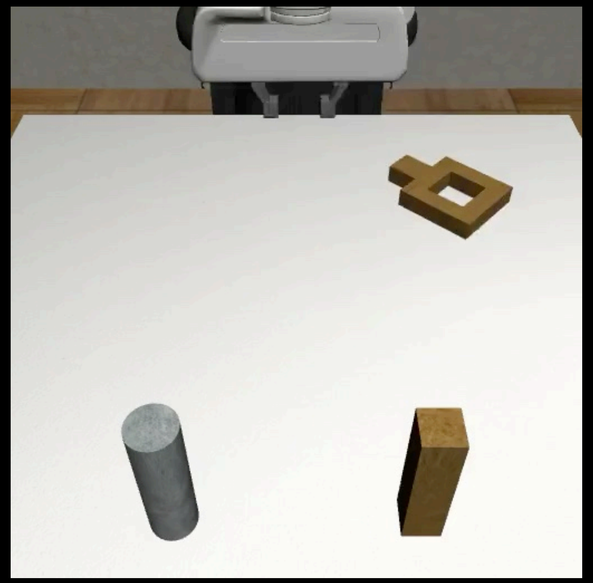
Making Coffee



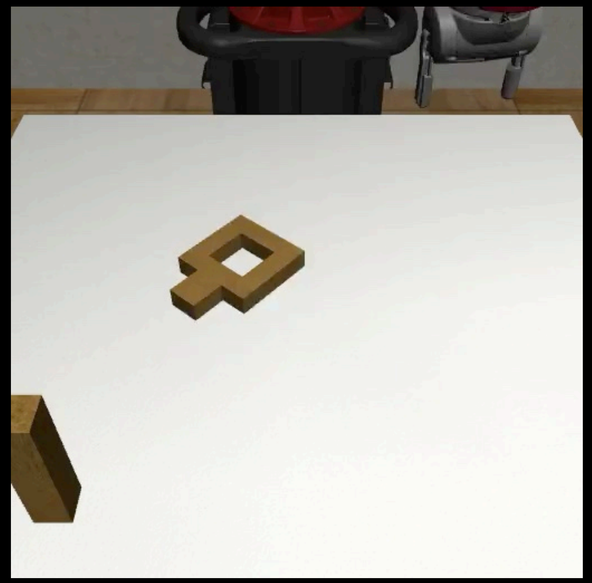
Threading



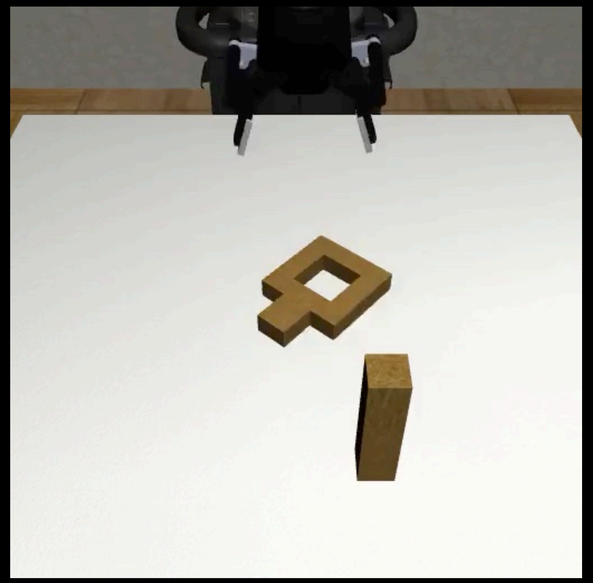
Put Mug in Drawer



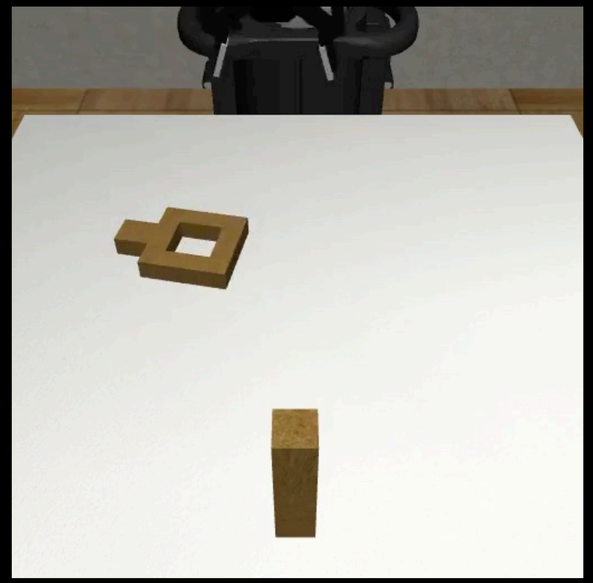
Panda



Sawyer



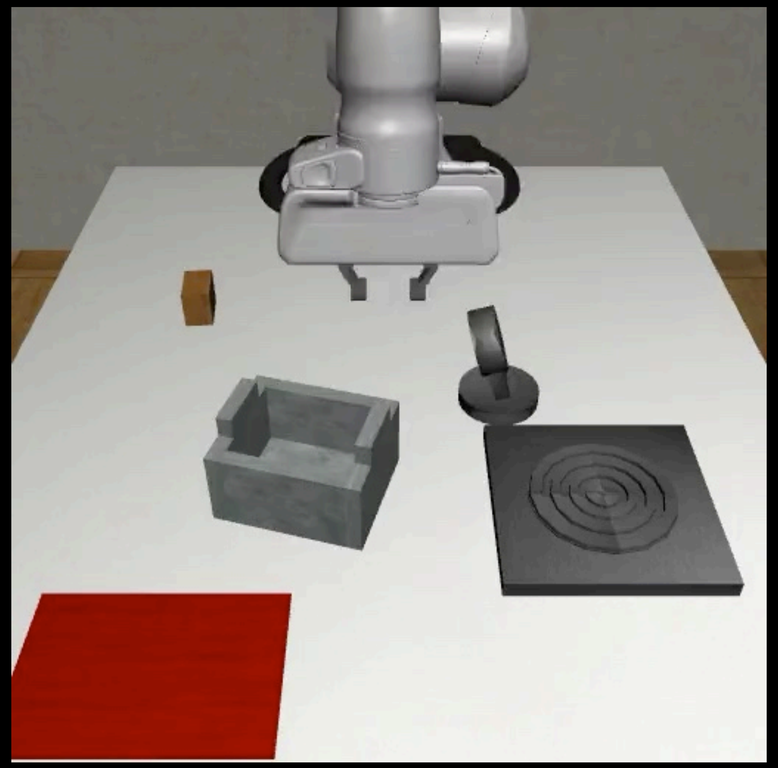
IIWA



UR5e

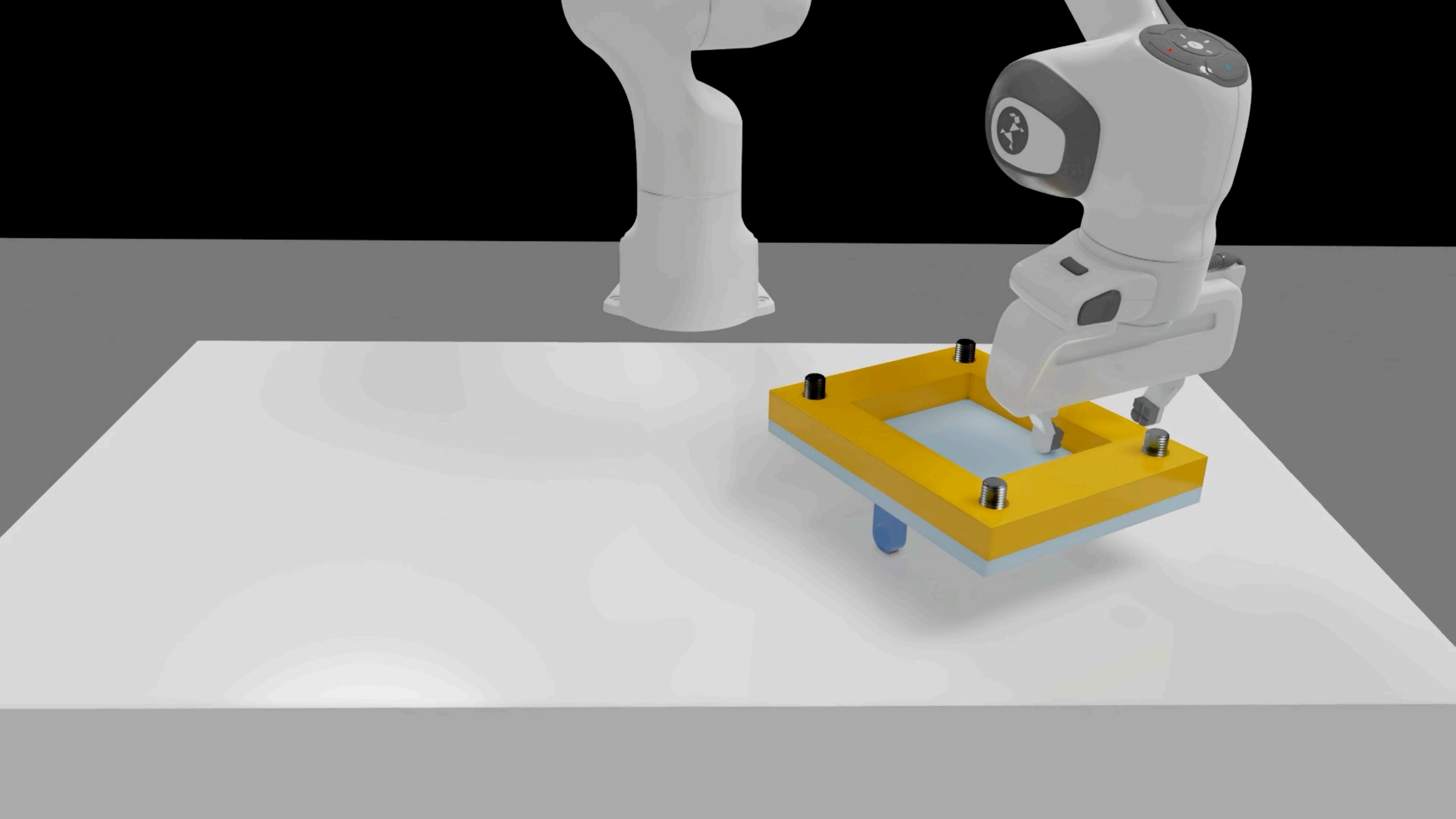
NVIDIA

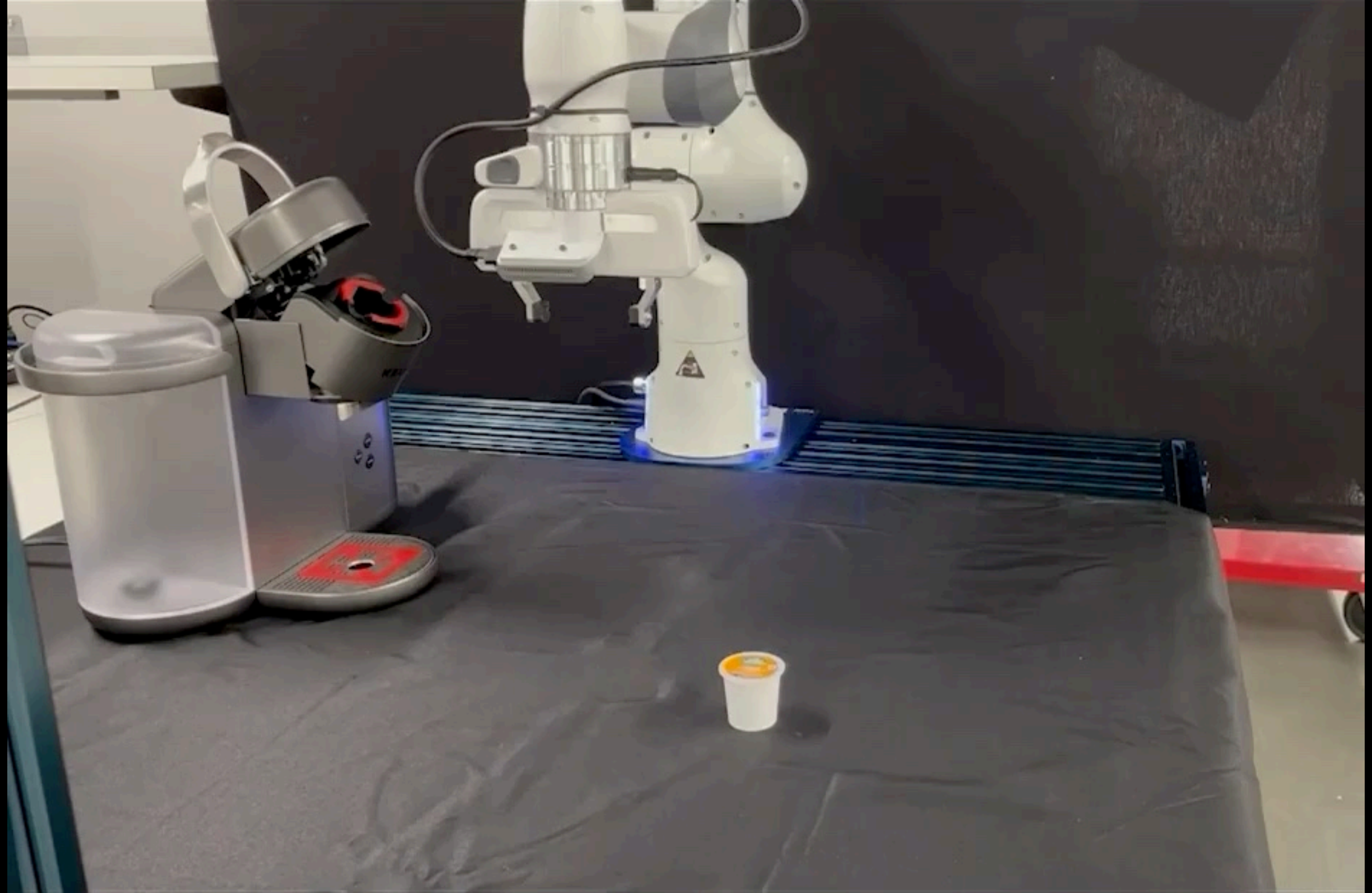
Prepare Coffee

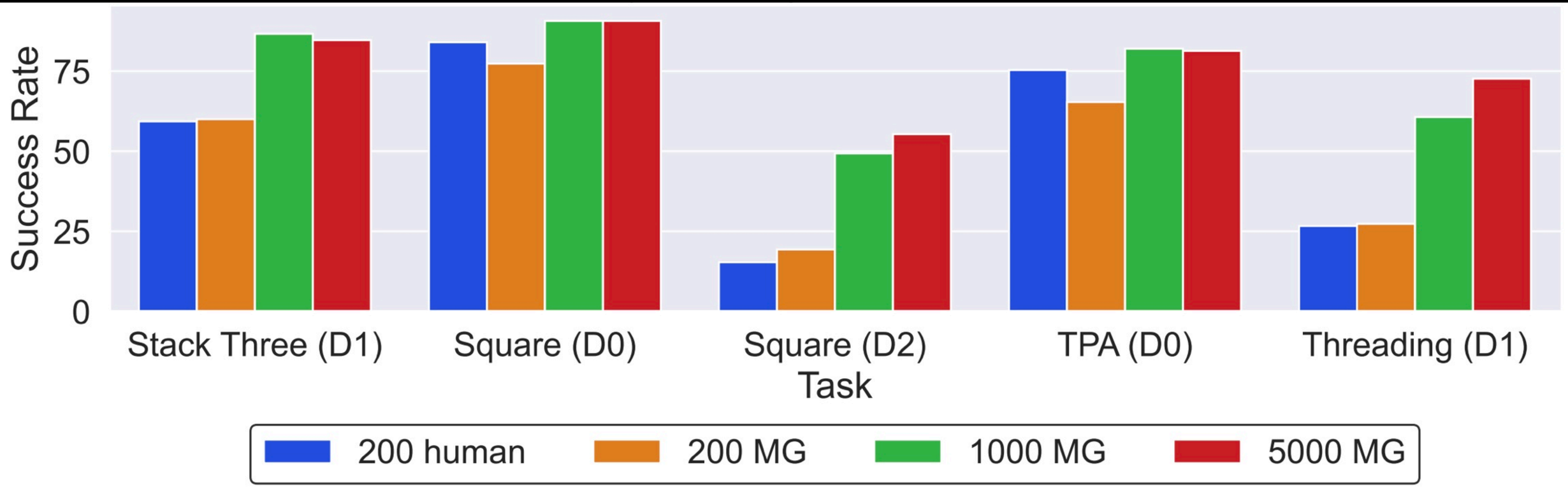


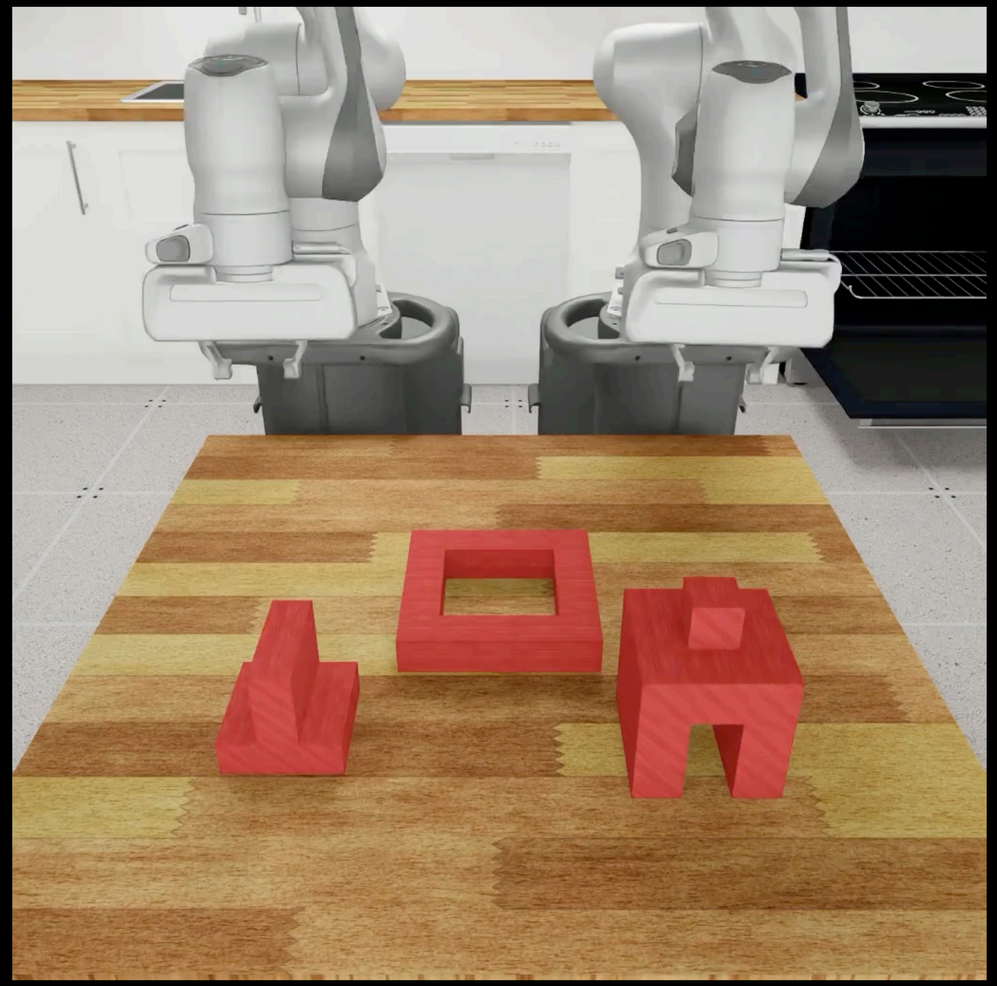
Kitchen Chores

Bin Sorting






Success Rate
0
25
50
75
Stack Three (D1)
Square (D0)
Square (D2)
TPA (D0)
Threading (D1)
Task
200 human
200 MG
1000 MG
5000 MG



Bimanual: **parallel** sub-tasks

- Asynchronous execution

Jiang & Xie et al. 2024.

Bimanual: **coordination** sub-tasks

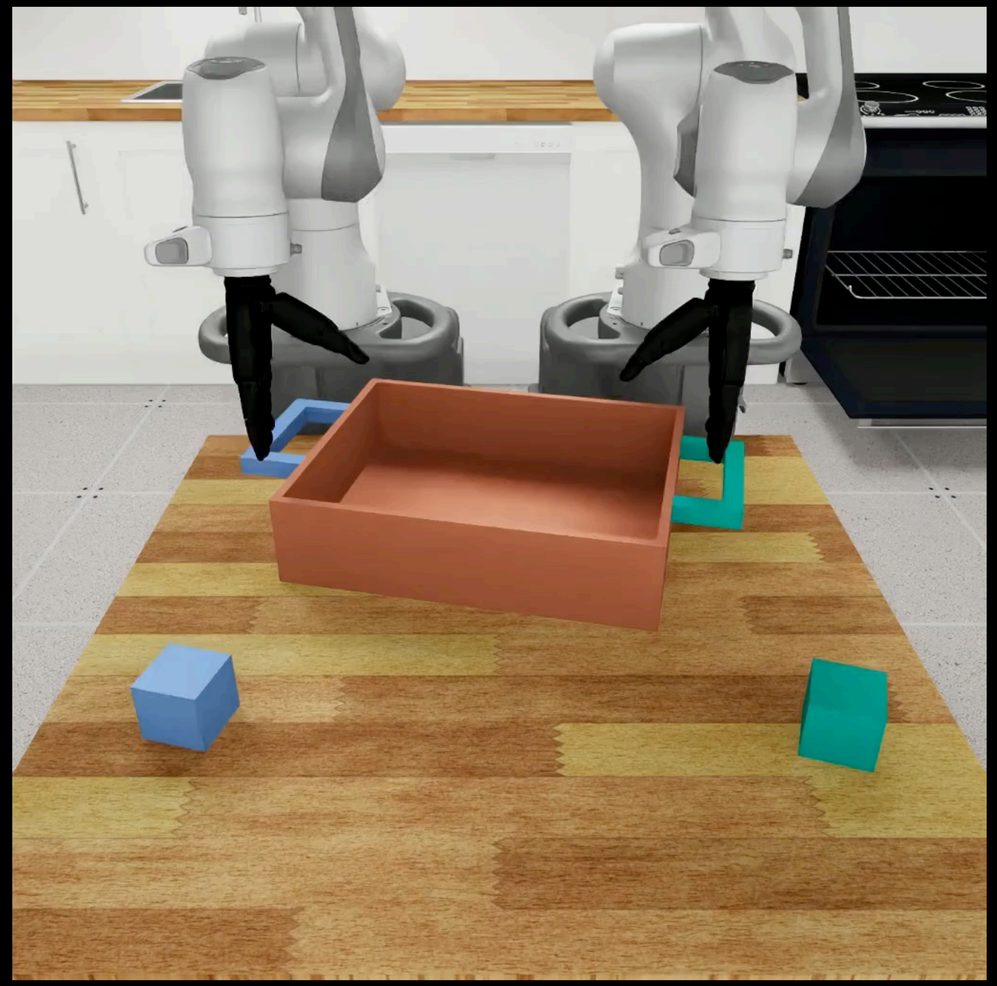
- Must apply same transformations
- Synchronization point

Jiang & Xie et al. 2024.

Bimanual: **sequential** sub-tasks

- Ordering constraint: pre-task, post-task

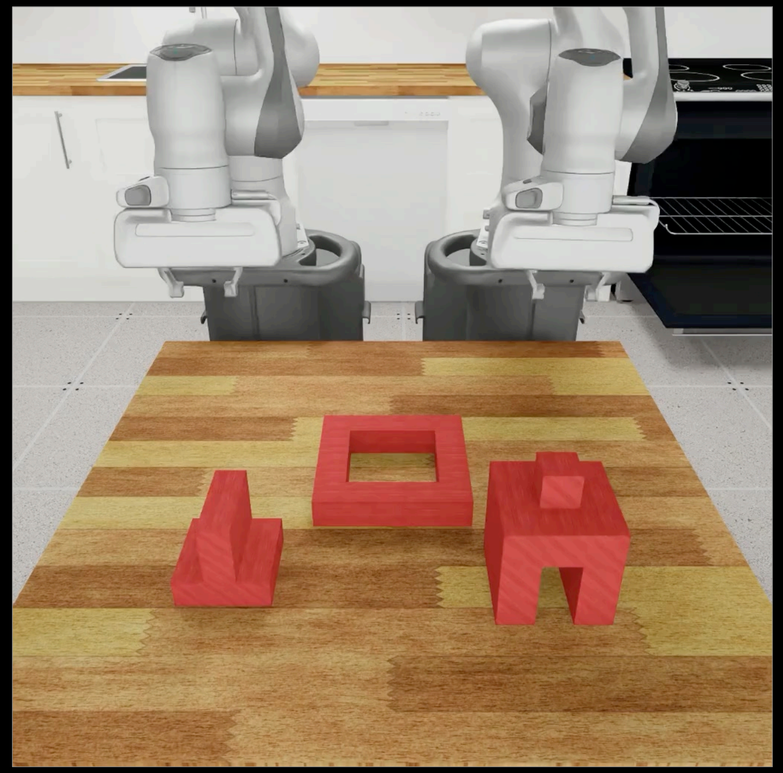
Jiang & Xie et al. 2024.



Sub-task strategies can mix & match

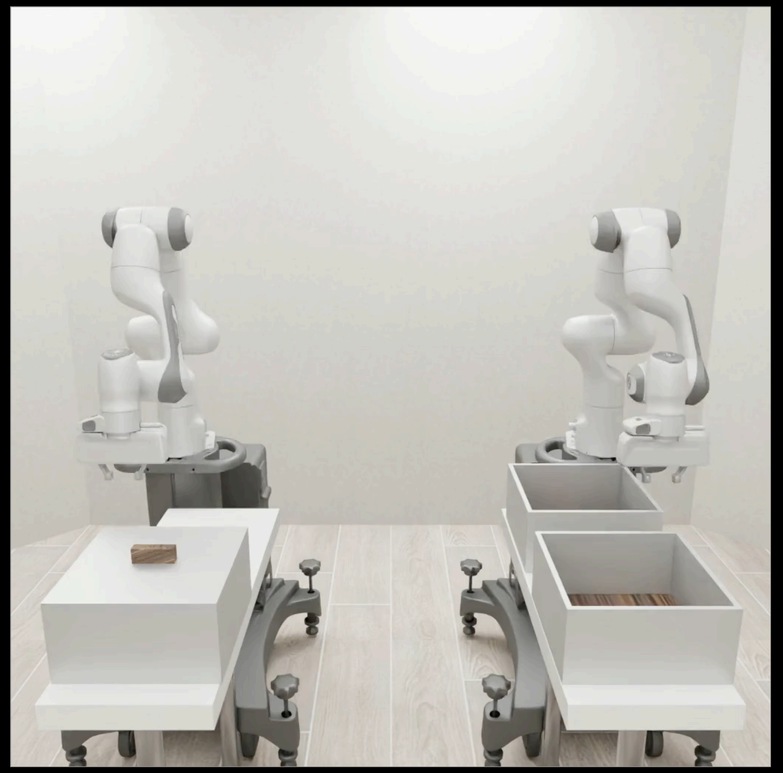
**Parallel** then **Coordination**.

Jiang & Xie et al. 2024.



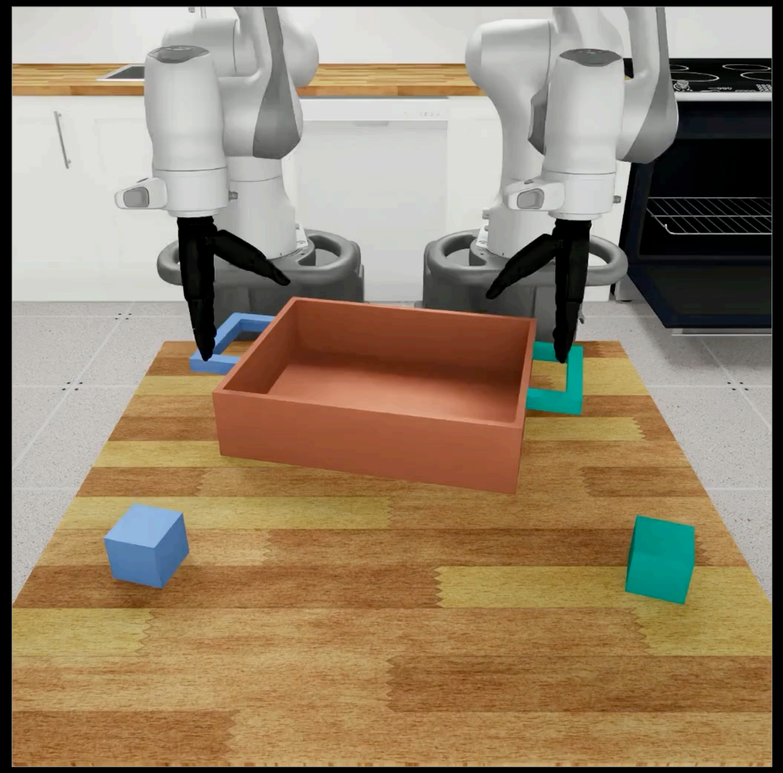
2-Gripper Piece Assembly

2-Gripper Transport

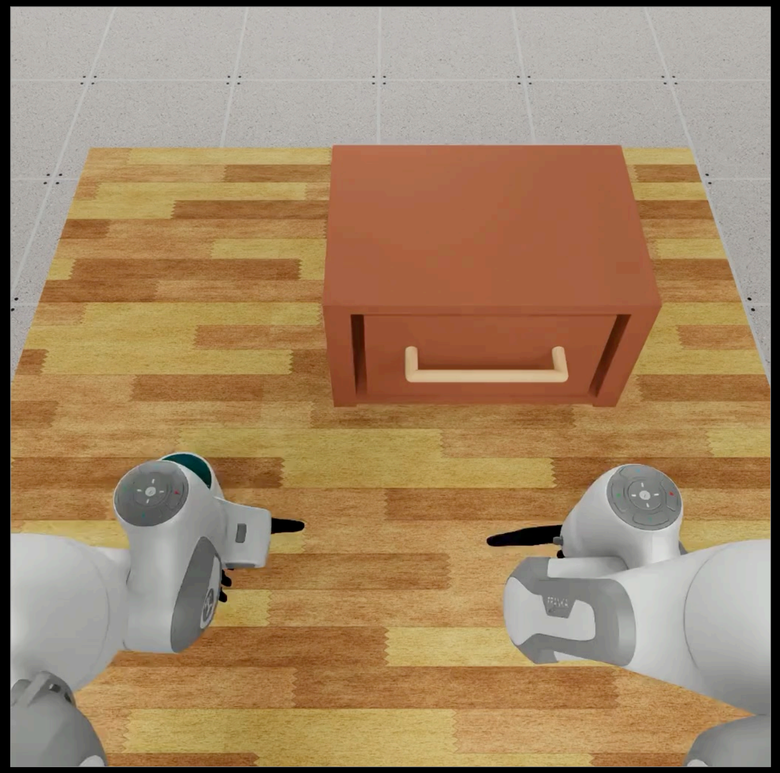


2-Gripper Threading

2-Hand Putting Box Lid



2-Hand Tray Lifting



2-Hand Drawer Cleanup

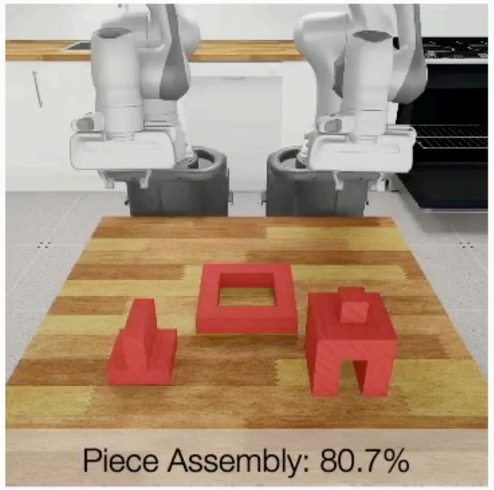
Humanoid Making Coffee

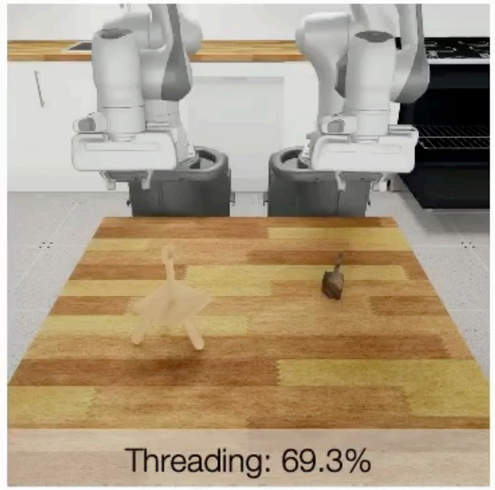
Humanoid Sorting Cans

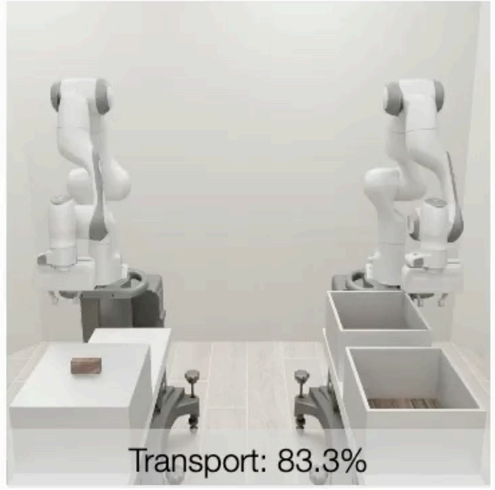
Humanoid Pouring

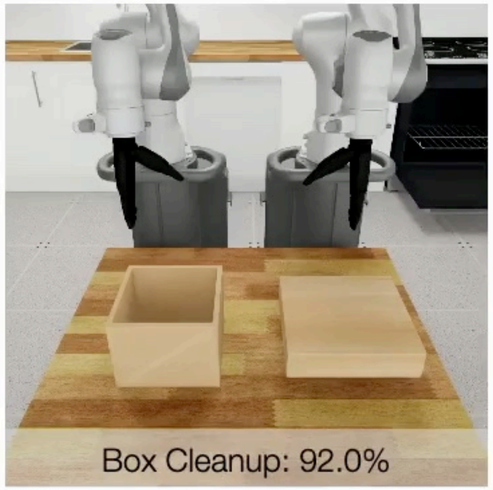
DexMimicGen

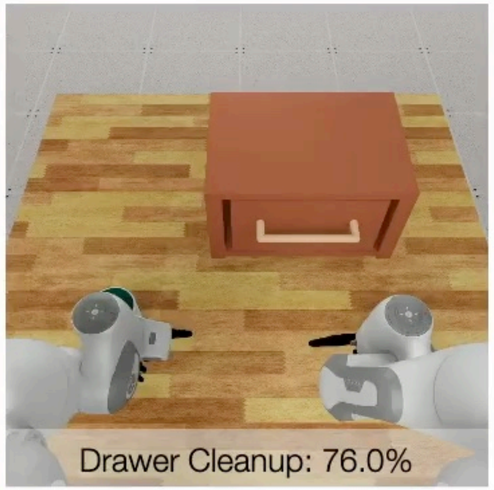
# Behavior cloning on DexMimicGen data trains performant policies.

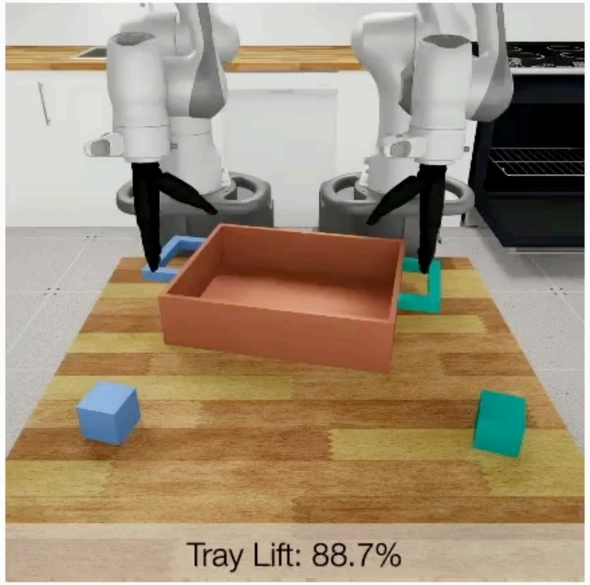

Piece Assembly: 80.7%

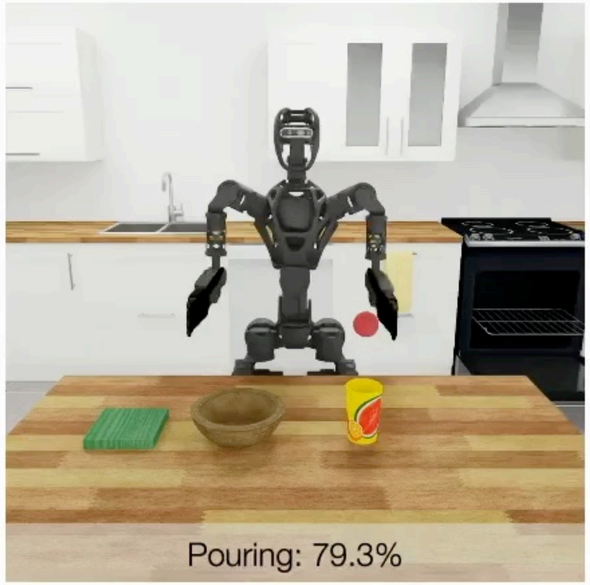

Threading: 69.3%


Transport: 83.3%

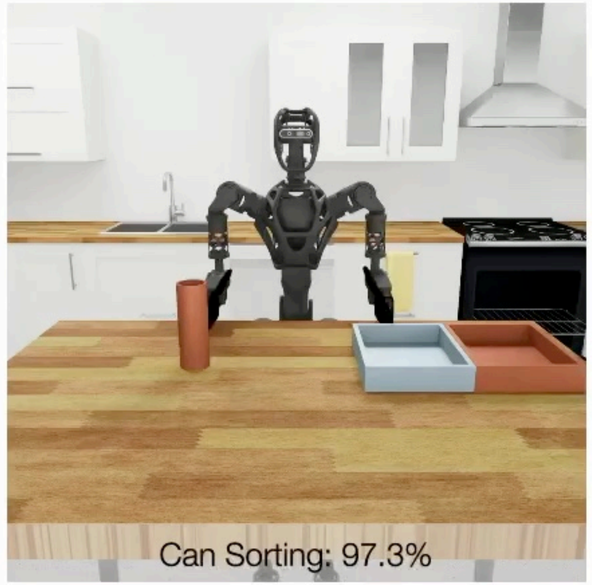

Box Cleanup: 92.0%


Drawer Cleanup: 76.0%

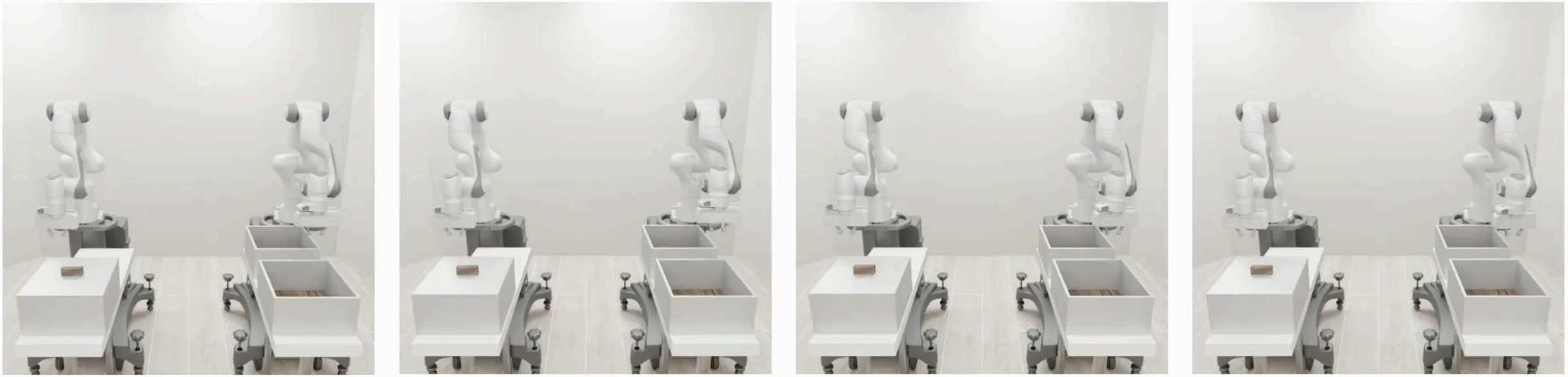

Tray Lift: 88.7%

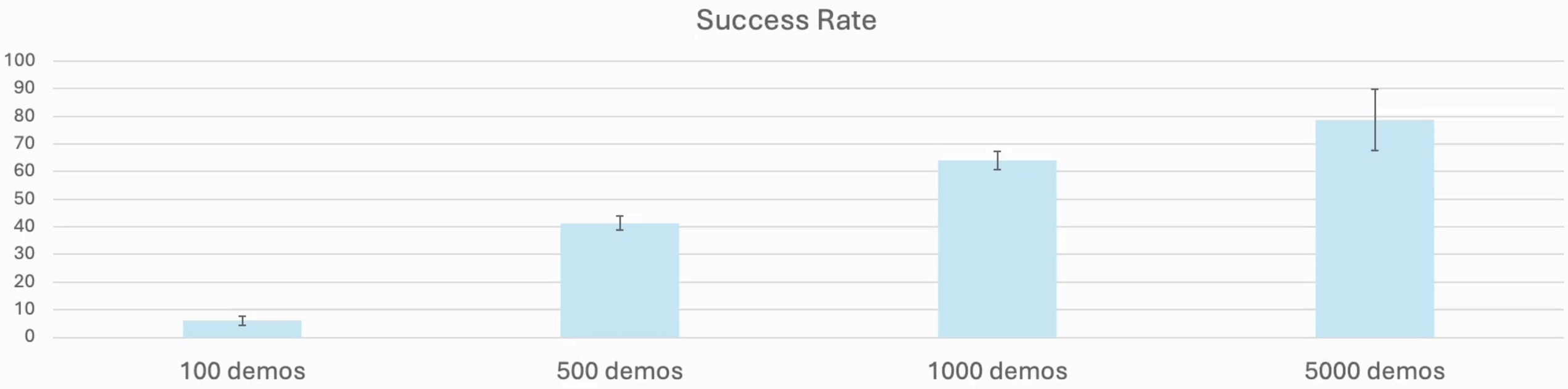

Pouring: 79.3%

Coffee: 77.3%


Can Sorting: 97.3%

Success rates of Diffusion Policy

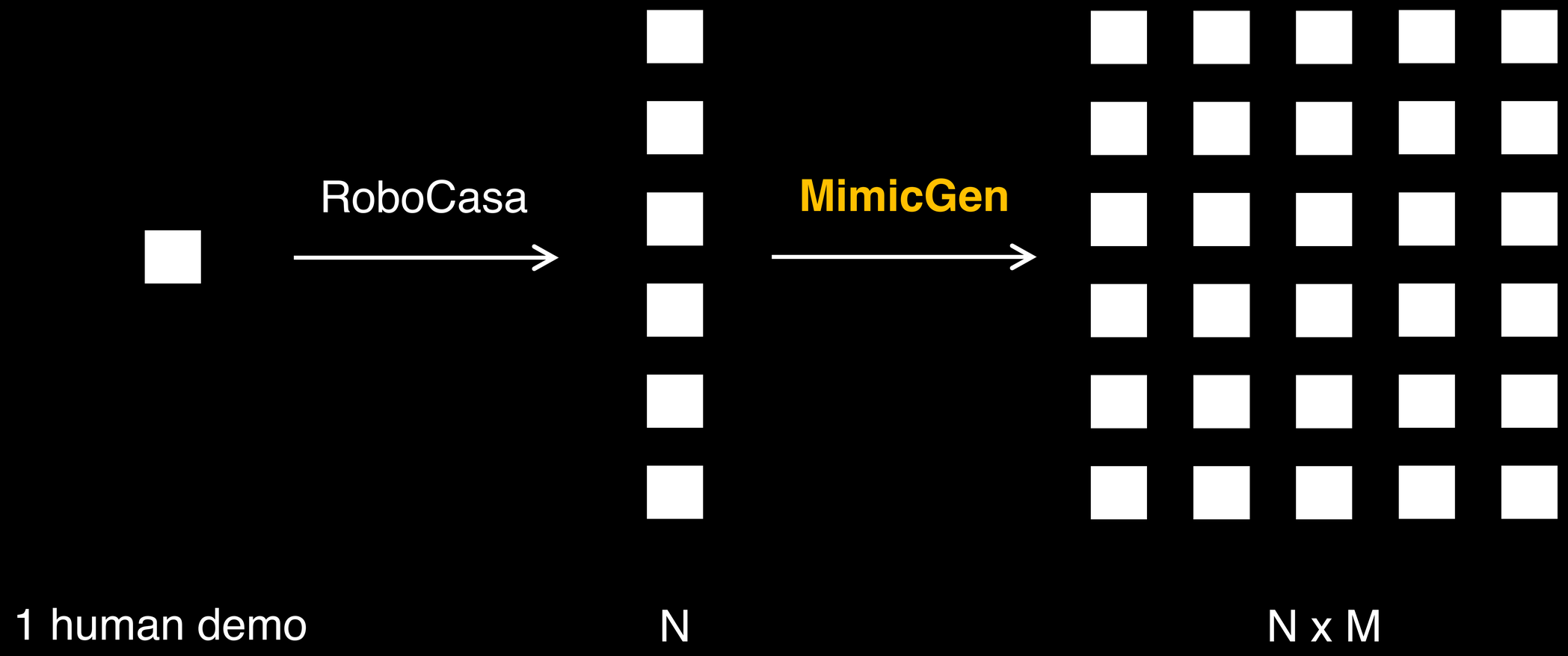



Success Rate
100
90
80
70
60
50
40
30
20
10
0
100 demos
500 demos
1000 demos
5000 demos

Transfer real demo to sim using digital twin to ensure the sim demos are valid in real

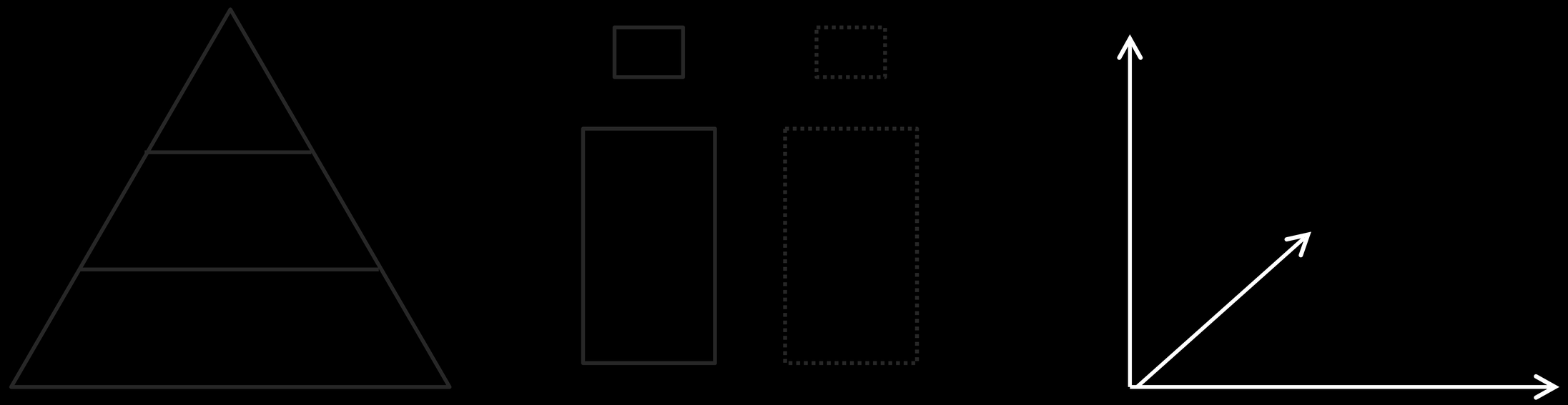
Transfer real demo to sim using digital twin to ensure the sim demos are valid in real

Transfer real demo to sim using digital twin to ensure the sim demos are valid in real


RoboCasa
MimicGen
1 human demo
N
N x M

The training data was collected
via human teleoperation

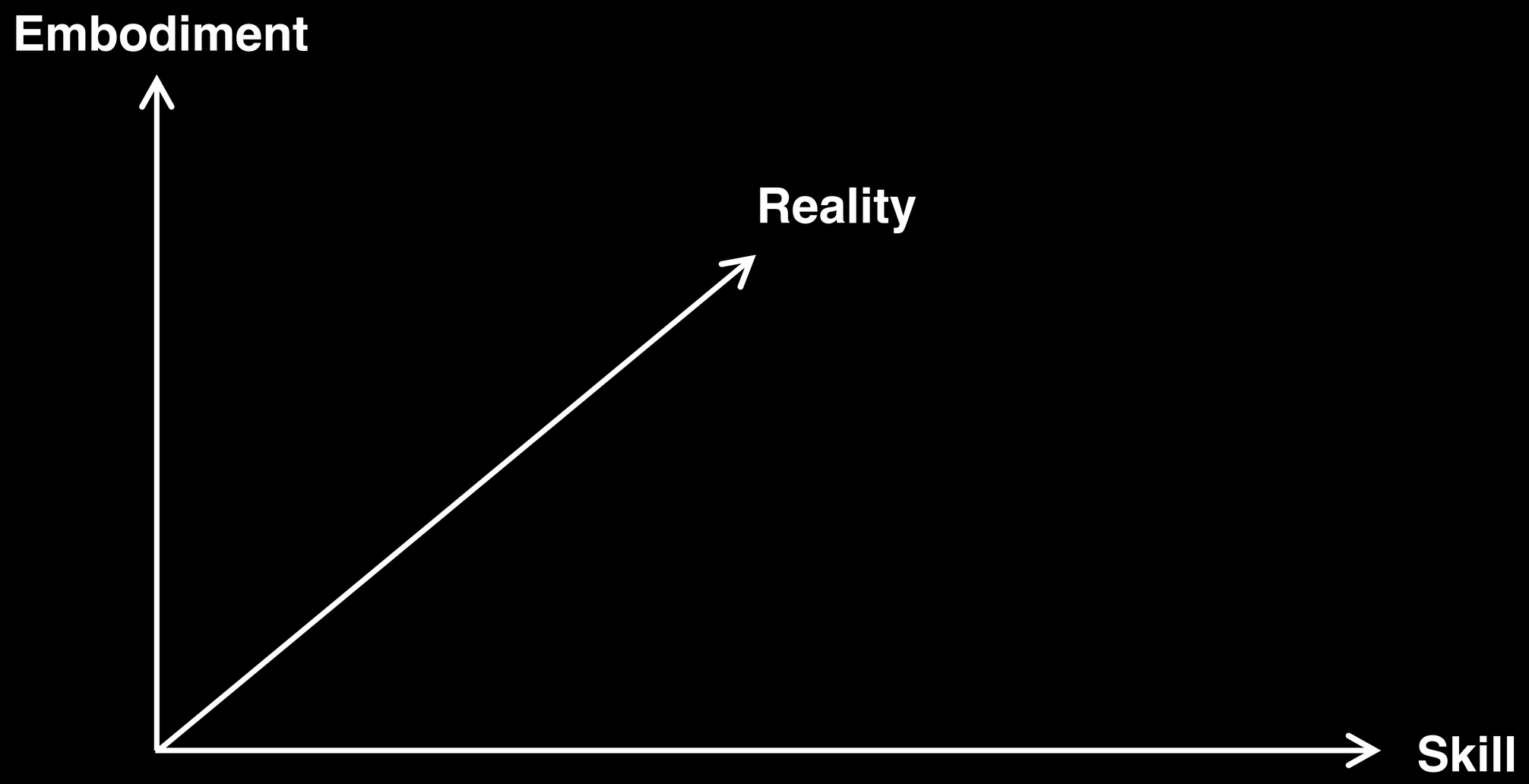
# Principle No. 3



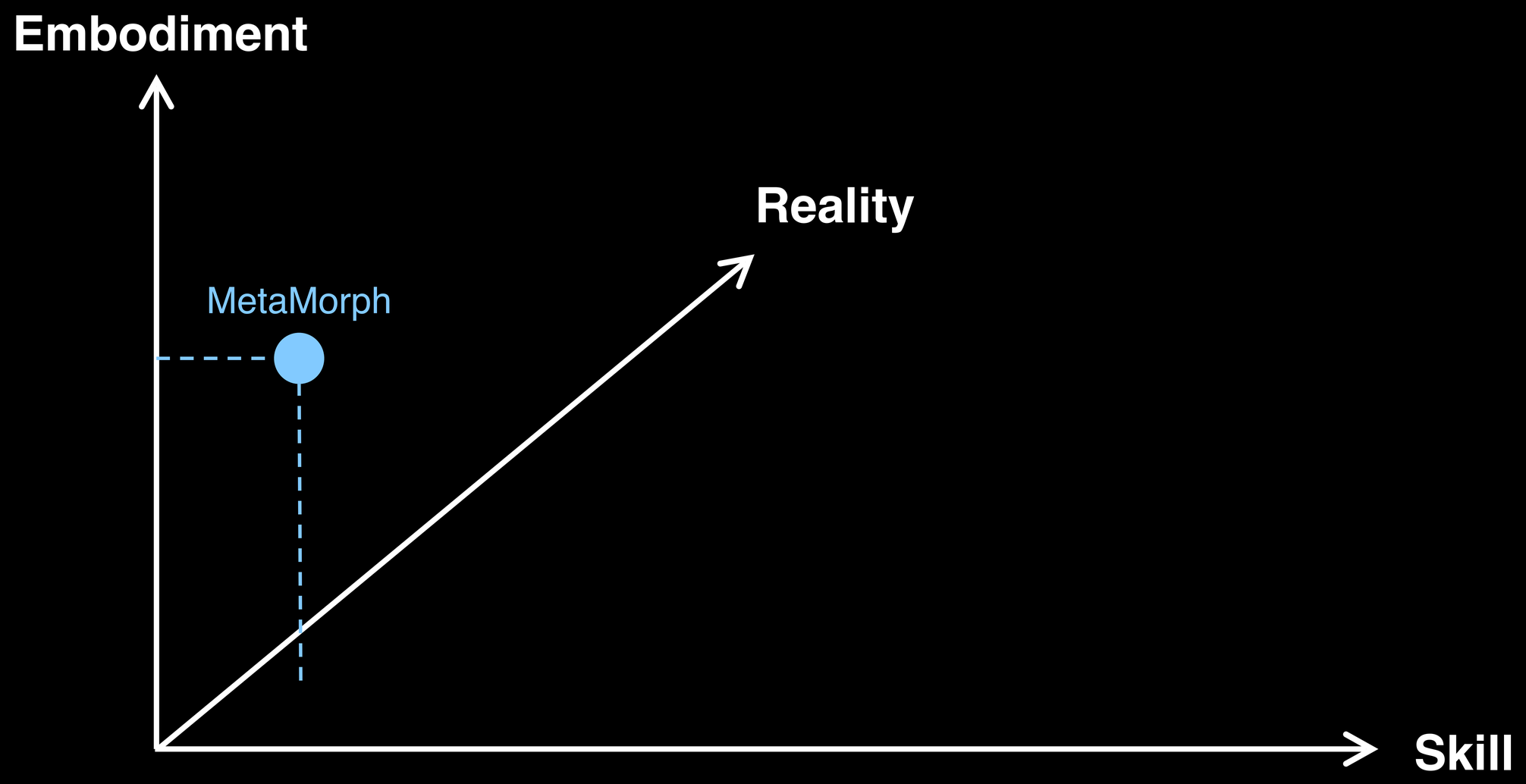
Data Pyramid

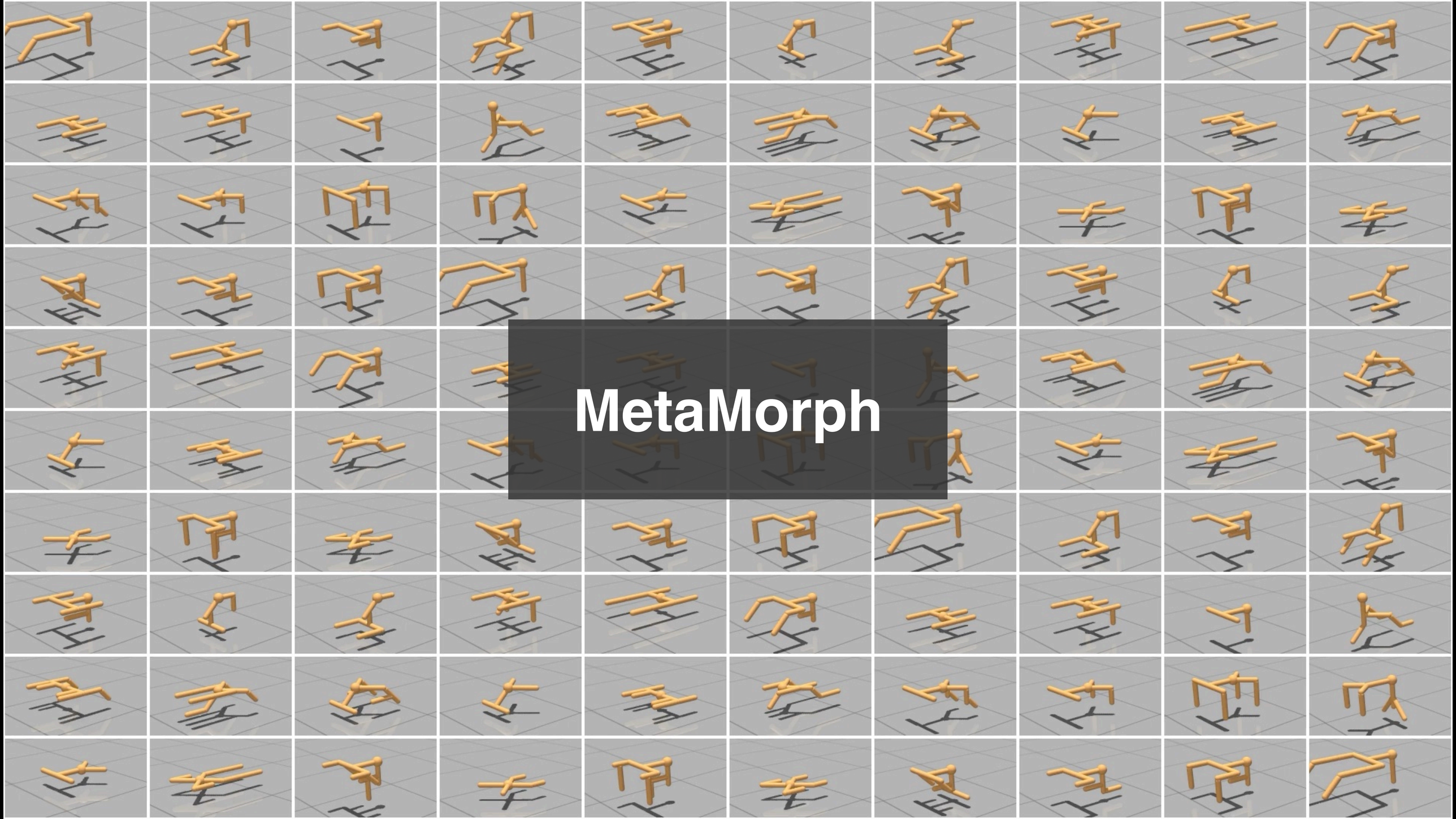
*“The Matrix”*

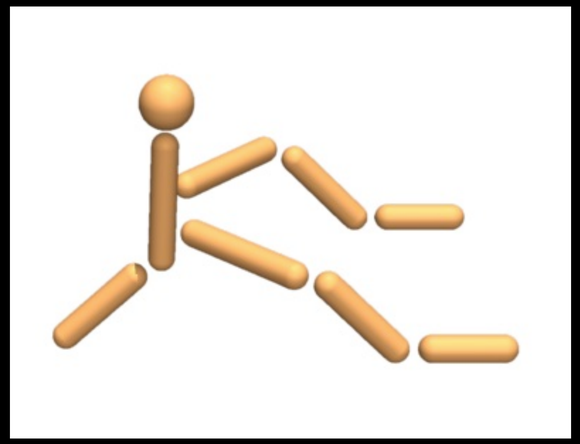
Foundation Agent


Embodiment
Reality
Skill

Diverse Robot Forms (“Embodiments”)

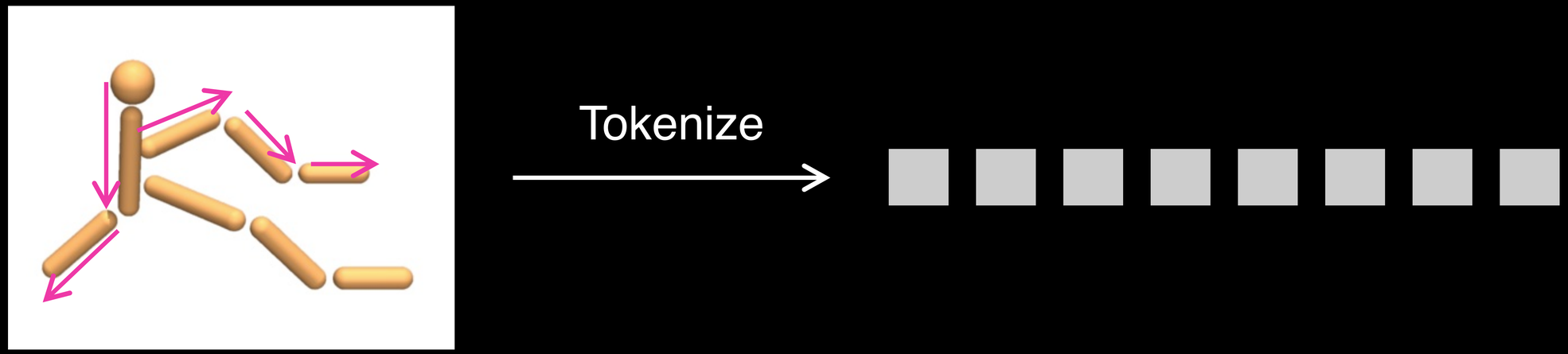

Embodiment
Reality
MetaMorph
Skill


MetaMorph

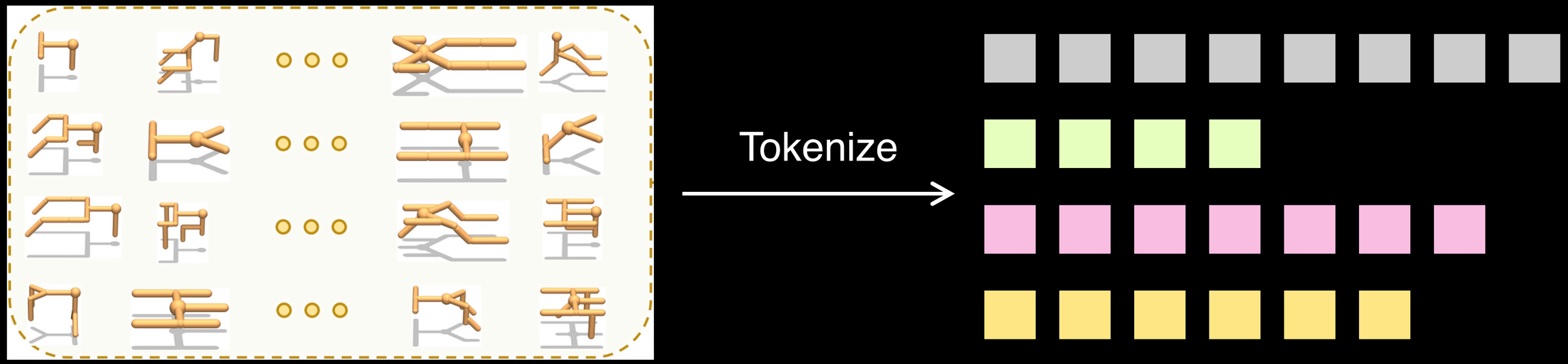


Graph of joints
“Kinematic tree”

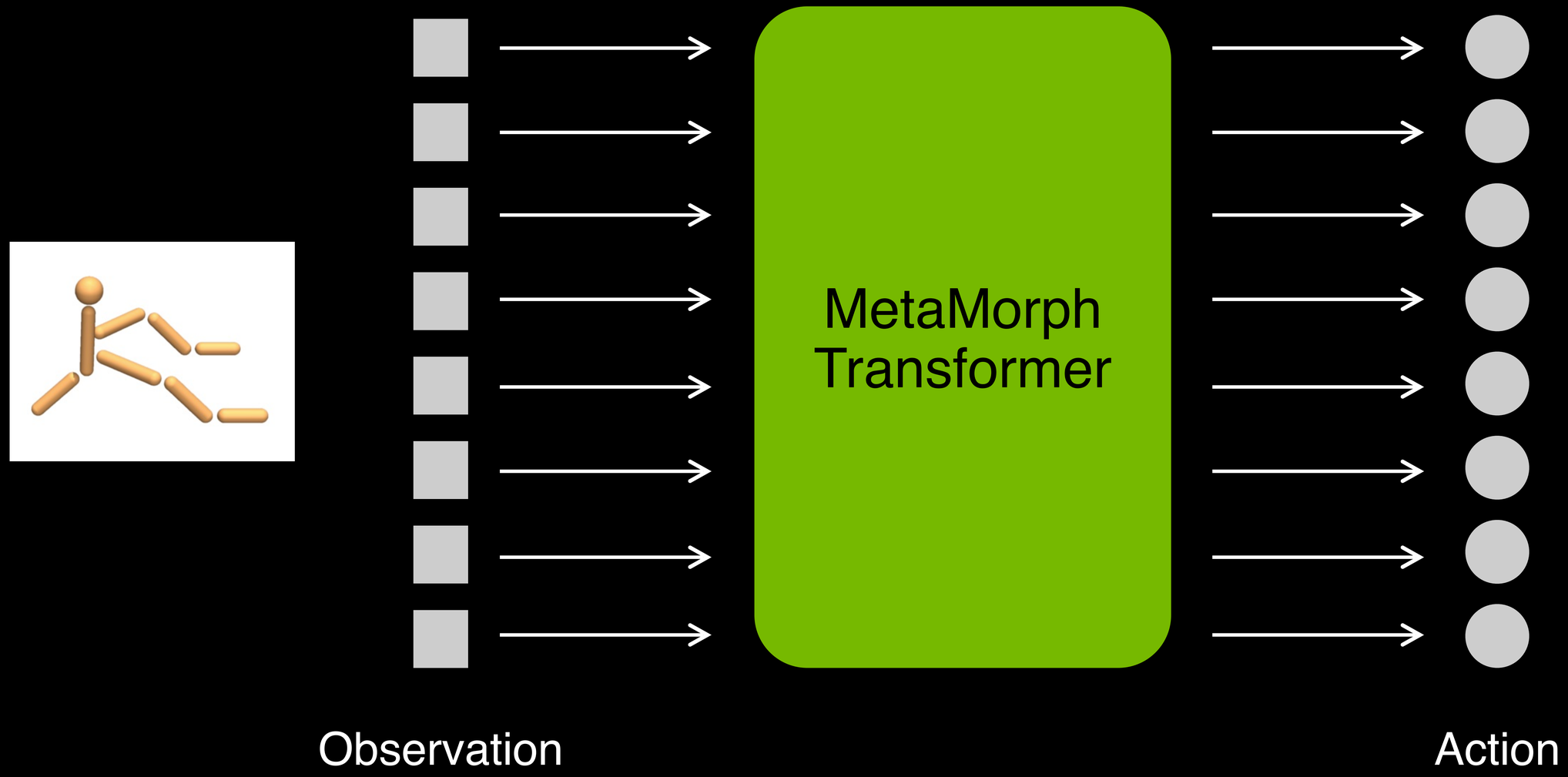
Gupta et al. ICLR 2022.

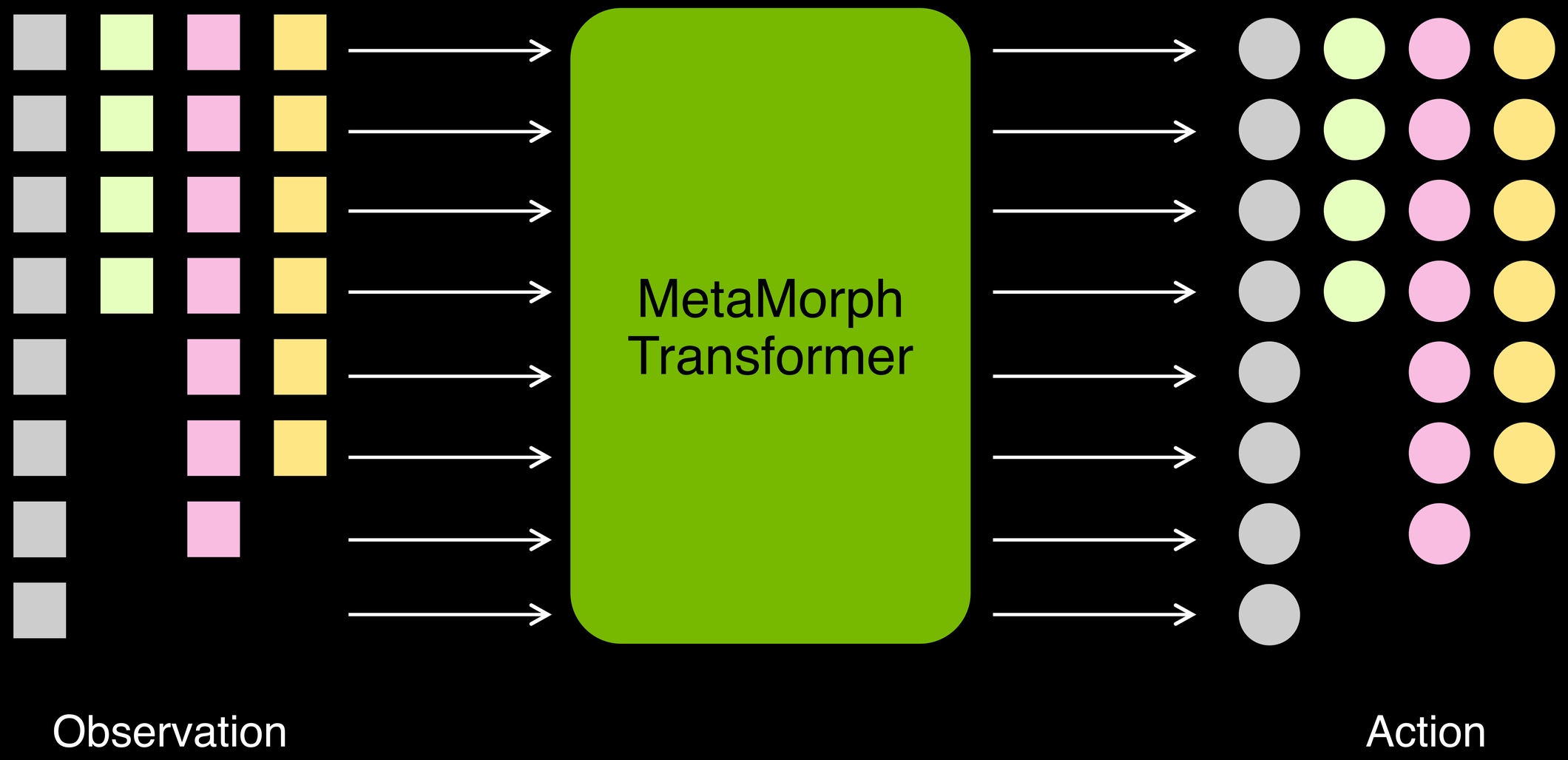



Gupta et al. ICLR 2022.




Gupta et al. ICLR 2022.


MetaMorph
Transformer
Observation
Action


MetaMorph
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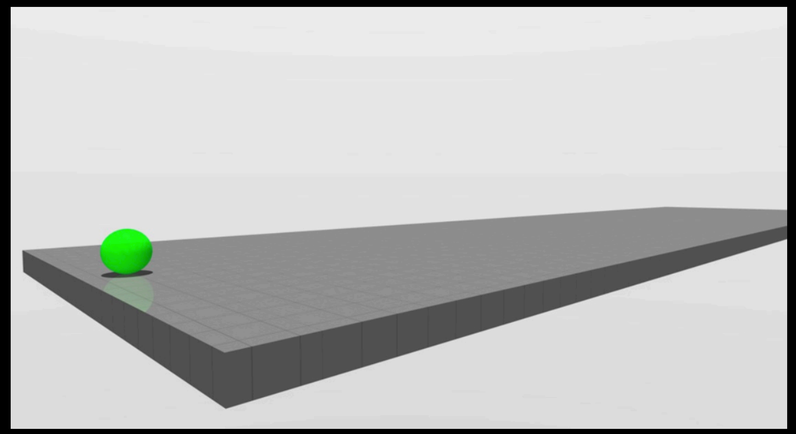
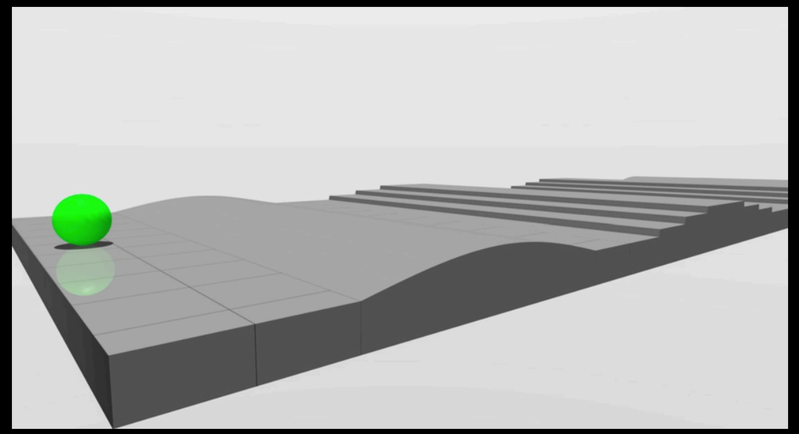
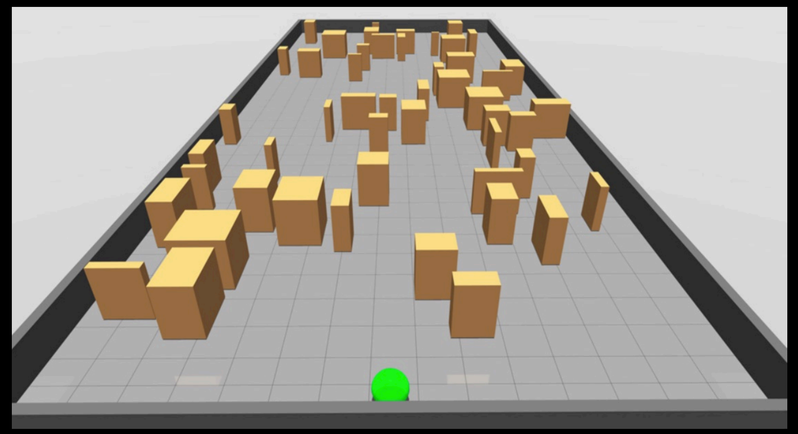


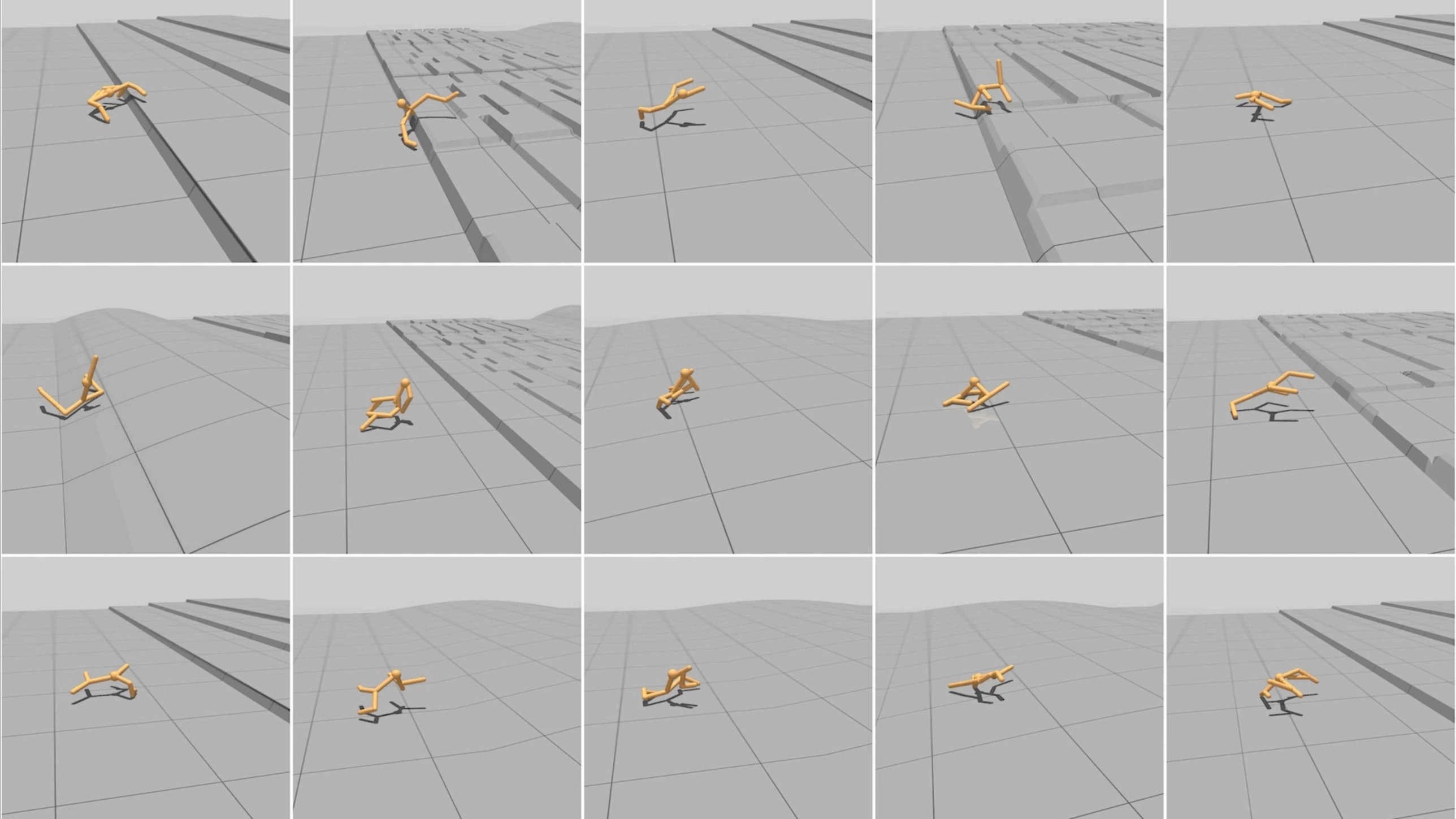
Flat Terrain

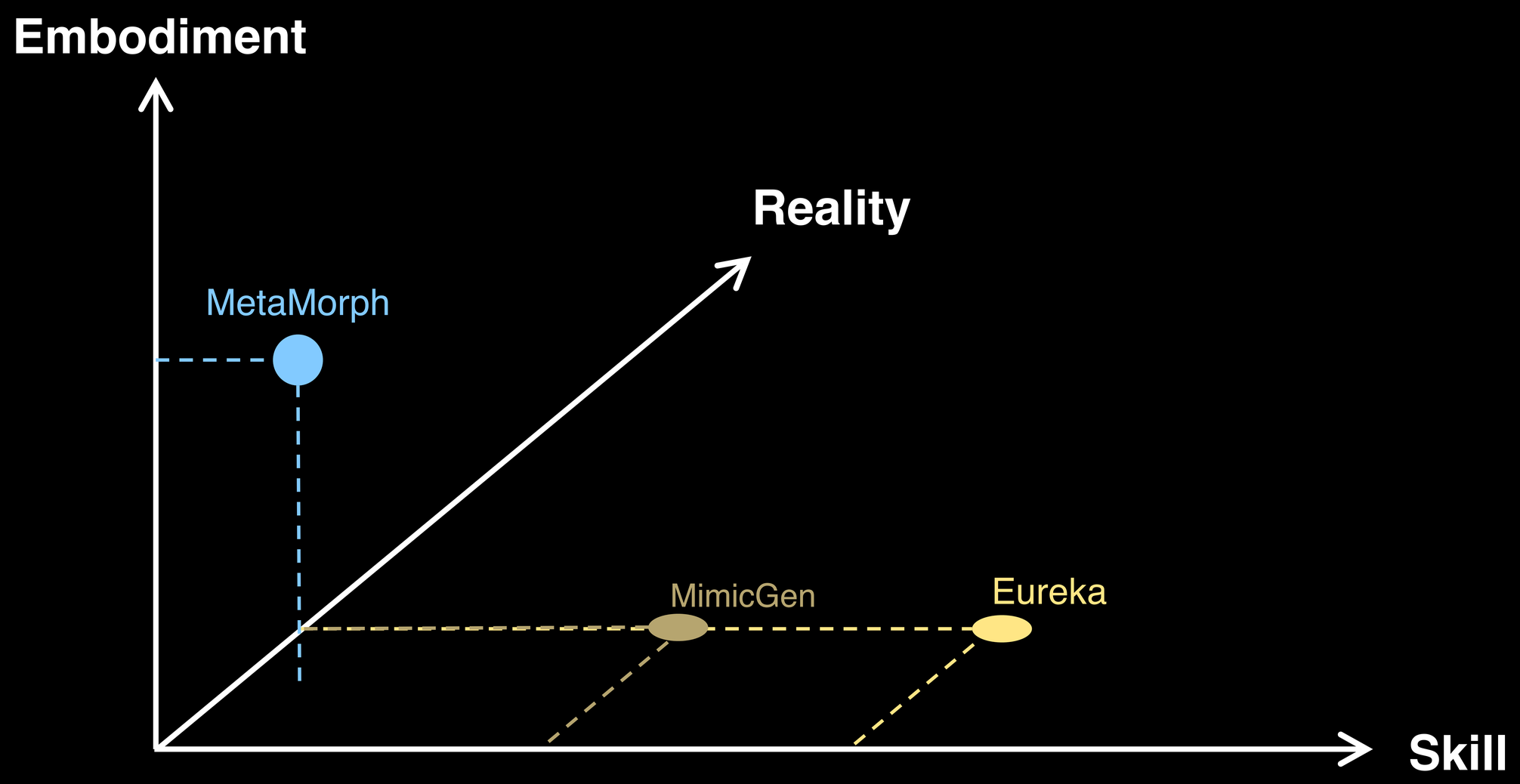


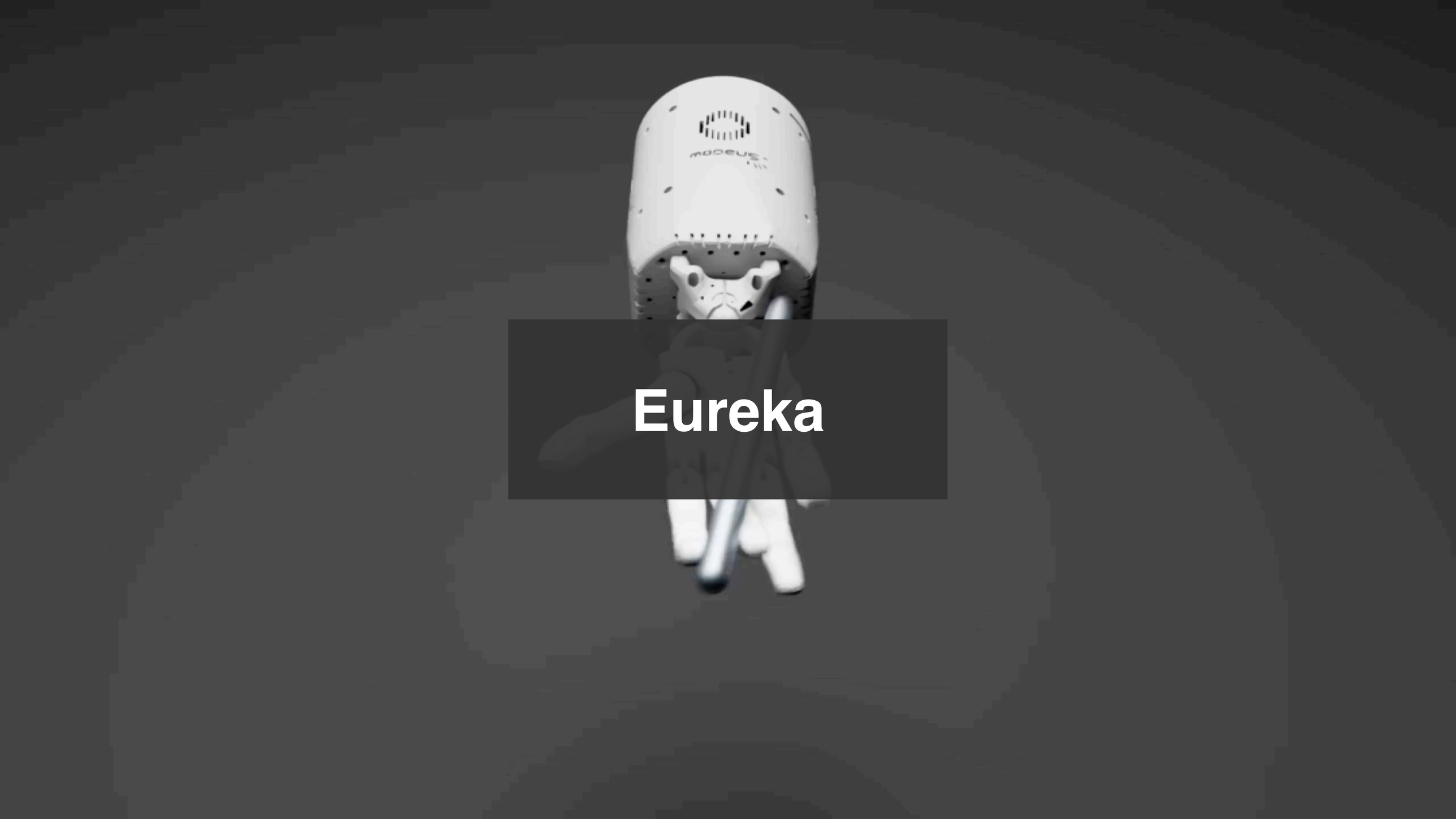
Complex Terrain



Obstacles

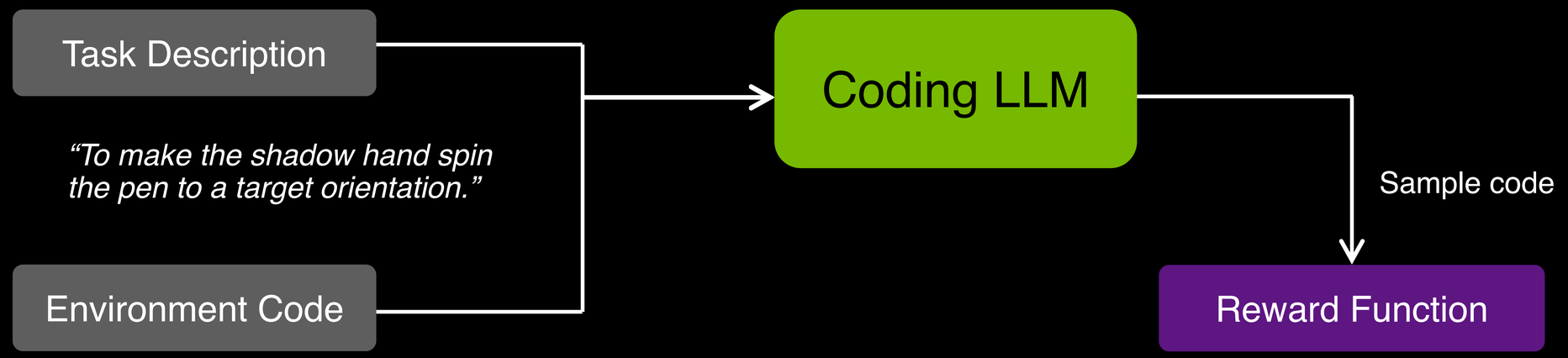



Embodiment
Reality
MetaMorph
MimicGen
Eureka
Skill


Eureka

```python
class ShadowHandPenSpin(VecTask):
    def compute_observations(self):
        self.obj_pose = ...
        self.obj_pos = ...
        self.obj_rot = ...
        self.obj_linvel = ...
        self.obj_angvel = ...

        self.tgt_pose = ...
        self.tgt_pos = ...
        self.tgt_rot = ...

        self.fingertip_state = ...
        self.fingertip_pos = ...

        self.compute_full_state()

    def compute_full_state(self):
        ...
```

Ma et al. ICLR 2024.




```python
class ShadowHandPenSpin(VecTask):
    def compute_observations(self):
        self.obj_pose = ...
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        self.obj_rot = ...
        self.obj_linvel = ...
        self.obj_angvel = ...

        self.tgt_pose = ...
        self.tgt_pos = ...
        self.tgt_rot = ...
```
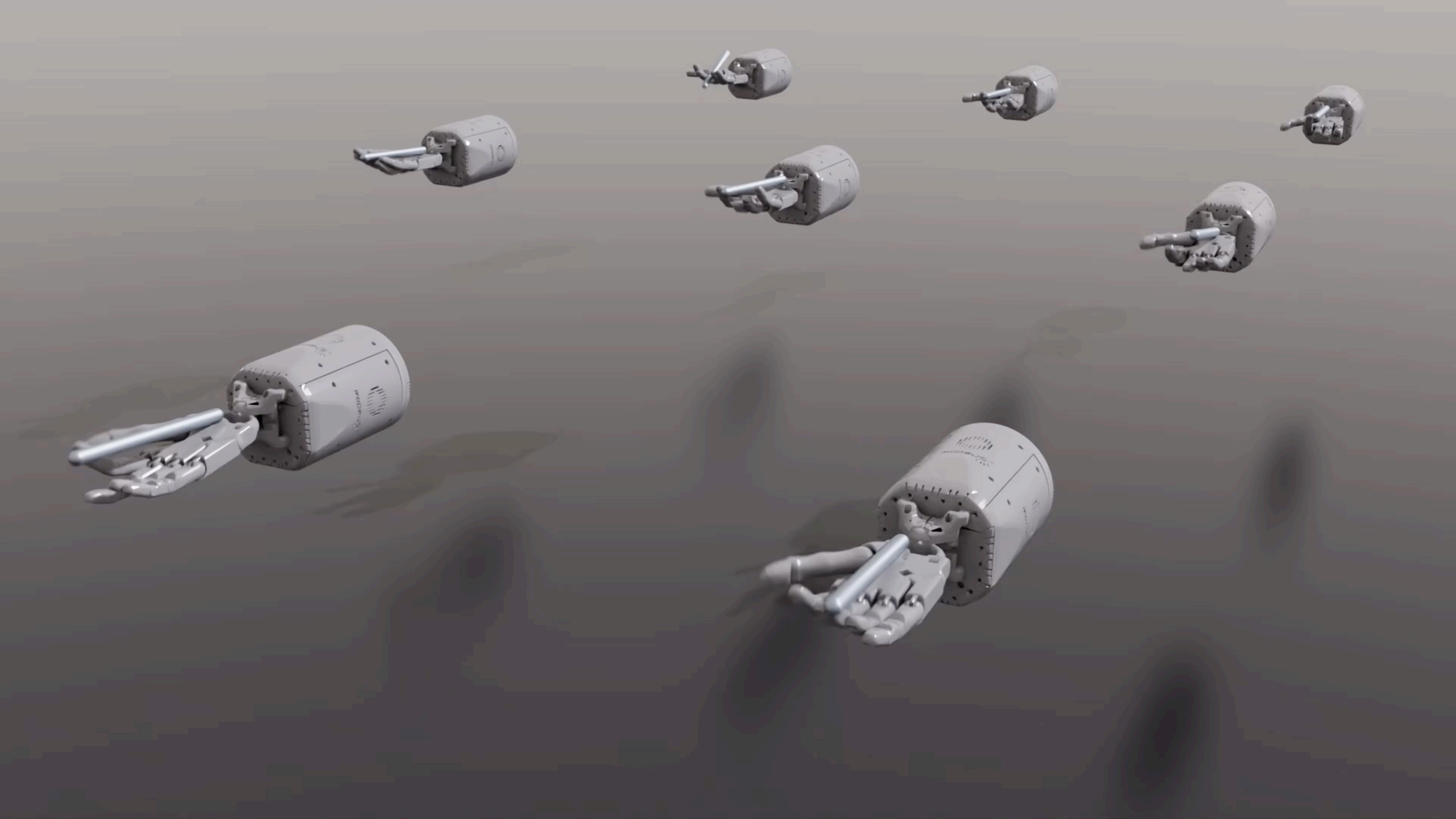
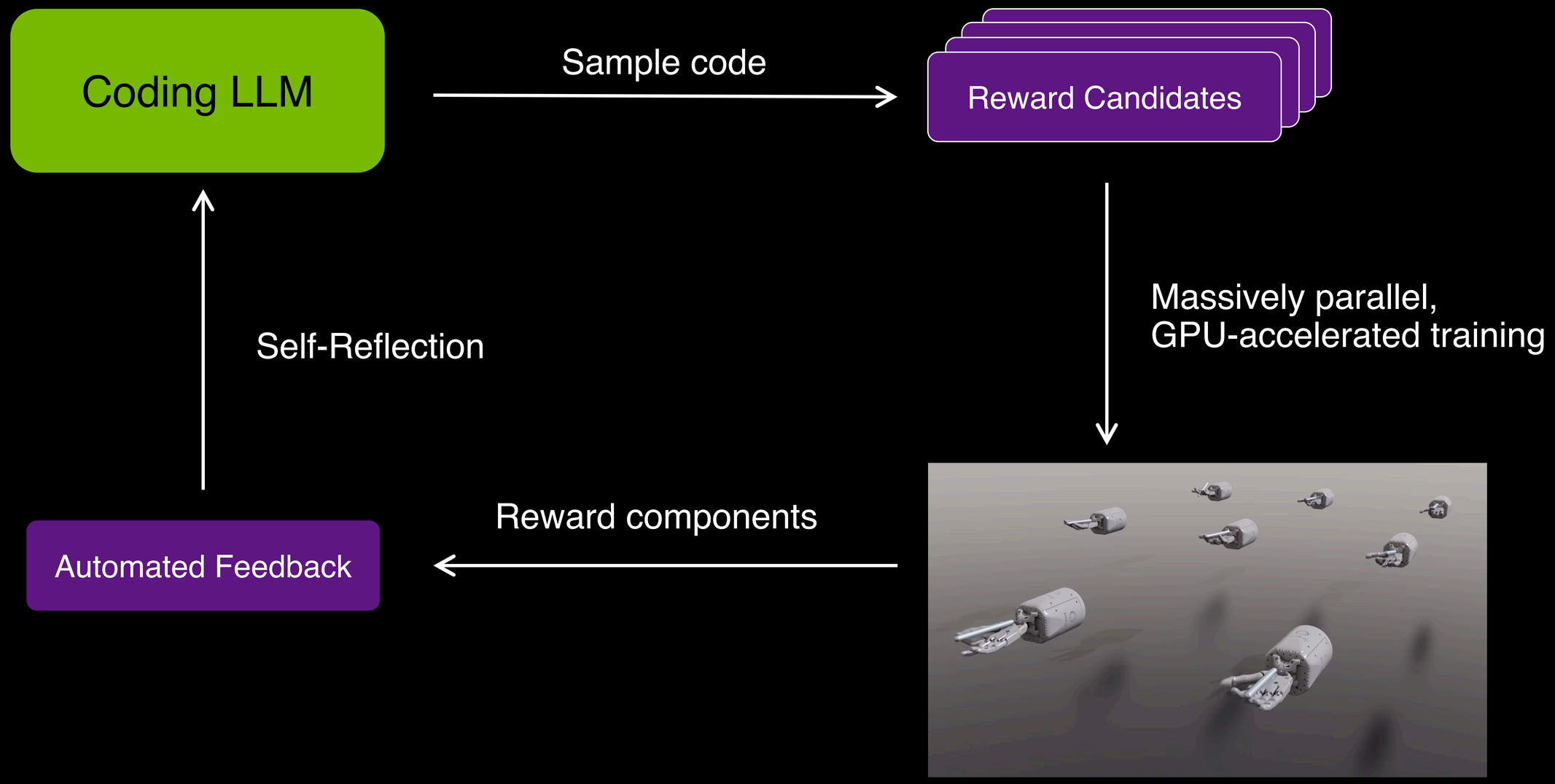

```python
def compute_reward(object_rot, goal_rot, object_angvel, object_pos, fingertip_pos):
    # Rotation reward
    rot_diff = torch.abs(torch.sum(object_rot * goal_rot, dim=1) - 1) / 2
    rotation_reward_temp = 20.0
    rotation_reward = torch.exp(-rotation_reward_temp * rot_diff)

    # Distance reward
    min_distance = torch.min(torch.norm(fingertip_pos - object_pos[:, None], dim=2), dim=1).values
    distance_reward = min_distance

    total_reward = rotation_reward + distance_reward

    reward_components = {
        "rotation_reward": rotation_reward,
        "distance_reward": distance_reward
    }

    return total_reward, reward_components
```



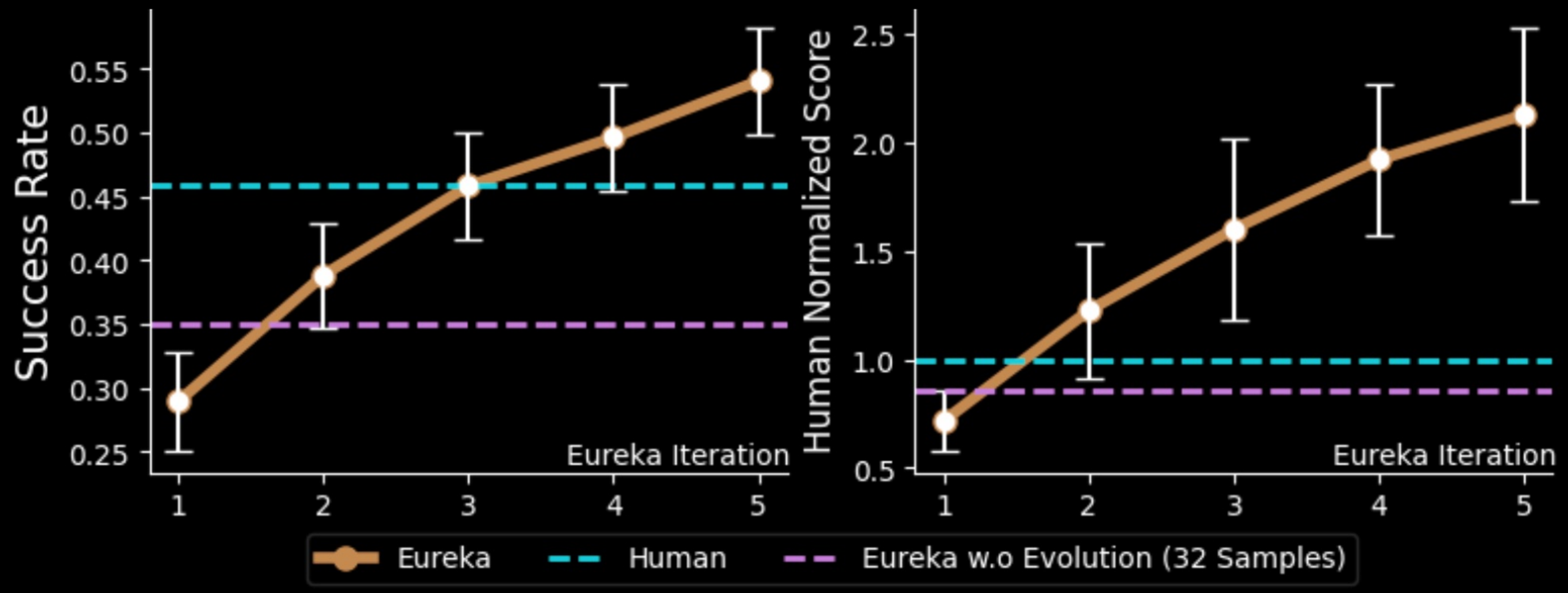


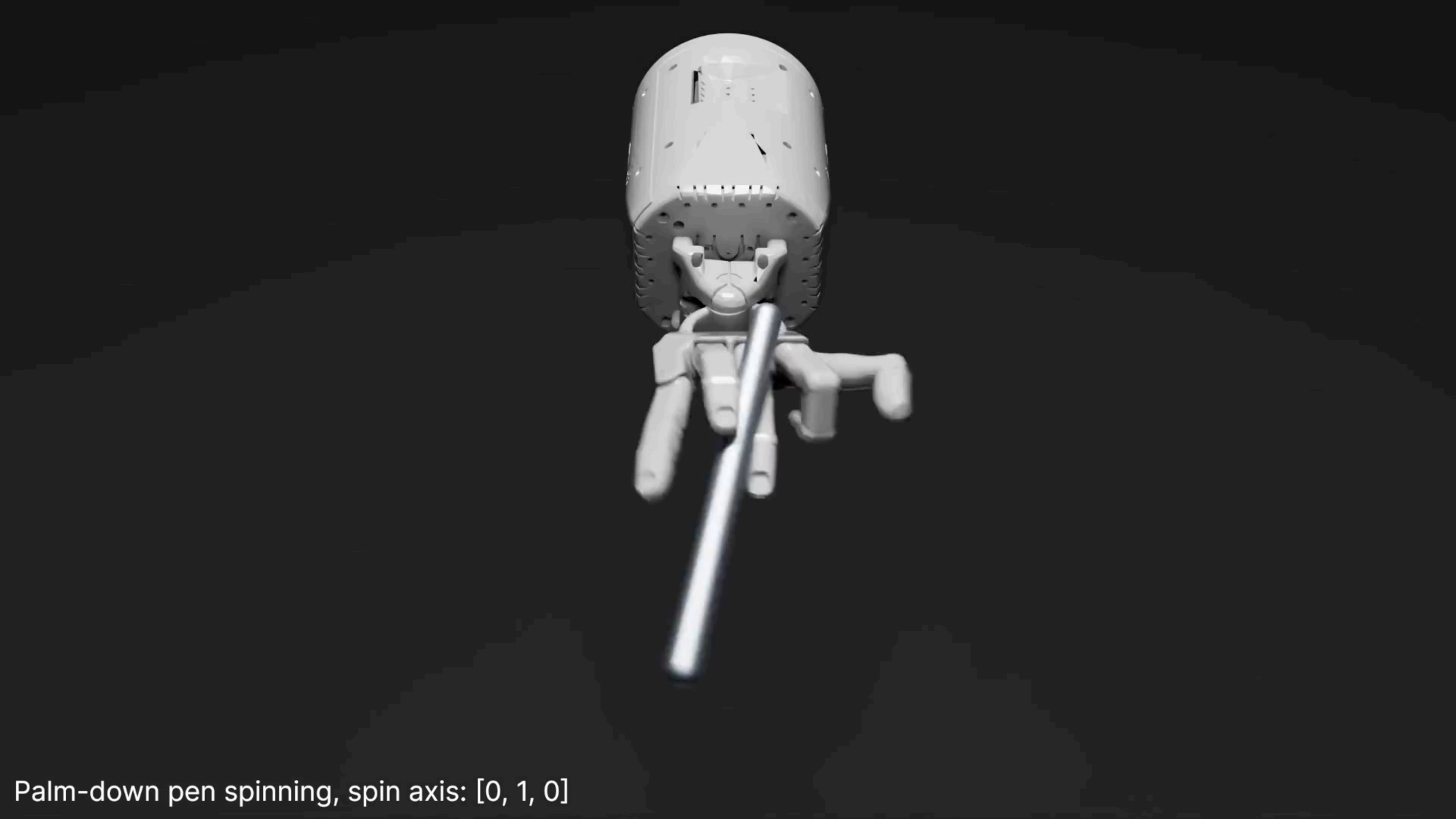

Ma et al. ICLR 2024.

```
def compute_reward(object_rot, goal_rot, object_angvel, object_pos, fingertip_pos):
    # Rotation reward
    rot_diff = torch.abs(torch.sum(object_rot * goal_rot, dim=1) - 1) / 2
-   rotation_reward_temp = 20.0
+   rotation_reward_temp = 30.0                                          Changing hyperparameter
    rotation_reward = torch.exp(-rotation_reward_temp * rot_diff)

    # Distance reward
+   min_distance_temp = 10.0
    min_distance = torch.min(torch.norm(fingertip_pos - object_pos[:, None], dim=2), dim=1).values
-   distance_reward = min_distance
+   uncapped_distance_reward = torch.exp(-min_distance_temp * min_distance)
+   distance_reward = torch.clamp(uncapped_distance_reward, 0.0, 1.0)    Changing functional form

-   total_reward = rotation_reward + distance_reward
+   # Angular velocity penalty                                           Adding new component
+   angvel_norm = torch.norm(object_angvel, dim=1)
+   angvel_threshold = 0.5
+   angvel_penalty_temp = 5.0
+   angular_velocity_penalty = torch.where(angvel_norm > angvel_threshold,
+       torch.exp(-angvel_penalty_temp * (angvel_norm - angvel_threshold)), torch.zeros_like(angvel_norm))
+
+   total_reward = 0.5 * rotation_reward + 0.3 * distance_reward - 0.2 * angular_velocity_penalty

    reward_components = {
        "rotation_reward": rotation_reward,
        "distance_reward": distance_reward,
+       "angular_velocity_penalty": angular_velocity_penalty,
    }

    return total_reward, reward_components
```

Dexterity Benchmark

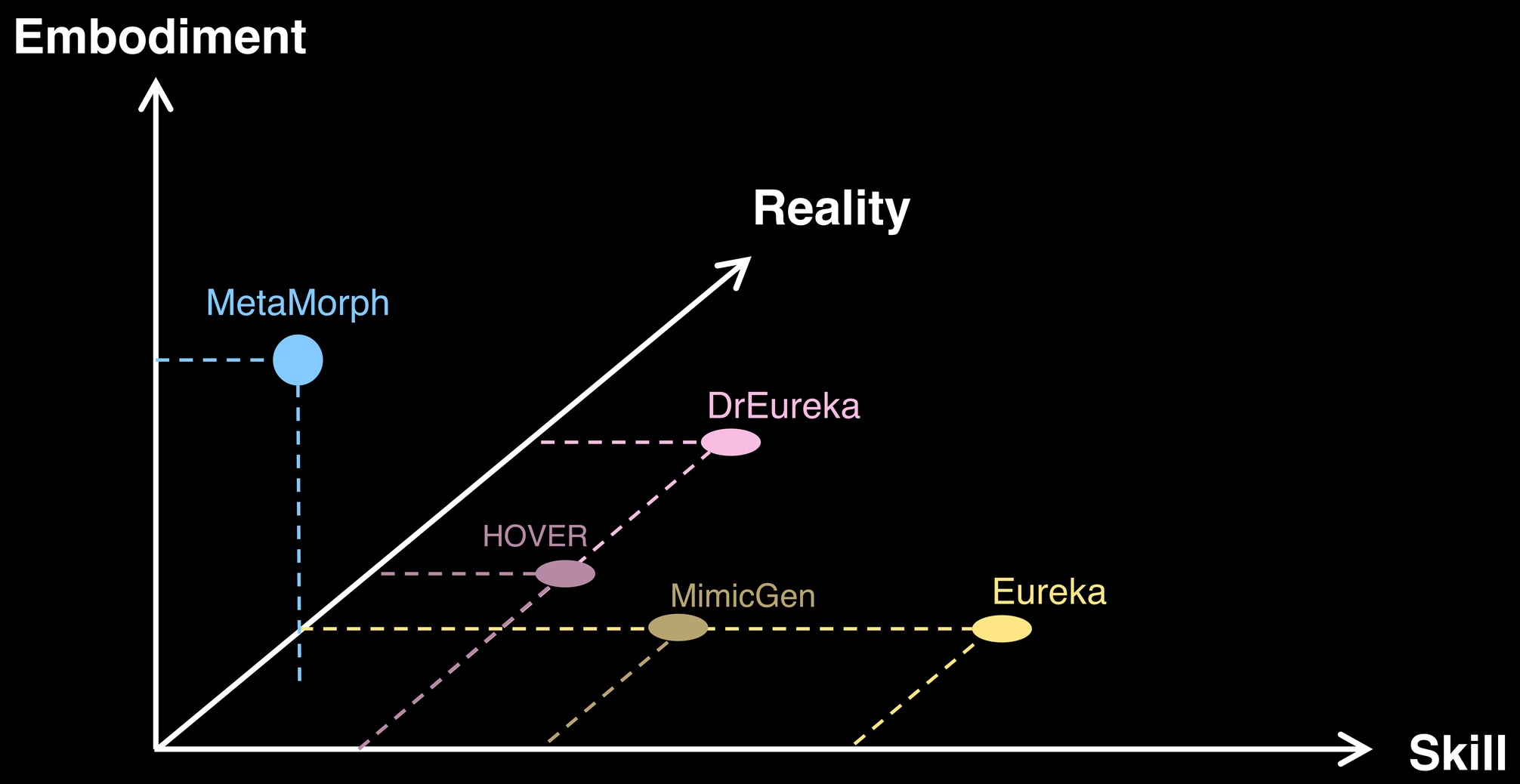
Isaac Benchmark

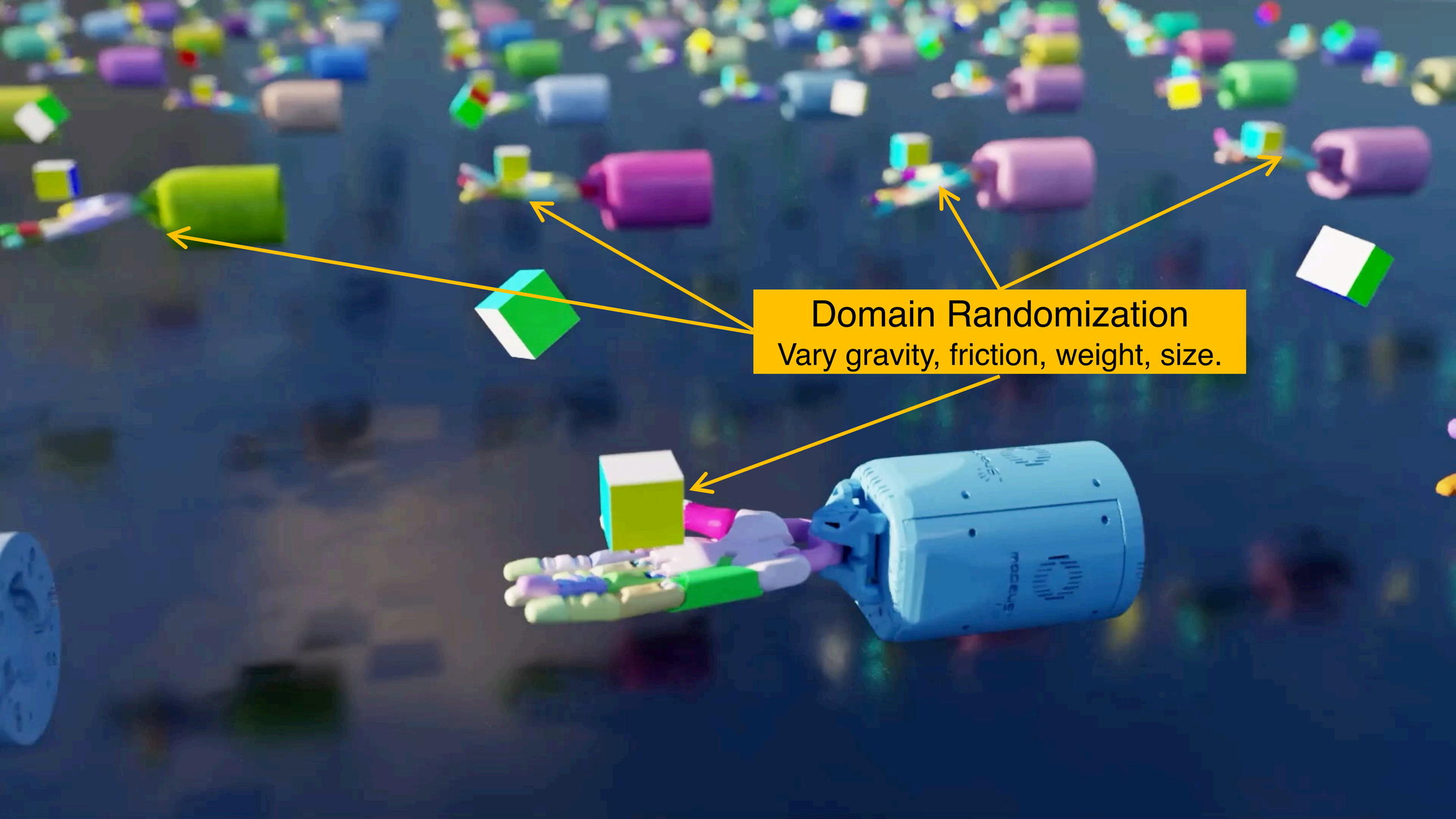


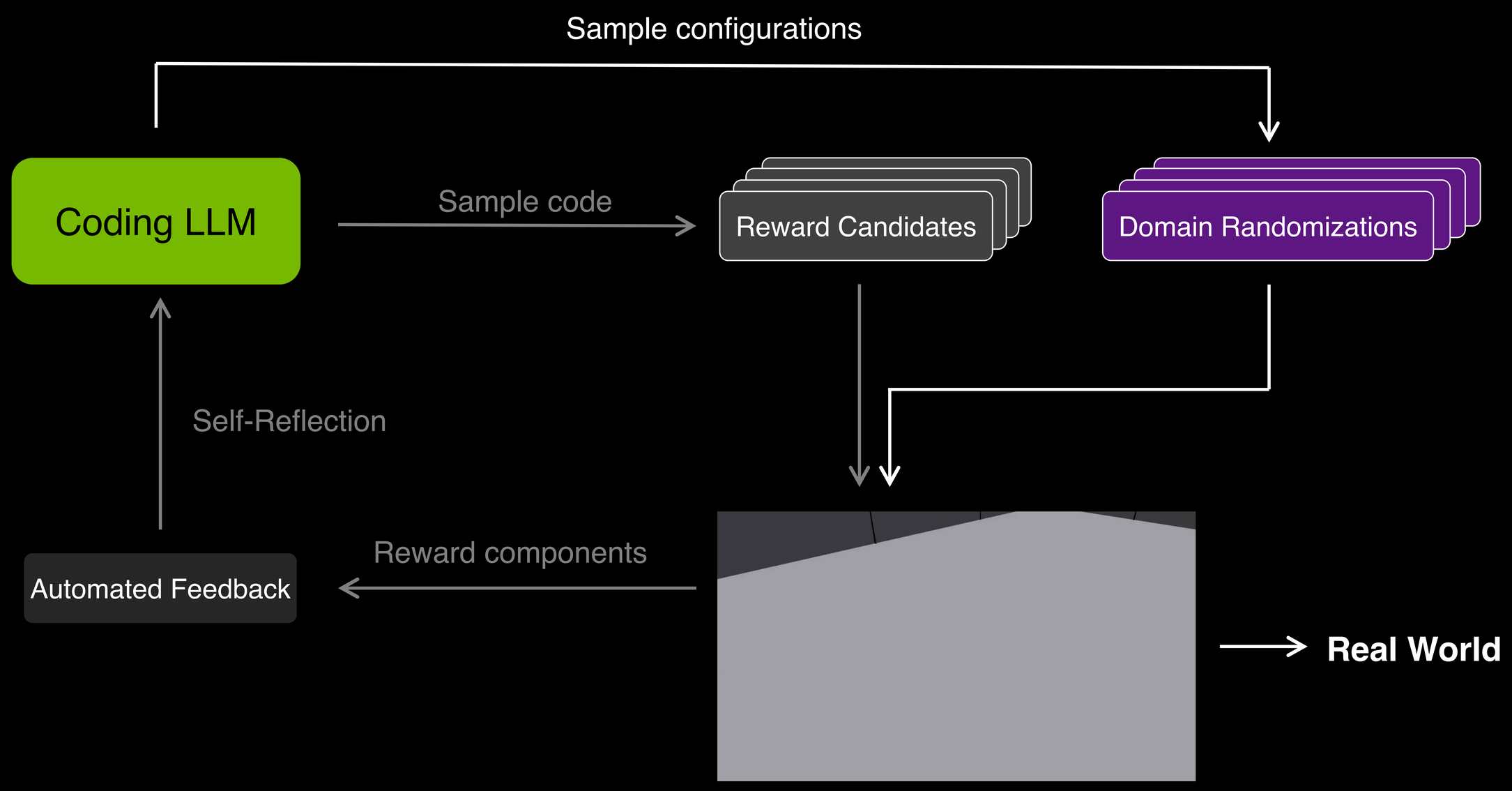


Palm-down pen spinning, spin axis: [0, 1, 0]

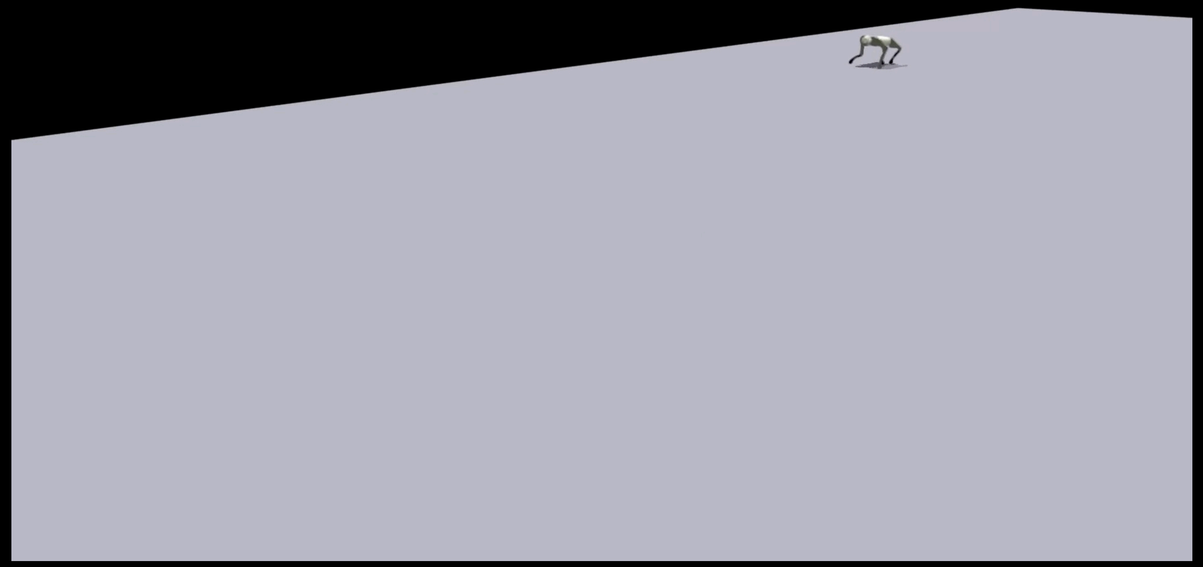
How to transfer from sim to the real world?


Embodiment
Reality
Skill
MetaMorph
DrEureka
HOVER
MimicGen
Eureka


Domain Randomization
Vary gravity, friction, weight, size.


Sample configurations
Coding LLM
Sample code
Reward Candidates
Domain Randomizations
Self-Reflection
Automated Feedback
Reward components
Real World

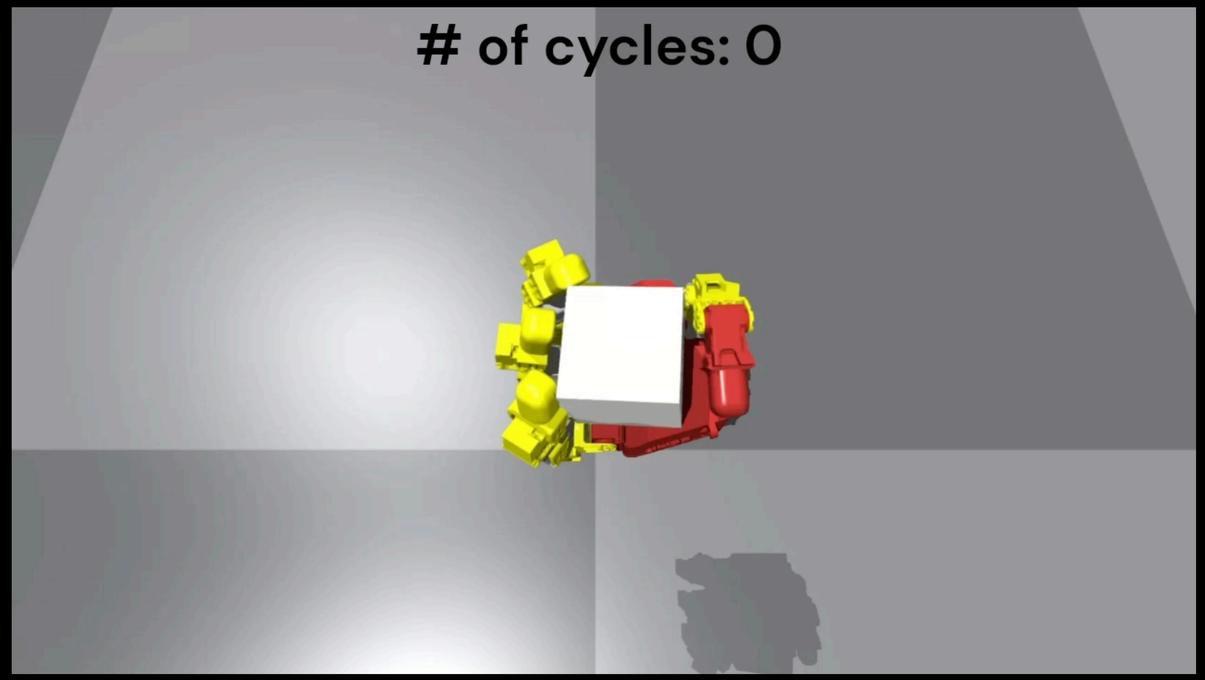
Ma et al, 2024



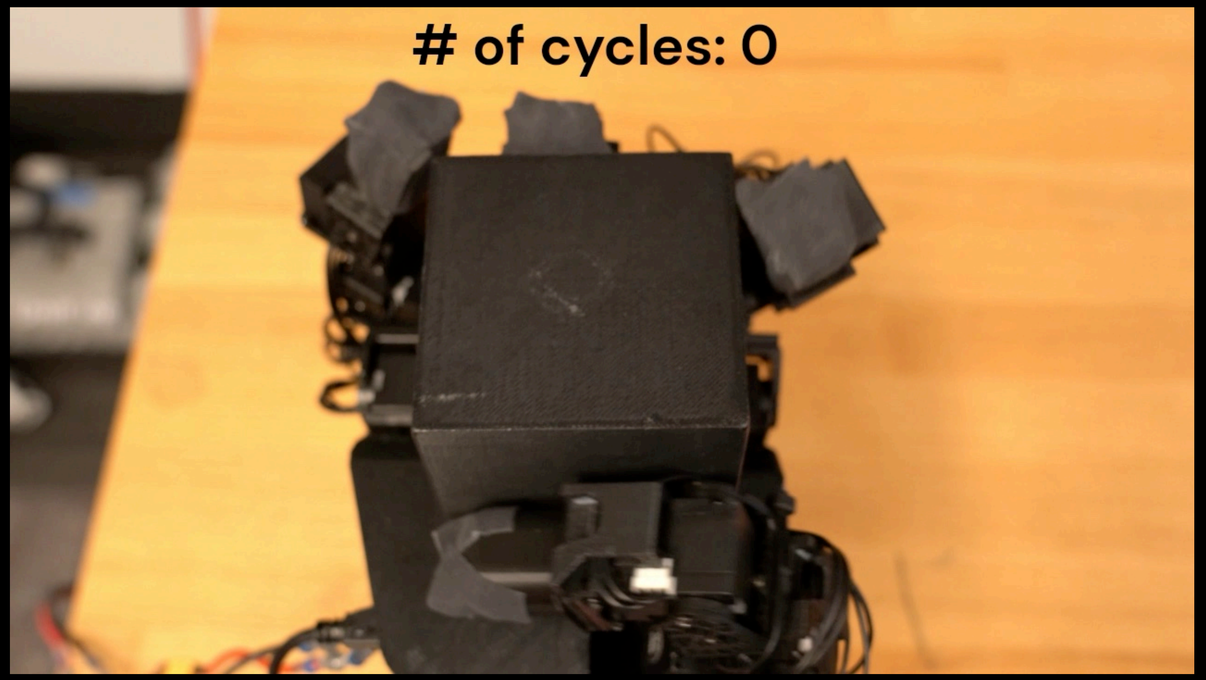
Simulation

Real World

Ma et al, 2023




Simulation

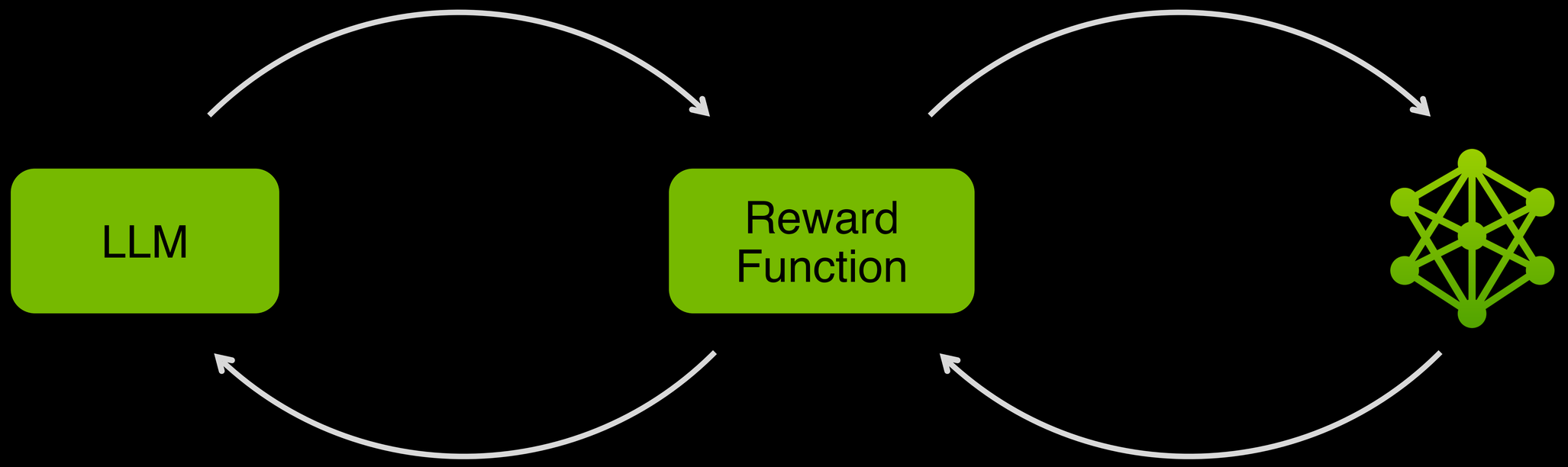



Real World

Ma et al, 2023

DrEureka

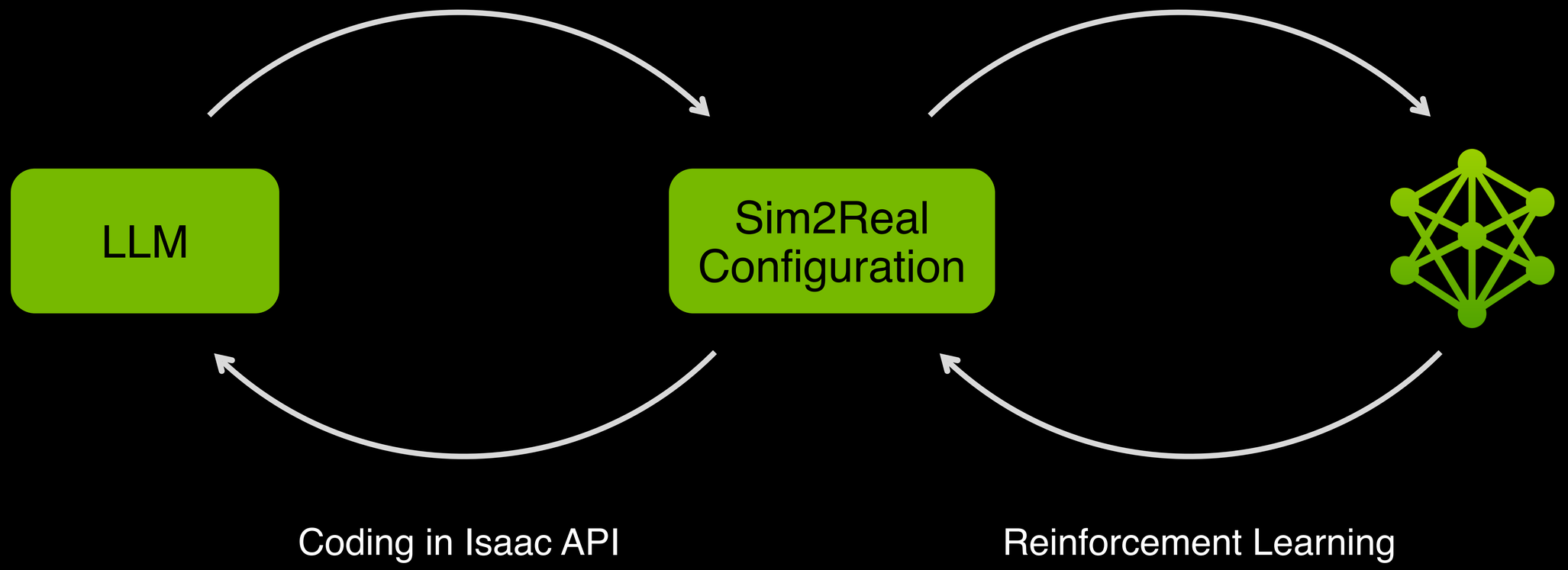
# Eureka



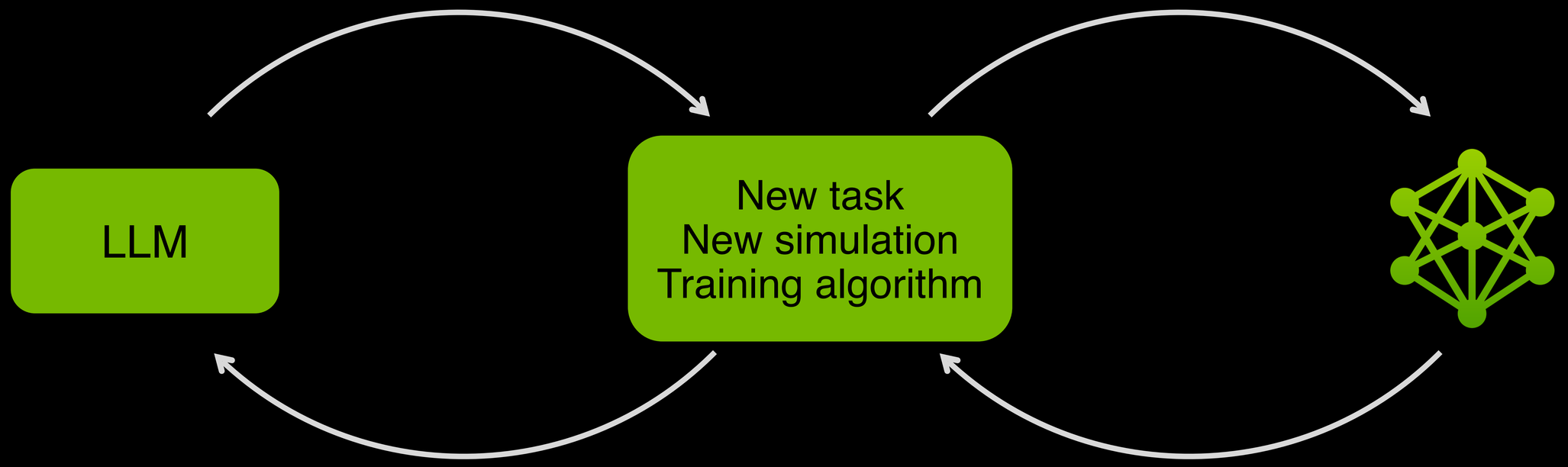

Coding in Isaac API

Reinforcement Learning

# DrEureka

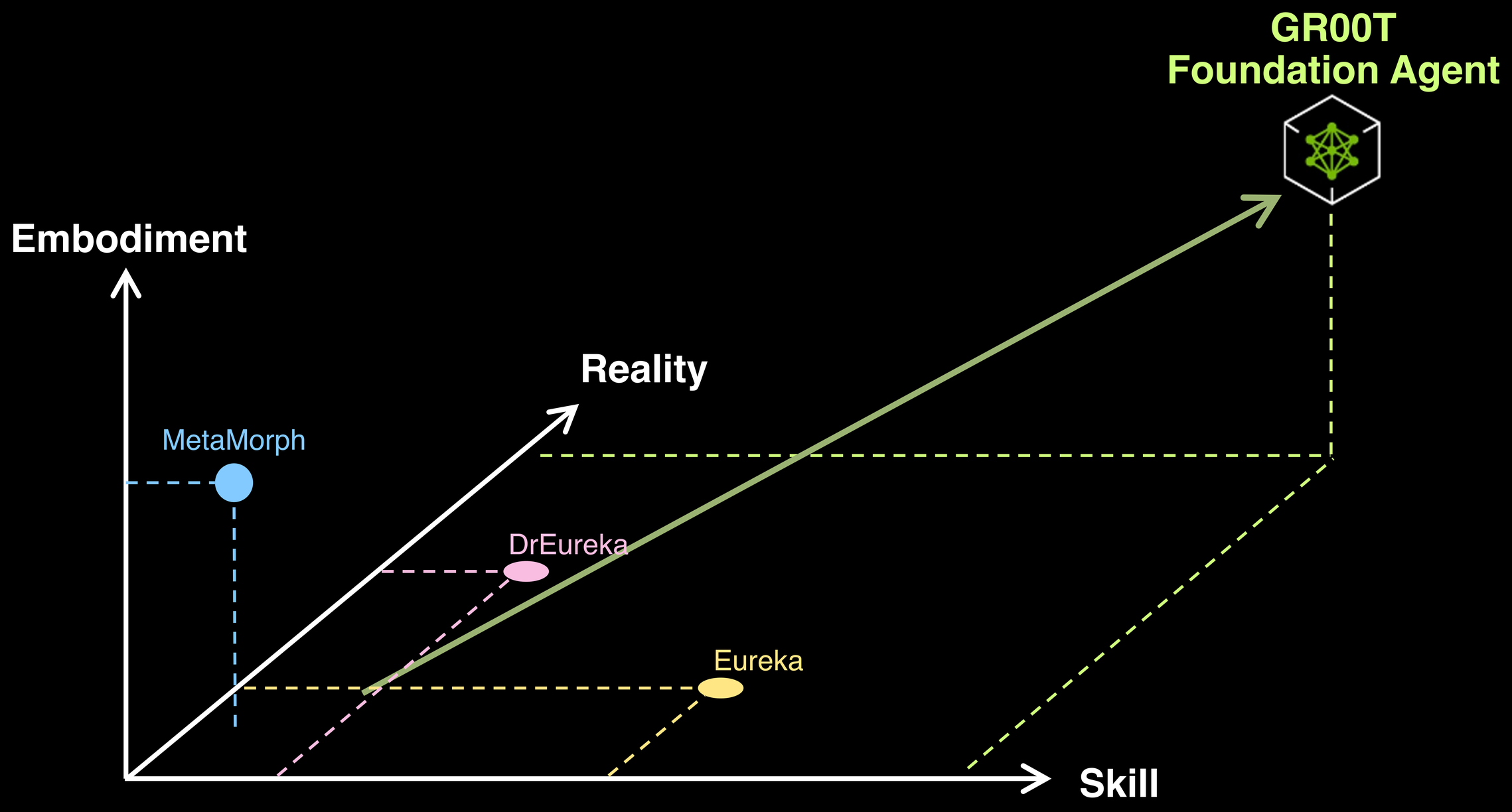

LLM
Sim2Real Configuration
Coding in Isaac API
Reinforcement Learning

# Eureka++



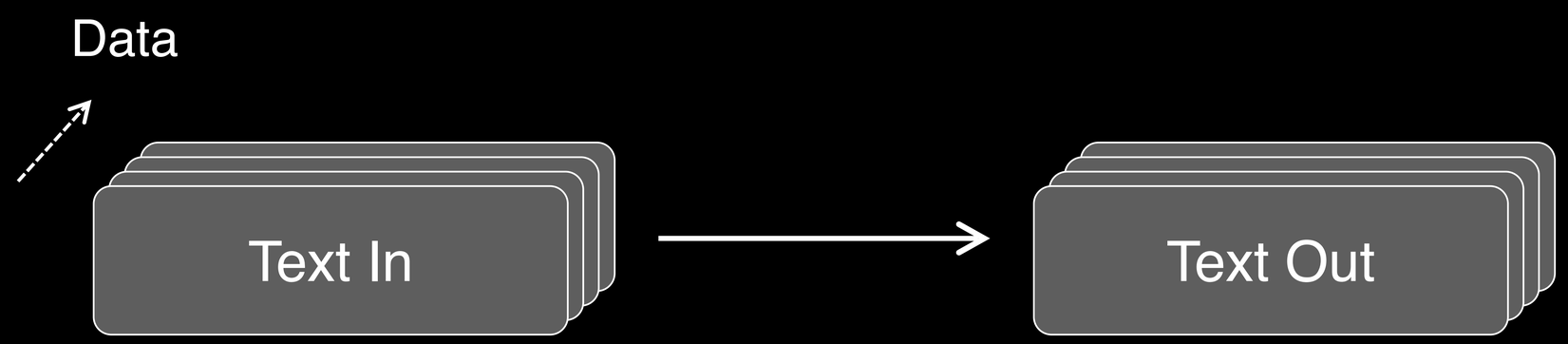

Coding in Isaac API

Reinforcement Learning


GR00T
Foundation Agent
Embodiment
Reality
MetaMorph
DrEureka
Eureka
Skill

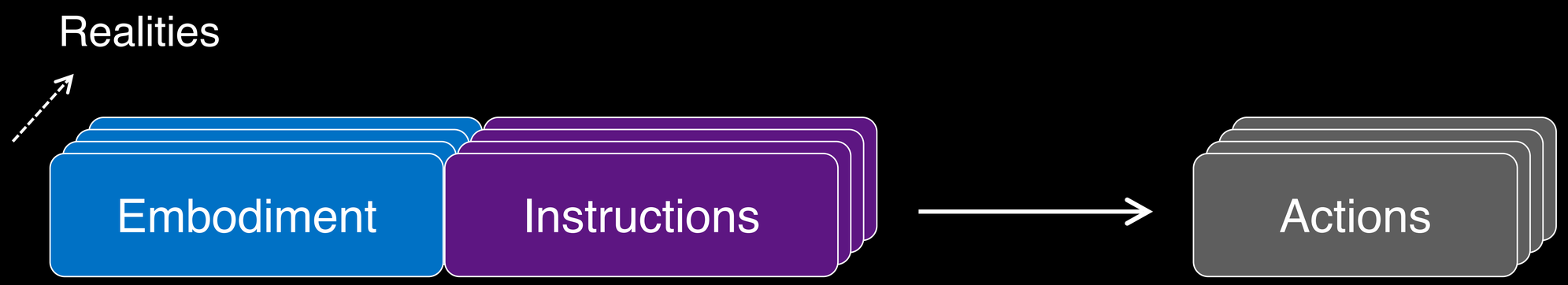
# ChatGPT

# ChatGPT



# GR00T

# GR00T

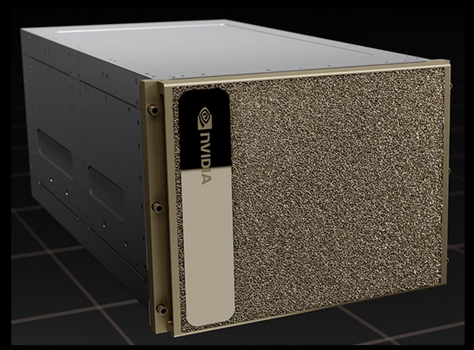


**OVX**: Generate Tokens
*RoboCasa, MimicGen, Eureka*

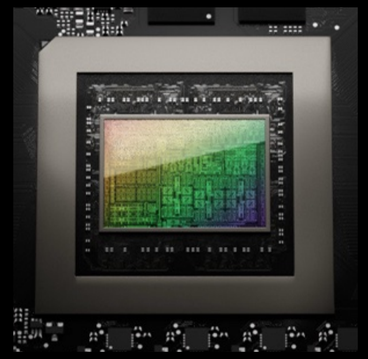
Synthetic data

Digital Twin Eval

**OSMO**



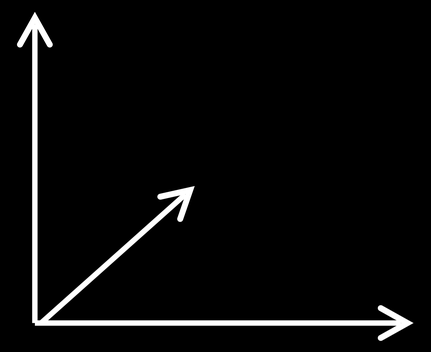
Edge inference



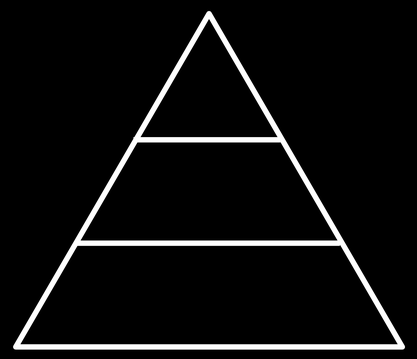
**DGX**: Learn Tokens
*Foundation Agent Models*

**AGX**: Deploy Tokens
*HOVER, DrEureka*

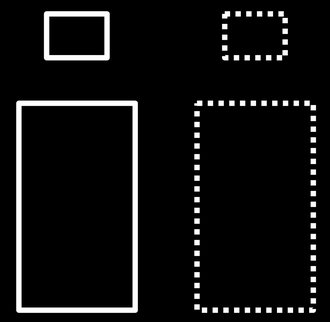
# 3 Principles



Foundation Agent



Data Pyramid

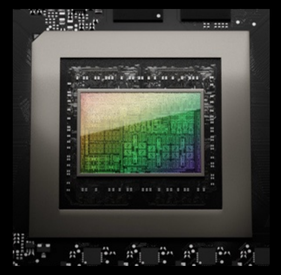


“The Matrix”

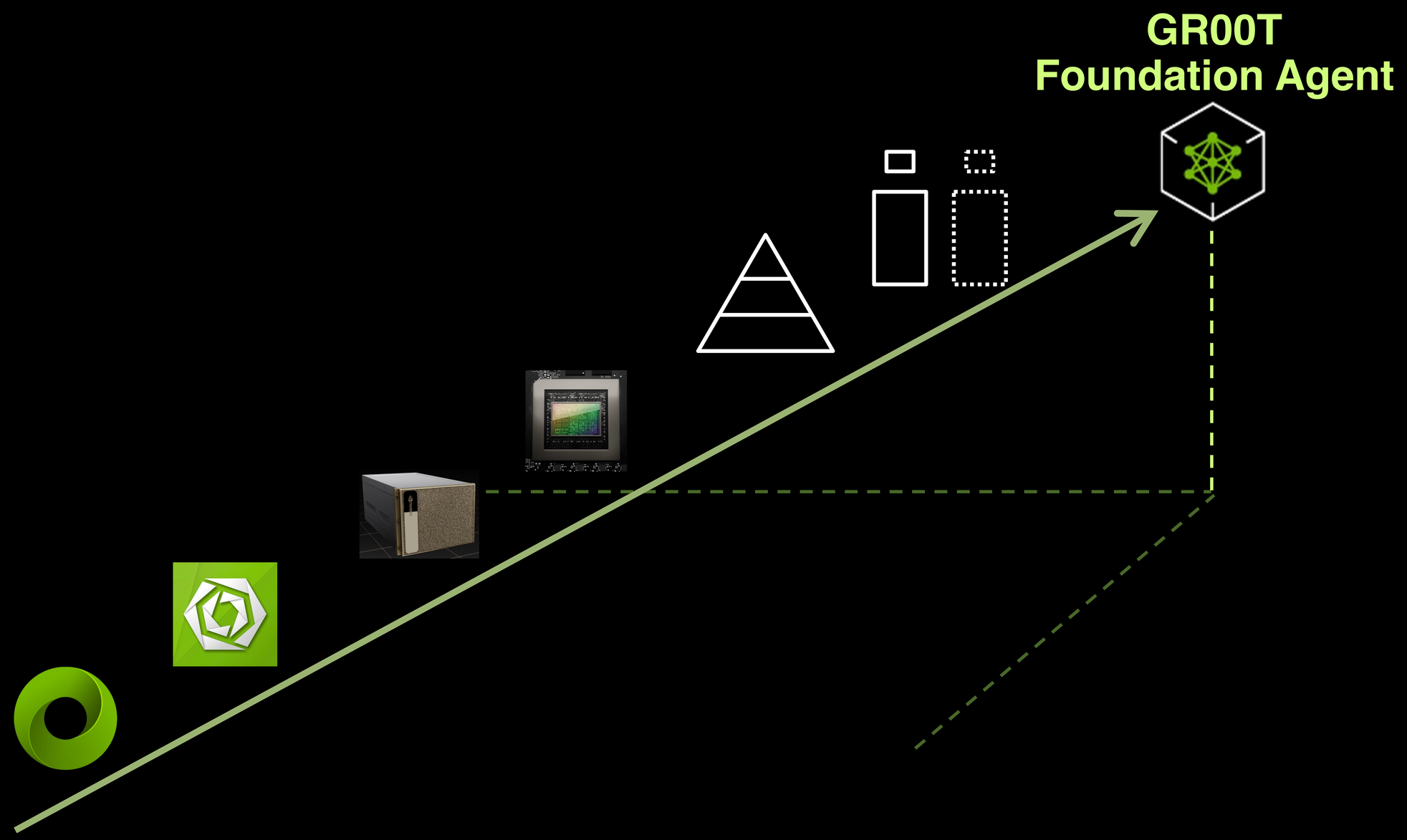
# 3 Computers

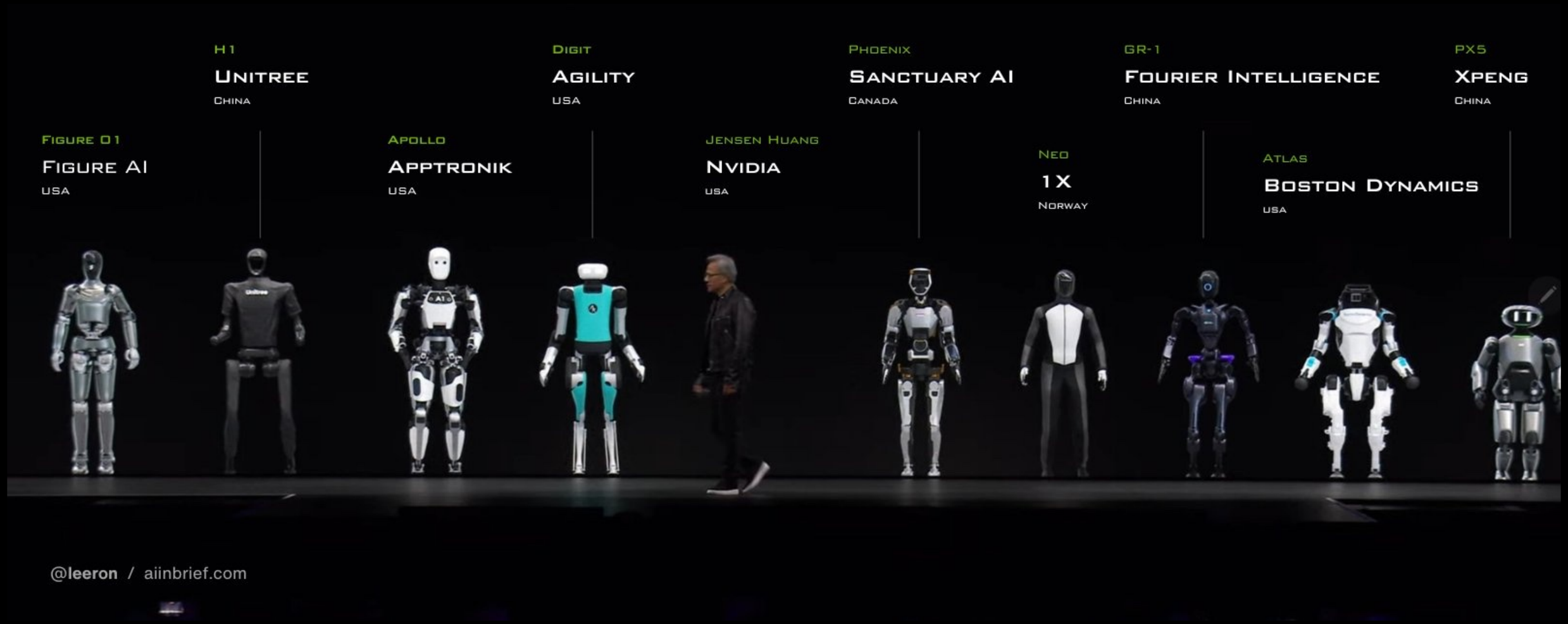
OVX

DGX

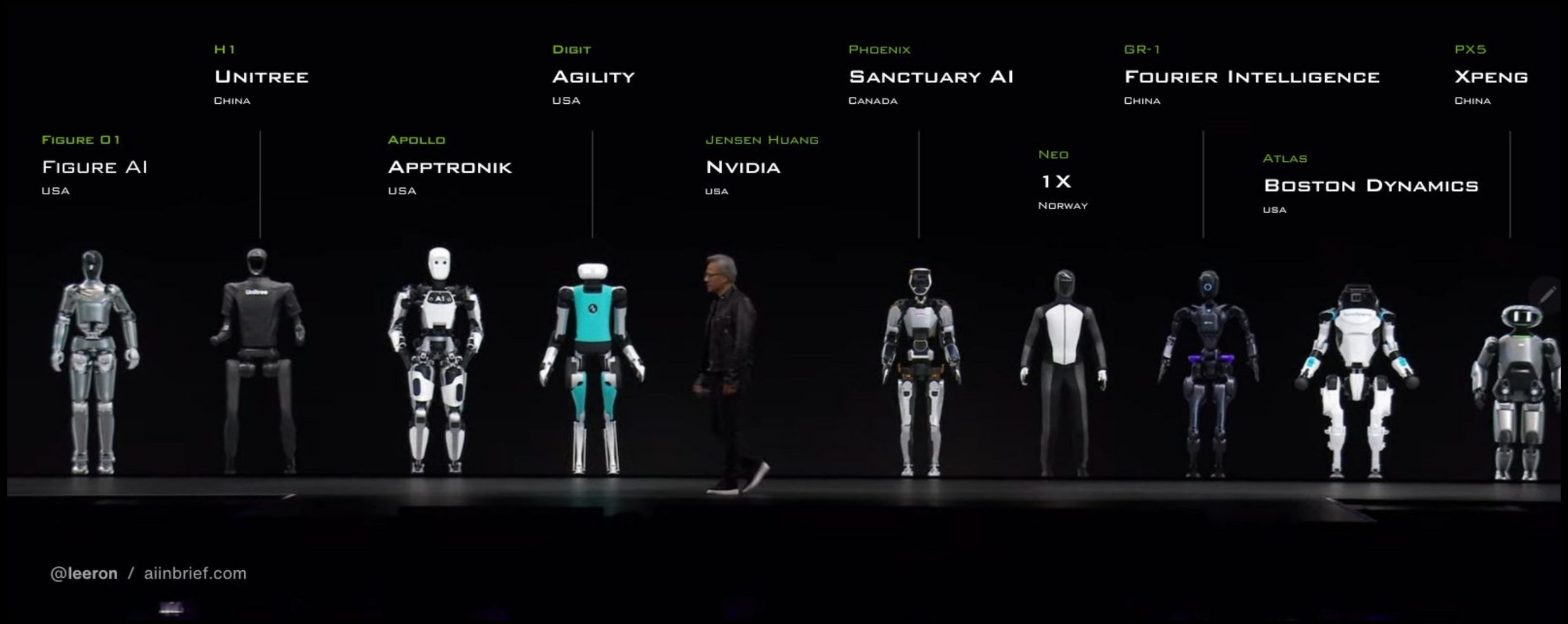


AGX

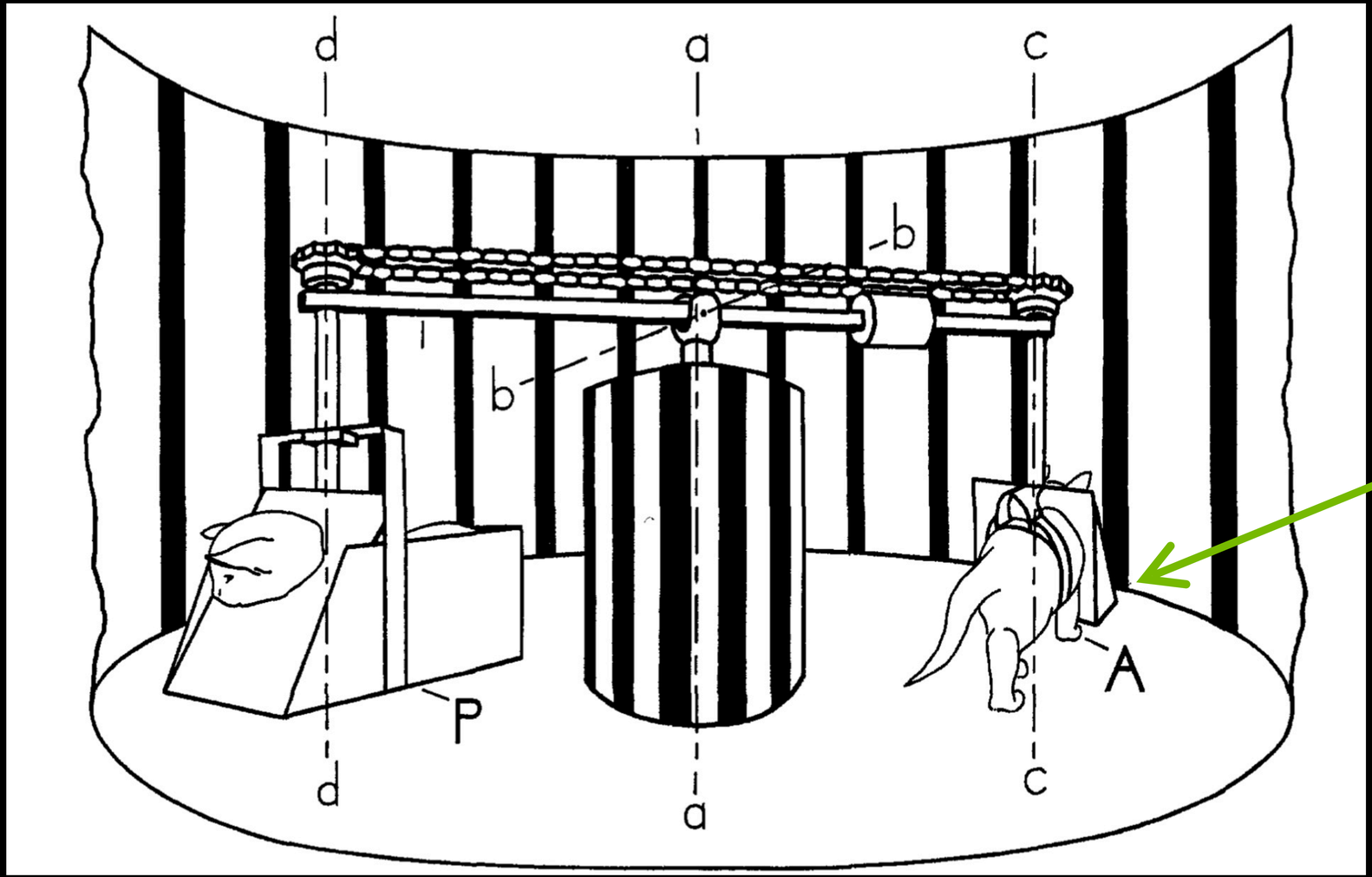

GR00T
Foundation Agent




Trillion-dollar Business




(Zero) Trillion-dollar Business




**Embodied AGI**

Held & Hein, 1963.

We are HIRING!!

GEAR Lab: **G**eneralist **E**mbodied **A**gent **R**esearch
https://research.nvidia.com/labs/gear

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NVIDIA