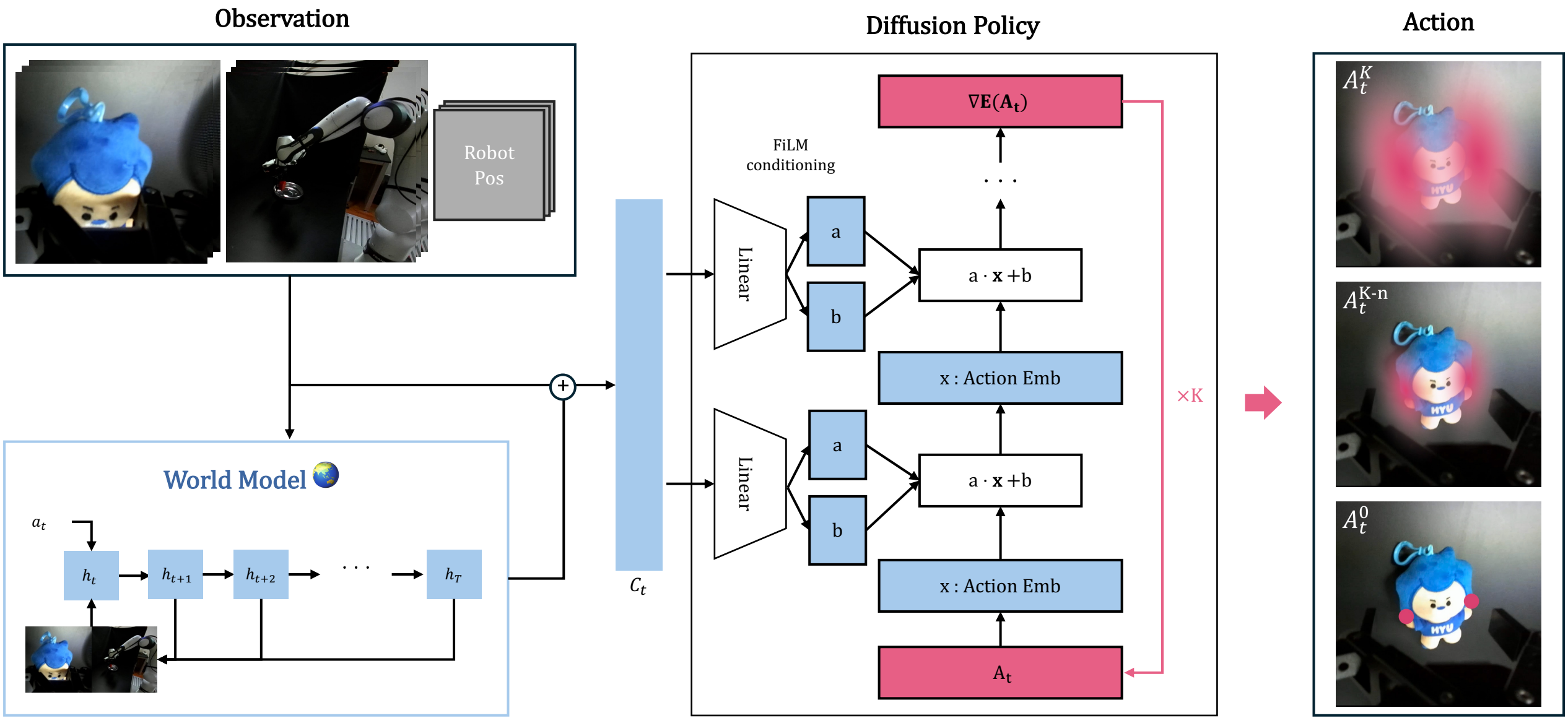

Observation
Robot Pos
World Model
a_t
h_t
h_{t+1}
h_{t+2}
h_T
C_t
Diffusion Policy
FiLM conditioning
Linear
a
b
$\nabla E(A_t)$
a · x +b
x : Action Emb
A_t
×K
Action
A_t^K
A_t^{K-n}
A_t^0