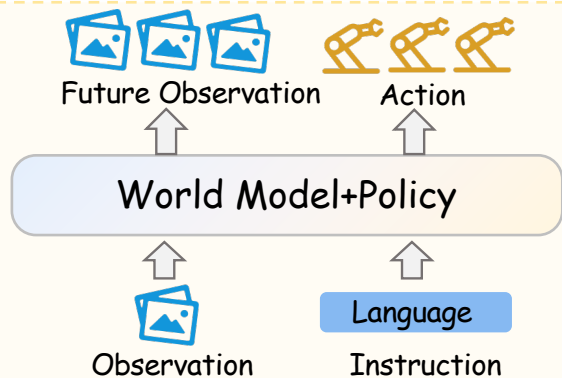
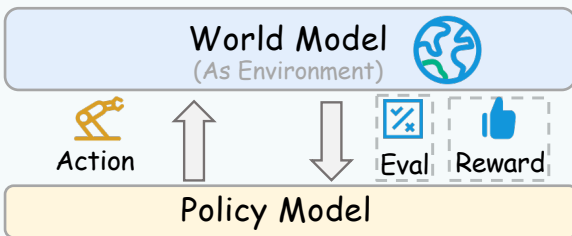
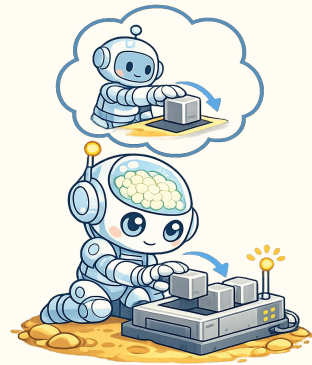




Sec 3. World Model for Policy

Classification by Model Architecture

- ❑ 3.1 Why World Models Help Robot Policy Learning
- ❑ 3.2 Inverse Dynamics Policies with World Models
- ❑ 3.3 Unified Policies with a Single World Model Backbone
- ❑ 3.4 MoE/MoT-Style Policies with World-Model Backbone
- ❑ 3.5 Unified Vision-Language-Action Models
- ❑ 3.6 Policies with Latent-Space World Modeling



Sec 4. World Model as Simulator

Classification by Different Application

- ❑ 4.1 World Model for Reinforcement Learning
- ❑ 4.2 World Model for Evaluation



Sec 5. World Model for Robotic Video Generation

Classification by World-Modeling Capability

- ❑ 5.1 Problem Setting and Scope
- ❑ 5.2 Video Generation as Imagination for Policy Learning
- ❑ 5.3 Action-Controllable World Model
- ❑ 5.4 Structure-Aware World Model
- ❑ 5.5 From Video Backbones to Foundation World Models

