

Task Code Generation Prompt



[Robot Description]

The berkeley humanoid is a bipedal robot ...

[Observation]

(1) base_lin_vel: Linear velocity of base

[Initial State & Environment Description]

Default initial values are initialized to make robot stand

[Target Task]

The original task in the environment is to walk or run ...

Task Info



Task 1

Name: Basic Stability Learning

Description: linear velocity [0, 0], heading angle [0, 0]

Reason: Ensure the robot to maintain balance ...

Task 2

Name: Learn to Walk

Description: linear velocity [-0.5, 0.5], heading angle [0, 0]

Reason: Simplifies the learning by first moving slow



Task Code Generation LLM

Previous Task Code

```
def compute_reward_curriculum():  
    # Keep upright  
    base_orientation_weight = 0.2  
    # Keep on feet  
    base_height_weight = 0.1
```



Policy Evaluation LLM

Policy for each Subtask

Task Code Sampling

```
def compute_reward_curriculum():  
    # Velocity tracking reward  
    lin_vel_error = torch.sum(  
        torch.square(command[:, :2]  
        - base_lin_vel[:, :2]))
```

Load Pre-trained Policy
and Fine-tune

Rollout of Trained Policy

Policy 1:

base_lin_vel: [-0.202 -0.114 0.017]

base_ang_vel: [-0.001 -0.004 0.084]

velocity_command: [-0.292 -0.156 0.074]

...

Policy 2:

...

