
Multistep Quasimetric Learning for Scalable Goal-conditioned Reinforcement Learning

Bill Chunyuan Zheng¹ Vivek Myers¹ Benjamin Eysenbach² Sergey Levine¹

¹UC Berkeley ² Princeton University

November 9, 2025

Abstract

Learning how to reach goals in an environment is a longstanding challenge in AI, yet reasoning over long horizons remains a challenge for modern methods. The key question is how to estimate the temporal distance between pairs of observations. While temporal difference methods leverage local updates to provide optimality guarantees, they often perform worse than Monte Carlo methods that perform global updates (e.g., with multi-step returns), which lack such guarantees. We show how these approaches can be integrated into a practical GCRL method that fits a quasimetric distance using a multistep Monte-Carlo return. We show our method outperforms existing GCRL methods on long-horizon simulated tasks with up to 4000 steps, even with visual observations. We also demonstrate that our method can enable stitching in the real-world robotic manipulation domain (Bridge setup). Our approach is the first end-to-end GCRL method that enables multistep stitching in this real-world manipulation domain from an unlabeled offline dataset of visual observations.¹

1 Introduction

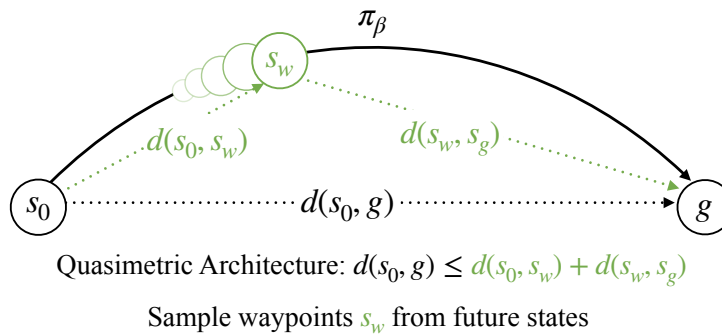


Figure 1: In this paper, we present Multistep Quasimetric Estimation (MQE). Unlike prior work in quasimetric distance learning that use single-step TD updates (Wang et al., 2023) or Monte-Carlo updates (Myers et al., 2024), MQE is the *first* work to incorporate multistep returns with real-world success.

It is natural for humans to use inherent ideas of distances to represent task progress: a GPS will tell you how far you are from the destination and a cookbook will tell you how long a recipe will take. Humans

¹Website and code: <https://mqe-paper.github.io>

can solve tasks by taking the shortest route possible (stitching) and combining several learned tasks together in sequence in a new environment (combinatorial generalization). The AI problem of reaching goals presents a rich structure (formally, an optimal substructure property) that can be exploited to decompose hard problems into easy problems, and reinforcement learning (RL) has been used to address such problems. However, many past attempts at leveraging this property in modern high-dimensional, stochastic settings still need much work. Current approaches tend to separate TD learning (local updates) (Kostrikov et al., 2022; Kumar et al., 2020; Mnih et al., 2013) and MC learning (global value propagation) (Eysenbach et al., 2022; Myers et al., 2024); as TD learning can theoretically recover the optimal Q function (Q^*), while MC methods can only recover the behavior Q function (Q_β), but tend to work well in practice.

However, the effectiveness of both the temporal difference and Monte Carlo methods degrades, often from a combination of increasing the horizon length for TD methods (Park et al., 2025b) or difficulties in finding the optimal temporal distance (Park et al., 2024a). These combined challenges present an intriguing opportunity to find methods that can leverage the advantages of both approaches, where one can perform both local and global value propagation at once.

Our main contribution lies in **Multistep Quasimetric Estimation (MQE)**, an offline GCRL method that incorporates both multistep value learning and quasimetric architectures without needing explicit hierarchy. By leveraging such a unique combinations of the benefits of TD and MC methods, MQE allows the learned policy to (i): display a much stronger level of horizon generalization compared to previous methods, which allow us to demonstrate the desired “stitching” behavior, (ii): provide a stable method that can extract strong goal-reaching policies even from noisy data, and (iii): such stability in training allows it to be applied in real-world robot learning problems without additional design choices. To our knowledge, MQE is the first method capable of taking advantage of multistep TD returns with global value propagation through quasimetric architectures. MQE can demonstrate SoTA performance on tasks that require complex control and long-horizon reasoning (up to 21 DoF and 4000 timesteps respectively), and in real world robotic settings, MQE displays compositional generalization behaviors that are not seen in previous RL algorithms.

2 Related Works

Our work build upon previous works in offline RL and temporal distance learning.

Goal-conditioned Reinforcement Learning. Our findings particularly concern the discussions seen in recent work regarding the stitching and horizon generalization capabilities of GCRL. Recent findings (Park et al., 2025b) have shown that while offline RL is easy to scale on short-horizon tasks, it is difficult to learn long-horizon tasks that require more complex reasoning within the agent, which can easily deviate from the optimal distance due to compounding TD errors. Other findings have shown that combinatorial generalization and stitching do not necessarily need dynamic programming (Brandfonbrener et al., 2023; Garg et al., 2023; Ghugare et al., 2024), which gives promise to using simpler methods for learning stitchable policies.

Offline RL for Robotics. In the same vein, we also focused on how we can apply these reinforcement learning techniques to robotics. Although reinforcement learning has been used to obtain highly capable specialist policies in various embodiments (Ball et al., 2023; Luo et al., 2025; Seo et al., 2025; Smith et al., 2023), behavior cloning still remains the most capable method for training generalist policies (O’Neill et al., 2024). Efforts have been made to allow self-supervised and offline RL in robotics (Zheng et al., 2024), however, directly training a policy with offline RL remains difficult, as many researchers have instead used other ways to incorporate RL, such as rejection sampling (Nakamoto et al., 2025; Wagenmaker et al., 2025) or data set curation (Mark et al., 2024; Xu et al., 2024). The focus of this work lies more on designing and implementing an offline RL method that can work in real world instead of only focusing on techniques for such training.

Under controlled datasets in simulated benchmarks, these algorithms may return a good goal-reaching policy, recent works have shown that additional work are needed for it to successfully train and deploy a policy in real life (Zheng et al., 2024). Additionally, most current methods struggle with compositionality (Kawaharazuka et al., 2025; Myers et al., 2025a), especially in domains with many objects, scenes, and scenarios, where this kind of stitching necessarily requires both temporal compositionality and generalization.

Temporal Distance Learning. Our work is partially inspired by successor representations (Blier et al., 2021; Dayan, 1993). Previous works have shown that by using contrastive learning, (Myers et al., 2024) Other works have also shown that using contrastive learning as a way to parameterize distance learning may also recover behavior Q function (Eysenbach et al., 2022).

Multistep RL. RL using multistep returns has been widely used in online RL and offline-to-online RL settings (Li et al., 2025; Tian et al., 2025). This is desirable because in on-policy settings, performing RL with multistep return is theoretically correct and yields better performance (Asis et al., 2018; Munos et al., 2016; Schulman et al., 2016). However, in an offline setting, the theory behind such correctness breaks down (Watkins, 1989), as the learning paradigm becomes an inherently off-policy manner. Methods that use the entire trajectory in a Monte Carlo manner and attempt to recover the Q function can also be seen as a multistep RL algorithm (Eysenbach et al., 2022). However, such approach can only recover the behavior Q function Q_β (Eysenbach et al., 2022; Myers et al., 2024).

3 Preliminaries

In this section, we define temporal distances and our learning objective.

Notation. We consider a controlled Markov process (CMP) \mathcal{M} with state space \mathcal{S} , action space \mathcal{A} , transition dynamics $P(s'|s, a)$, and discount factor as γ . We consider goal-reaching policies $\pi(a|s, g) : \mathcal{S} \times \mathcal{S} \rightarrow \mathcal{A} \in \Pi$. We denote the behavior policy that is used to populate the offline dataset as π_β . In lieu of rewards, we optimize the maximum discounted likelihood of a policy reaching the goal, in which we can represent the goal-conditioned Q function and the value function as:

$$Q_g^\pi(s, a) \triangleq \mathbb{E}_{\{\mathbf{s}_t, \mathbf{a}_t\} \sim \pi} \left[\sum_{t=0}^{\infty} \gamma^t P(\mathbf{s}_t = g \mid \mathbf{s}_0 = s, \mathbf{a}_0 = a) \right]. \quad (1)$$

$$V_g^\pi(s) \triangleq \mathbb{E}_{\{\mathbf{s}_t\} \sim \pi} \left[\sum_{t=0}^{\infty} \gamma^t P(\mathbf{s}_t = g \mid \mathbf{s}_0 = s) \right]. \quad (2)$$

Equivalently, we can define the optimal Q-function as $Q_g^*(s, a) \triangleq \max_{\pi \in \Pi} Q_g^\pi(s, a)$. Previous work have shown that using contrastive leaning (Eysenbach et al., 2022; van den Oord et al., 2019) can recover the behavior distance, but not the optimal distance.

Similarly, prior work on MC learning (Eysenbach et al., 2021, 2022; Myers et al., 2024) has demonstrated that instead of only using the end of trajectories as the goal state, we sample future states via a geometric distribution as described in Eq. (3). This allows us to classify any future state in trajectory as goals, providing a robust way of learning goal-reaching policies.

$$\mathbf{s}_t^+ \triangleq \mathbf{s}_{t+K}, K \sim \text{Geom}(1 - \gamma). \quad (3)$$

Quasimetric distance representations. Traditionally, offline RL algorithms use neural networks to represent the critic and value function $Q_g(s, a)$ and $V_g(s)$ (Kostrikov et al., 2022; Kumar et al., 2020). Separately, other works have been using dot products $Q(s, a, g) \triangleq \varphi(s, a)^\top \psi(g)$ (Eysenbach et al., 2022; Zheng et al., 2024) or geometric norms $\|\varphi(s) - \psi(g)\|_k$ for suitable values of k (Eysenbach et al., 2024;

Park et al., 2024c). We use quasimetric architectures (Pitis et al., 2020; Wang et al., 2023) to parameterize our value functions, which by construction satisfies (i): positivity, (ii): triangle inequality, and (iii): identity (Cobzaş, 2013).

To enforce the quasimetric properties of the successor distances, we use Metric Residual Networks (MRN) (Liu et al., 2023) that operate directly on vector-based representations, which is defined by Eq. (4). MRN splits the representation into N equally sized ensembles, and in each part, takes the sum of the asymmetric component (maximum of ReLU) and a symmetric component (l_2 norm) of the difference between the two embeddings x and y . For simplicity, we denote $d(x, y)$ by $d_{\text{MRN}}(x, y)$.

$$d_{\text{MRN}}(x, y) \triangleq \frac{1}{N} \sum_{k=1}^N \max_{m=1 \dots M} \max(0, x_{kM+m} - y_{kM+m}) + \|x_{kM+m} - y_{kM+m}\|_2 \quad (4)$$

4 Multistep Quasimetric Estimation (MQE)

In this section, we develop MQE framework based on quasimetric architectures, which can be broken down into 3 parts: (1) multistep backup under a quasimetric architecture, (2) imposing action invariance as an additional optimization objective, (3) practical implementation details for extracting the goal-reaching policy. To the best of our knowledge, MQE is the **first** method to effectively combine multistep returns with a quasimetric distance parameterization, and achieves superior results to previous methods that use TD returns, contrastive learning for value estimation, or hierarchical methods.

Definitions. We will define a distance (quasi)metric over states and state-action pairs that is proportional to the goal-conditioned Q and V functions (Myers et al., 2024):

$$Q_g(s, a) = V_g(g) e^{-d((s,a),g)}, \quad V_g(s) = V_g(g) e^{-d(s,g)}. \quad (5)$$

We learn a parameterized form of this distance with learned state and state-action $\psi(s) \in \mathbb{R}^{NM}$ and $\phi(s, a) \in \mathbb{R}^{NM}$ representations and a quasimetric distance function (4):

$$d((s, a), g) \triangleq d_{\text{MRN}}(\phi(s, a), \psi(g)), \quad d(s, g) \triangleq d_{\text{MRN}}(\psi(s), \psi(g)). \quad (6)$$

4.1 Multistep Returns with Quasimetric Architecture

The first design principle of MQE is to use multistep returns under a quasimetric architecture. To that end, we start with the fitted onestep Q iteration that operates on quasimetric distance representations, in which \leftarrow denotes regressing from the LHS to the RHS:

$$e^{-d((s,a),g)} \leftarrow \mathbb{E}_{\{(s,a,s')\} \sim \mathcal{D}} [\gamma \cdot e^{-d(s',g)}]. \quad (7)$$

This is similar to optimizing the critic in traditional RL (Kostrikov et al., 2022; Lillicrap et al., 2019), the main difference being that we use a quasimetric architecture to represent the Q and value function. Due to the quasimetric architecture of the network, the reward signal is embedded within the parameterized distance, as $V_g(s)$ is defined to have a value of $V_g(g) > 0$ when $s = g$. We denote this regression objective as \mathcal{T} .

Our insight for the \mathcal{T} objective described in Eq. (7) is that, instead of applying this invariance to only the future state $s' \sim P(s'|s, a)$, we can extend this principle to any state between the current state and goal. This transforms a onestep optimization into a on-policy multistep optimization procedure. To do so, we first define the shorthand s_t^w , which refers to a “**waypoint**” between the current state and goal state. Empirically, we find that using a combination of Bernoulli distribution and geometric distribution

(described in Eq. (8)), capped at the index of the future state work the best.

$$s_t^w \leftarrow s_{t+k'} \quad \text{for} \quad \begin{cases} k' \sim \min(\text{Geom}(1 - \lambda), K) & \text{with probability } 1 - p, \\ k' = 1 & \text{with probability } p. \end{cases} \quad (8)$$

We now optimize the same objective as in Eq. (7), but across any such waypoint we sample. To account for the multistep nature of this objective, we modify Eq. (7) below to accommodate such changes.

$$e^{-d((s,a),g)} \leftarrow \mathbb{E}_{\{(s_t, a_t), s_t^w\} \sim \mathcal{D}} [\gamma^{k'} \cdot e^{-d(s_t^w, g)}]. \quad (9)$$

We denote this new objective as \mathcal{T}_β , as the future state of the sample is restricted by trajectories generated by π_β . This is similar to the n -step returns in prior work (Li et al., 2025; Munos et al., 2016; Sutton, 1988), although we do not sample future states with a fixed number of steps. In practice, we can use any loss function to make the LHS equal to the RHS (in expectation) concerning Eq. (7) and Eq. (9). We use a form of Bregman divergence with LINEX losses (Parsian and Kirmani, 2002), as it does not incur vanishing gradients when the two distances have become close in value (Banerjee et al., 2004):

$$D_T(d, d') \triangleq \exp(d - d') - d' \quad (10)$$

Using this loss, we can concretely define both $\mathcal{L}_{\mathcal{T}_\beta}$ and $\mathcal{L}_{\mathcal{T}}$ that can optimize the objectives of \mathcal{T} and \mathcal{T}_β .

$$\mathcal{L}_{\mathcal{T}_\beta}(\phi, \psi; \{s_i, a_i, s_i^w, g_i, k'_i\}_{i=1}^N) = \sum_{i=1}^N \sum_{j=1}^N D_T(d((s_i, a_i), g_j), d(s_i^w, g_j)) - k'_i \log \gamma. \quad (11)$$

These two losses, when applied to our quasimetric network, will allow us to propagate the value in either a onestep or multistep manner.

Remark: relationship between p , multistep backup \mathcal{T}_β , and onestep backup \mathcal{T} . By changing p , we can adjust the distance (in expectation) from the waypoint from the current state, as $p = 1$ means that \mathcal{T}_β is equivalent to \mathcal{T} (as $k' = 1$). We demonstrate in Section 5.3 why only using $\mathcal{L}_{\mathcal{T}}$ is insufficient for learning a good distance representation and goal-conditioned policy.

4.2 Enforcing Action Invariance

With respect to quasimetric networks, (Myers et al., 2024) has demonstrated that if the training data is collected using a Markovian policy, then the optimal critic should observe the property of *Action Invariance*. As a result, the optimal critic should observe the following property (Sutton and Barto, 2018):

$$V_g^*(s) = \max_{a \in \mathcal{A}} Q_g^*(s, a). \quad (12)$$

This can be satisfied, under our construction, if $d(s, (s, a)) = 0$ for each action $a \in \mathcal{A}$ (Myers et al., 2025b) (action invariance). Since our construction of Q and value function do not observe this property, we need to enforce it using gradient descent, as described in Eq. (13).

$$d(\psi(s), \varphi(s, a)) \leftarrow 0 \quad (13)$$

One common failure case of basic regressions, such as using L_1 or L_2 regression for Eq. (13), is that the algorithm quickly converges to trivial solution in which $\varphi(s, a) = \psi(s) = 0$, which fails to learn any valuable distance measures. To counteract this, we use a smoother formulation that allows more relaxed enforcement of Eq. (13) when the violation is low in magnitude. As a result, we can define $\mathcal{L}_{\mathcal{I}}$ as:

$$\mathcal{L}_{\mathcal{I}}(\varphi, \psi; \{s_i, a_i\}_{i=1}^N) = \sum_{i,j=1}^N (e^{-d(\psi(s_i), \varphi(s_i, a_j))} - 1)^2. \quad (14)$$

Now the loss will scale with the magnitude of such deviation, which removes the need of hyperparameter tuning for an appropriate multiplier as well as stabilizing training dynamics.

4.3 Policy Extraction

We extract the goal-conditioned policy $\pi(s, g) : \mathcal{S}^2 \rightarrow \mathcal{A}$ using the learned distance using the behavior-regularized deep-deterministic policy gradient (DDPG + BC) (Fujimoto and Gu, 2021):

$$\mathcal{L}_\mu(\pi; \{s_i, a_i, g_i\}_{i=1}^N) = \mathbb{E} \left[\sum_{i,j=1}^N d((s_i, \pi(s_i, g_j)), g_j) - \alpha \log \pi(a_i | s_i, g_i) \right]. \quad (15)$$

Given that a smaller d measure correspond to a higher Q value, as defined in Eq. (5), we can maximize the Q values by minimizing the distance produced by our quasimetric network. We tune the BC coefficient α per environment. We provide more hyperparameter details in Section B.

4.4 Implementation Details & Algorithm

We concisely define our final learning objective in Algorithm 1. Unlike previous works in hierarchical RL (Nachum et al., 2018; Park et al., 2024b), we randomly sample these waypoints, and we learn a single critic Q that operates on \mathcal{S} and \mathcal{A} and a single goal-reaching policy π_μ . As a result, our method does not contain any additional components and is simpler to implement than these hierarchical methods.

Algorithm 1: Multistep Quasimetric Estimation

Require: Dataset \mathcal{D} , Batch size B , training iteration T , Probability p

- 1: Initialize quasimetric network \mathcal{Q} with parameters (φ, ψ) , goal-reaching policy π_μ
 - 2: **for** $t = 1 \dots T$ **do**
 - 3: Sample $\{s_i, a_i, s'_i, s_i^w, g_i\}_{i=1}^B \sim \mathcal{D}$ (8)
 - 4: Update \mathcal{Q} with multistep backup by minimizing $\mathcal{L}_{\mathcal{T}_\beta}(\varphi, \psi; \{s_i, a_i, s_i^w, k'_i\}_{i=1}^B)$ (9)
 - 5: Update \mathcal{Q} with action invariance constraints by minimizing $\mathcal{L}_{\mathcal{I}}(\varphi, \psi; \{s_i, a_i\}_{i=1}^B)$ (14)
 - 6: Update policy π_μ with DDPG+BC by minimizing $\mathcal{L}_\mu(\pi_\mu; \{s_i, a_i, g_i\}_{i=1}^B)$ (15)
 - 7: **return** π_μ
-

5 Experiments

Our goal of experiments is to understand the benefits MQE brings when it comes to enabling a policy to generalize compositionally (execute multiple tasks seen in training separately together) and in terms of horizon (generalize over a longer task when a similar but shorter task was seen in training set). To that end, we ask the following research questions:

1. How much does MQE improve the horizon generalization abilities of agents?
2. What qualitative improvements does MQE bring in terms of compositional generalization?
3. What are the design decisions to ensure the success of MQE?

Experiment setup Our experiments use challenging, long-horizon problems in offline RL benchmarks as well as real-world settings. We use OGBench (Park et al., 2025a) for our experiments on simulated benchmarks and the BridgeData setup (Walke et al., 2024) for our real-world evaluation.

5.1 Simulated Evaluation on Offline Goal-Reaching Tasks

We evaluate MQE in both locomotion and manipulation in OGBench (Park et al., 2025a). For locomotion tasks, in addition to the three standard sized mazes, we also designed a “colossal”-sized maze. This maze is 50% larger than that of the “giant”-sized mazes currently available on OGBench, and it requires

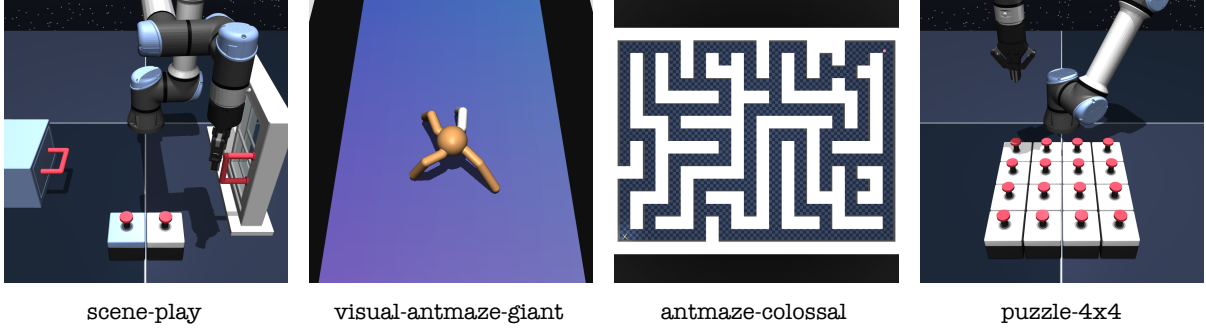


Figure 2: Tasks from various state and pixel-based environments for OGBench. Antmaze-colossal is 50% larger than any other mazes available on OGBench, and in *stitch* datasets, test the agent’s ability to generalize over horizon that is up to **1000%** longer.

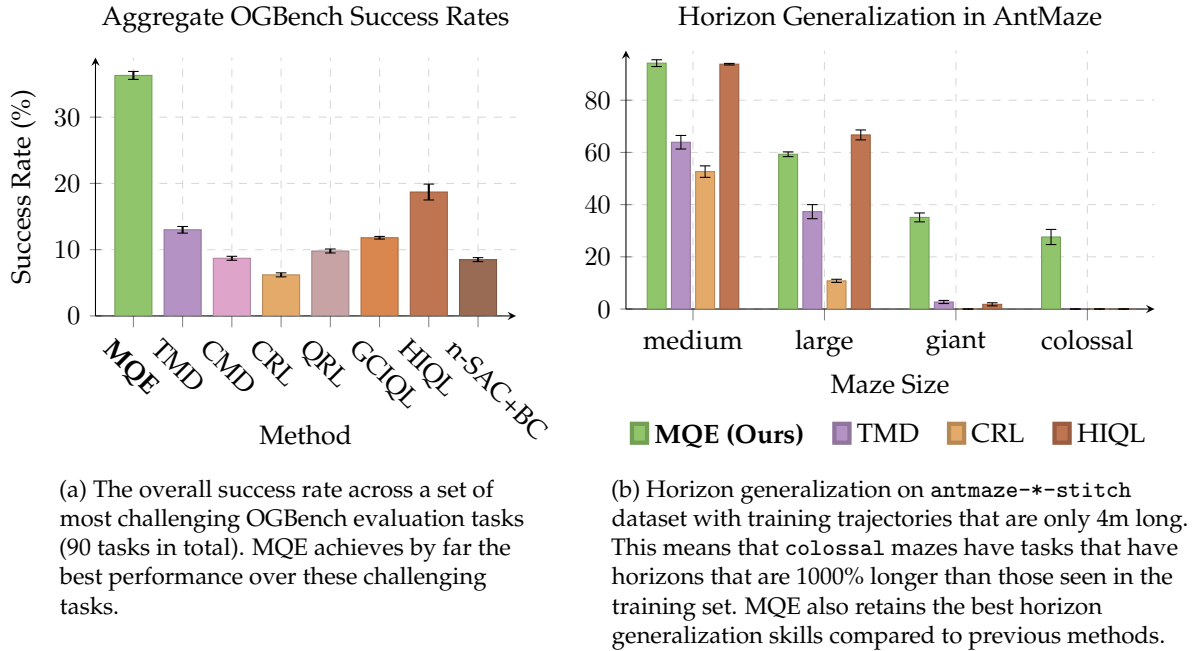


Figure 3: Comparisons of MQE against prior methods on OGBench.

as many as 4000 steps for an agent to traverse through the entire maze (see Fig. 2). We employ 13 state-based environments and 5 pixel-based environments (each pixel-based environment takes in a $64 \times 64 \times 3$ observation) with 5 tasks each, bringing a total of **90** tasks to evaluate in our OGBench setup.

We compare against the following baselines: GCIQL (Kostrikov et al., 2022), CRL (Eysenbach et al., 2022), QRL (Wang et al., 2023), HIQL (Park et al., 2024b), nSAC+BC (Haarnoja et al., 2018; Park et al., 2025b), CMD (Myers et al., 2024), and TMD (Myers et al., 2025b). These methods use either only TD learning (GCIQL, QRL, nSAC+BC), MC value estimation via contrastive learning (CRL, CMD, TMD), use horizon reduction techniques (nSAC+BC with value horizon, HIQL with policy horizon) or use a quasimetric architecture for distance learning (QRL, CMD, TMD). We detail how these methods are implemented in Section B. By comparing against these methods, we can gain a better outlook on *what* advantage MQE has over other works that learn distances only locally, globally, or in a hierarchical manner.

Table 4 and Fig. 3 show the performance of MQE across state- and pixel-based environments on OGBench. In general, MQE exhibits considerably better capabilities of extracting goal-reaching policies, and in

some instances (such as `humanoidmaze-giant-stitch`, exhibits a $10\times$ improvement over the previous best methods, including HIQL and n-SAC+BC, which does explicit policy horizon reduction. The only exception to this is vision-based manipulation, where HIQL performed better. We also compared the performance of MQE against TMD, CRL, and HIQL on `antmaze` of various sizes, with the training set fixed to only 4 meters long via the usage of `stitch` datasets. We show that as the evaluation horizon becomes longer, MQE still exhibits strong horizon generalization, and it is the *only* method that still exhibits nonzero success rates in `colossal` mazes.

5.2 Real-World Evaluation of MQE

While OGBench environments focus on learning long-horizon tasks using mixed quality data in a single environment, we can use real-world BridgeData tasks to evaluate a more sophisticated kind of compositionality. BridgeData tasks consist of individual object manipulation primitives (e.g. picking up a banana and placing it on a plate), and our evaluation tasks are significantly longer (up to $4\times$), requiring the composition of multiple tasks in the dataset (e.g. placing four different objects on the plate) (Walke et al., 2024). The dataset *does not contain any example trajectories* that compose multiple tasks in this way. Accomplishing this sort of temporal composition is an important goal in offline RL, because it allows “stitching” long behaviors out of shorter chunks.

We designed the tasks on BridgeData to test whether policies can compose multiple tasks at once without external guidance. Instead of instructing the policy to complete a single pick and place (abbreviated as PnP), we evaluate a policy’s performance with PnP of up to 4 objects in sequence. To our knowledge, such a task **has never been completed without the use of hierarchical policies or high-level planners**. We also evaluate the policy on tasks requiring dependencies (i.e. the second task can only succeed when the first task succeeds), with the policy being tasked with opening a drawer and then placing the item within the drawer all conditioned by one image of an opened drawer with an item inside. Only **one previous work** (Myers et al., 2025a) has shown consistent success when using an end-to-end policy, noting the challenges involved with this type of policy.

We use a 6DoF, 5Hz, WidowX250 manipulator for our robot learning tasks and we train and deploy a policy $\pi(a \mid s, g)$ conditioned on observations and goal images. We compare against the following methods: GCBC (Ding et al., 2020), GCIQL, and TRA (Myers et al., 2025a). We compare MQE against GCIQL, a commonly used offline RL method, and we compare MQE against both GCBC (Ding et al., 2020) and TRA (Myers et al., 2025a). Comparisons against both GCBC and TRA are important as , TRA learns a set of representations that align present and future representations for compositional generalization. TRA is designed for following both goal images and language instructions, but we only use goal images as the modality to test. We provide more details on policy training in Section C.1.

As in prior work that focused on long-horizon manipulation tasks (Black et al., 2024; Shi et al., 2025), we use task progress to measure the effectiveness of these policies due to the long-horizon nature of these tasks. We detail more on the experimental setup and how we assign progress in Section C.1.

Fig. 5 reports the *overall task progress* on 2 single-stage tasks and 4 tasks that require compositionality, and Table 6 reports the binary success rate of each task. We provide further analysis of policy rollout in

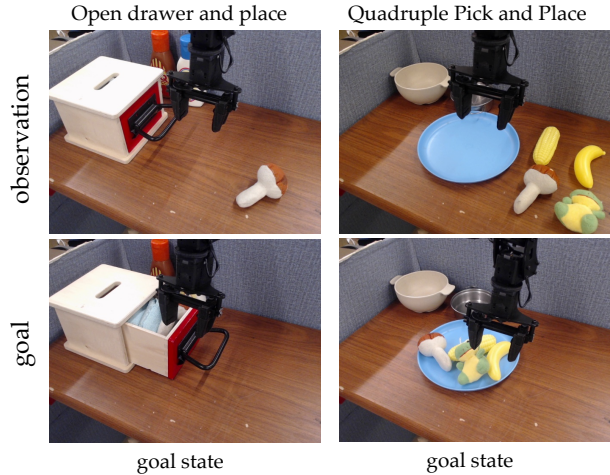


Figure 4: We evaluate MQE on multi-stage manipulation tasks on BridgeData. Below are examples of the starting observations and goal image being passed in.



Figure 6: MQE allow a robot to perform up to 4 tasks consecutively when evaluated on BridgeData.

Section C. Here, we observe that while MQE helps with single-stage tasks (single PnP, open drawer) against GCBC, both TRA and GCIQL can still perform competitively. However, as the number of tasks needed to be performed in sequence increases, we see that MQE is able to retain a relatively high task progress, while both GCIQL and TRA’s performance regressed.

Taking a look at the two most difficult tasks, we have quadruple PnP and drawer open and place. These tasks are the most challenging since quadruple PnP required the agent to reason 4 consecutive primitives together, and drawer open and place required the agent to complete the first task (open the drawer) before completing the second task (putting the mushroom in the drawer). Among all methods that we have tested, only MQE and TRA displayed positive success rate, as demonstrated in Table 6. We provide more details on policy rollouts in Section C.

5.3 Ablation Studies

In this section, we explore the design choices involved for MQE. To that end, we investigate the heuristics needed for MQE. We use the `humanoidmaze-giant-stitch` environment and dataset, and explore the following design questions:

- How do different distributions for sampling the waypoint s_t^w affect MQE’s success?
- Is the objective of action invariance \mathcal{I} necessary in MQE?
- How do λ and p , the two hyperparameters that affect the geometric sampling of s_t^w , change MQE’s performance?

Should we use action invariance? Table 1a shows that when using the same set of hyperparameters, imposing action invariance as an explicit term helps to learn a much better critic, as compared to only using $\mathcal{L}_{\mathcal{T}_\beta}$.

How should we sample our waypoints? We first evaluate the best distribution to sample future waypoints. Table 1b shows that when using a geometric distribution, we achieved much better performance than using a uniform distribution or using a fixed interval. We believe that since the goals are sampled via a geometric distribution, matching the waypoint with another geometric distribution helps the network to generalize better between the two separate observations.

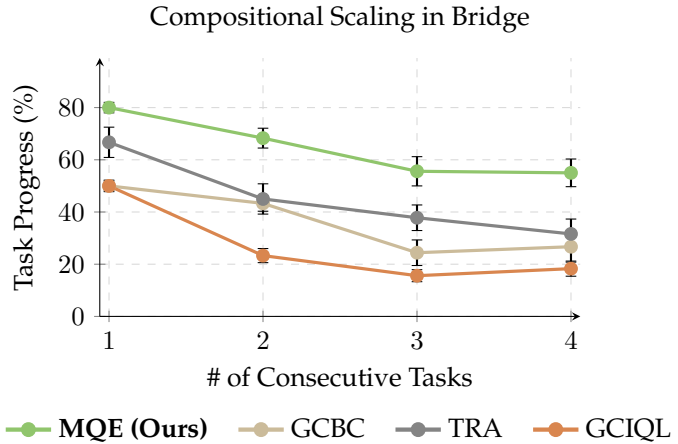


Figure 5: Task progress on BridgeData tasks based on how many consecutive tasks the agent is required to perform, plotted with both the mean and the standard error bars.

Table 1: Ablation results.

(a) $\mathcal{L}_{\mathcal{T}}$ Ablation		(b) s_t^w Sampling Ablation	
Configuration	Success Rate (%)	Configuration	Success Rate (%)
With $\mathcal{L}_{\mathcal{T}}$	26.5	$k' \sim \text{Geom}(1 - \lambda)$	26.5
Without $\mathcal{L}_{\mathcal{T}}$	7.9	$k' \sim \text{Unif}[1, K]$	18.9
		$k' \sim \text{Unif}[1, 50]$	17.8
		$k' = 50$	1.7

We then investigate how to combine the hyperparameters λ and p for best performance. Fig. 7 provides an illustration of success rate over pairs of (p, λ) . The figure suggests that both hyperparameters need to be relatively high in value. This indicates that MQE needs: (1) a waypoint far enough for the value to rapidly propagate and (2) a high enough p to ensure that local consistencies are being respected. We also see that if we increase the value of the sampling coefficient p , MQE cannot learn a good policy for goal-reaching. This shows that \mathcal{T} is *not* sufficient to learn a good distance for policy learning, as the agent did not learn a good distance representation.

6 Conclusion

We introduced Multistep Quasimetric Estimation (MQE), a novel method that combines the benefits of fast value propagation via multistep backup and the global constraint of quasimetric distances. MQE is able to solve challenging and long-horizon tasks in simulated benchmarks and on a real-world robotic manipulator.

Limitations and Future Work. While MQE achieves strong performance, we sample the waypoints based on empirical analyses. This could incur more computational costs when finding the optimal way of sampling the waypoint for environments that are outside of our evaluation range. Future work can investigate the theoretical connection between sampling waypoints and successor distances, investigate the effect of such policy learning on different policy classes such as autoregressive (i.e. transformer) or flow policies, and apply the same method across methods beyond offline RL in scenarios such as offline-to-online RL.

Acknowledgements We would like to thank Seohong Park, Qiyang Li, Michael Psenka, and Kwanyoung Park for helpful discussions. This material is based upon work supported by the National Science Foundation under Award No. 2441665 and ONR N00014-25-1-2060. Any opinions, findings and conclusions or recommendations expressed in this material are those of the author(s) and do not necessarily reflect the views of the NSF and ONR.

References

- Kristopher De Asis, J. Fernando Hernandez-Garcia, G. Zacharias Holland, and Richard S. Sutton. Multistep Reinforcement Learning: A Unifying Algorithm. arXiv:1703.01327, 2018.
- Philip J. Ball, Laura Smith, Ilya Kostrikov, and Sergey Levine. Efficient Online Reinforcement Learning With Offline Data. *International Conference on Machine Learning*, 2023.



Figure 7: Success rate of MQE on humanoidmaze_giant_stitch using $\alpha = 0.01$, averaged over 4 seeds.

- Arindam Banerjee, Srjana Merugu, Inderjit Dhillon, and Joydeep Ghosh. Clustering With Bregman Divergences. *SIAM International Conference on Data Mining*, pp. 234–245, 2004.
- Kevin Black, Noah Brown, Danny Driess, Adnan Esmail, Michael Equi, Chelsea Finn, Niccolo Fusai, Lachy Groom, et al. π_0 : A Vision-Language-Action Flow Model for General Robot Control. arXiv:2410.24164, 2024.
- Léonard Blier, Corentin Tallec, and Yann Ollivier. Learning Successor States and Goal-Dependent Values: A Mathematical Viewpoint. arXiv:2101.07123, 2021.
- David Brandfonbrener, Alberto Bietti, Jacob Buckman, Romain Laroche, and Joan Bruna. When does return-conditioned supervised learning work for offline reinforcement learning? arXiv:2206.01079, 2023.
- Ştefan Cobzaş. *Quasi-metric and Quasi-uniform Spaces*, pp. 1–97. Springer Basel, Basel, 2013.
- Peter Dayan. Improving Generalisation for Temporal Difference Learning: The Successor Representation. *Neural Computation*, (4):613–624, 1993.
- Yiming Ding, Carlos Florensa, Mariano Phielipp, and Pieter Abbeel. Goal-conditioned Imitation Learning. arXiv:1906.05838, 2020.
- Benjamin Eysenbach, Vivek Myers, Ruslan Salakhutdinov, and Sergey Levine. Inference via Interpolation: Contrastive Representations Provably Enable Planning and Inference. *Neural Information Processing Systems*, 2024.
- Benjamin Eysenbach, Ruslan Salakhutdinov, and Sergey Levine. C-Learning: Learning to Achieve Goals via Recursive Classification. *International Conference on Learning Representations*, 2021.
- Benjamin Eysenbach, Tianjun Zhang, Ruslan Salakhutdinov, and Sergey Levine. Contrastive Learning as Goal-Conditioned Reinforcement Learning. *Neural Information Processing Systems*, volume 35, pp. 35603–35620, 2022.
- Scott Fujimoto and Shixiang Shane Gu. A Minimalist Approach to Offline Reinforcement Learning. *Neural Information Processing Systems*, 34:20132–20145, 2021.
- Divyansh Garg, Joey Hejna, Matthieu Geist, and Stefano Ermon. Extreme Q-Learning: MaxEnt RL without Entropy. arXiv:2301.02328, 2023.
- Raj Ghugare, Matthieu Geist, Glen Berseth, and Benjamin Eysenbach. Closing the Gap Between TD Learning and Supervised Learning – a Generalisation Point of View. *International Conference on Learning Representations*, 2024.
- Tuomas Haarnoja, Aurick Zhou, Pieter Abbeel, and Sergey Levine. Soft Actor-Critic: Off-Policy Maximum Entropy Deep Reinforcement Learning With a Stochastic Actor. *International Conference on Machine Learning*, 2018.
- Kento Kawaharazuka, Jihoon Oh, Jun Yamada, Ingmar Posner, and Yuke Zhu. Vision-Language-Action Models for Robotics: A Review Towards Real-World Applications. *IEEE Access*, 13:162467–162504, 2025.
- Ilya Kostrikov, Ashvin Nair, and Sergey Levine. Offline Reinforcement Learning With Implicit Q-Learning. *International Conference on Learning Representations*, 2022.
- Aviral Kumar, Aurick Zhou, George Tucker, and Sergey Levine. Conservative Q-Learning for Offline Reinforcement Learning. *Neural Information Processing Systems*, volume 33, pp. 1179–1191, 2020.
- Qiyang Li, Zhiyuan Zhou, and Sergey Levine. Reinforcement Learning With Action Chunking. arXiv:2507.07969, 2025.
- Timothy P. Lillicrap, Jonathan J. Hunt, Alexander Pritzel, Nicolas Heess, Tom Erez, Yuval Tassa, David Silver, and Daan Wierstra. Continuous control with deep reinforcement learning. arXiv:1509.02971, 2019.
- Bo Liu, Yihao Feng, Qiang Liu, and Peter Stone. Metric Residual Networks for Sample Efficient Goal-Conditioned Reinforcement Learning. arXiv:2208.08133, 2023.

- Jianlan Luo, Zheyuan Hu, Charles Xu, You Liang Tan, Jacob Berg, Archit Sharma, Stefan Schaal, Chelsea Finn, Abhishek Gupta, and Sergey Levine. SERL: A Software Suite for Sample-Efficient Robotic Reinforcement Learning. *International Conference on Robotics and Automation*, 2025.
- Max Sobol Mark, Tian Gao, Georgia Gabriela Sampaio, Mohan Kumar Srirama, Archit Sharma, Chelsea Finn, and Aviral Kumar. Policy Agnostic RL: Offline RL and Online RL Fine-Tuning of Any Class and Backbone. arXiv:2412.06685, 2024.
- Volodymyr Mnih, Koray Kavukcuoglu, David Silver, Alex Graves, Ioannis Antonoglou, Daan Wierstra, and Martin Riedmiller. Playing Atari With Deep Reinforcement Learning. arXiv:1312.5602, 2013.
- Rémi Munos, Tom Stepleton, Anna Harutyunyan, and Marc G. Bellemare. Safe and Efficient Off-Policy Reinforcement Learning. arXiv:1606.02647, 2016.
- Vivek Myers, Bill Chunyuan Zheng, Anca Dragan, Kuan Fang, and Sergey Levine. Temporal Representation Alignment: Successor Features Enable Emergent Compositionality in Robot Instruction Following. arXiv:2502.05454, 2025a.
- Vivek Myers, Bill Chunyuan Zheng, Benjamin Eysenbach, and Sergey Levine. Offline Goal Conditioned Reinforcement Learning With Temporal Distance Representations. *Neural Information Processing Systems*, 2025b.
- Vivek Myers, Chongyi Zheng, Anca Dragan, Sergey Levine, and Benjamin Eysenbach. Learning Temporal Distances: Contrastive Successor Features Can Provide a Metric Structure for Decision-Making. *International Conference on Machine Learning*, 2024.
- Ofir Nachum, Shixiang Gu, Honglak Lee, and Sergey Levine. Data-Efficient Hierarchical Reinforcement Learning. arXiv:1805.08296, 2018.
- Mitsuhiko Nakamoto, Oier Mees, Aviral Kumar, and Sergey Levine. Steering Your Generalists: Improving Robotic Foundation Models via Value Guidance. arXiv:2410.13816, 2025.
- Abby O’Neill, Abdul Rehman, Abhiram Maddukuri, Abhishek Gupta, Abhishek Padalkar, Abraham Lee, Acorn Pooley, Agrim Gupta, et al. Open X-Embodiment: Robotic Learning Datasets and RT-X Models. *International Conference on Robotics and Automation*, 2024.
- Seohong Park, Kevin Frans, Benjamin Eysenbach, and Sergey Levine. OGBench: Benchmarking Offline Goal-Conditioned RL. *International Conference on Learning Representations*, 2025a.
- Seohong Park, Kevin Frans, Sergey Levine, and Aviral Kumar. Is Value Learning Really the Main Bottleneck in Offline RL? arXiv:2406.09329, 2024a.
- Seohong Park, Kevin Frans, Deepinder Mann, Benjamin Eysenbach, Aviral Kumar, and Sergey Levine. Horizon Reduction Makes RL Scalable. arXiv:2506.04168, 2025b.
- Seohong Park, Dibya Ghosh, Benjamin Eysenbach, and Sergey Levine. HIQL: Offline Goal-Conditioned RL With Latent States as Actions. *Neural Information Processing Systems*, 2024b.
- Seohong Park, Tobias Kreiman, and Sergey Levine. Foundation Policies With Hilbert Representations. arXiv:2402.15567, 2024c.
- Ahmad Parsian and SNUA Kirmani. Estimation under LINEX loss function. *Handbook of applied econometrics and statistical inference*, pp. 75–98. CRC Press, 2002.
- Ethan Perez, Florian Strub, Harm de Vries, Vincent Dumoulin, and Aaron Courville. FiLM: Visual Reasoning With a General Conditioning Layer. *AAAI Conference on Artificial Intelligence*, 2017.
- Silviu Pitis, Harris Chan, Kiarash Jamali, and Jimmy Ba. An Inductive Bias for Distances: Neural Nets That Respect the Triangle Inequality. *International Conference on Learning Representations*, 2020.
- John Schulman, Philipp Moritz, Sergey Levine, Michael Jordan, and Pieter Abbeel. High-Dimensional Continuous Control Using Generalized Advantage Estimation. *International Conference on Learning Representations*, 2016.
- Younggyo Seo, Carmelo Sferrazza, Haoran Geng, Michal Nauman, Zhao-Heng Yin, and Pieter Abbeel. FastTD3: Simple, Fast, and Capable Reinforcement Learning for Humanoid Control. arXiv:2505.22642, 2025.

- Lucy Xiaoyang Shi, Brian Ichter, Michael Equi, Liyiming Ke, Karl Pertsch, Quan Vuong, James Tanner, Anna Walling, et al. Hi Robot: Open-Ended Instruction Following with Hierarchical Vision-Language-Action Models. arXiv:2502.19417, 2025.
- Laura Smith, Yunhao Cao, and Sergey Levine. Grow Your Limits: Continuous Improvement With Real-World RL for Robotic Locomotion. arXiv:2310.17634, 2023.
- R. Sutton. Learning to predict by the method of temporal differences. *Machine Learning*, 3:3–9–44, 1988.
- Richard S. Sutton and Andrew G. Barto. *Reinforcement Learning: An Introduction*. The MIT Press, second edition, 2018.
- Dong Tian, Ge Li, Hongyi Zhou, Onur Celik, and Gerhard Neumann. Chunking the Critic: A Transformer-Based Soft Actor-Critic With N-Step Returns. arXiv:2503.03660, 2025.
- Aaron van den Oord, Yazhe Li, and Oriol Vinyals. Representation Learning With Contrastive Predictive Coding. arXiv:1807.03748, 2019.
- Andrew Wagenmaker, Mitsuhiko Nakamoto, Yunchu Zhang, Seohong Park, Waleed Yagoub, Anusha Nagabandi, Abhishek Gupta, and Sergey Levine. Steering Your Diffusion Policy With Latent Space Reinforcement Learning. arXiv:2506.15799, 2025.
- Homer Walke, Kevin Black, Abraham Lee, Moo Jin Kim, Max Du, Chongyi Zheng, Tony Zhao, Philippe Hansen-Estruch, et al. BridgeData V2: A Dataset for Robot Learning at Scale. arXiv:2308.12952, 2024.
- Tongzhou Wang, Antonio Torralba, Phillip Isola, and Amy Zhang. Optimal Goal-Reaching Reinforcement Learning via Quasimetric Learning. *International Conference on Machine Learning*, pp. 36411–36430, 2023.
- Christopher Watkins. *Learning From Delayed Rewards*. phdthesis, 1989.
- Charles Xu, Qiyang Li, Jianlan Luo, and Sergey Levine. RLDG: Robotic Generalist Policy Distillation via Reinforcement Learning. arXiv:2412.09858, 2024.
- Chongyi Zheng, Benjamin Eysenbach, Homer Walke, Patrick Yin, Kuan Fang, Ruslan Salakhutdinov, and Sergey Levine. Stabilizing Contrastive RL: Techniques for Robotic Goal Reaching From Offline Data. *International Conference on Learning Representations*, 2024.

A Website and Code

We provide the full implementation of MQE, TMD, CMD, and the new antmaze-colossal mazes on OGBench <https://anonymous.4open.science/r/ogbench-D4D9/>. We provide website for MQE at <https://anonymous.4open.science/w/mqe-paper-686D/>.

B OGBench Experiment Details

B.1 Baseline Details

Here, we briefly describe the inner workings of each baseline on OGBench.

Goal-conditioned Implicit Q-learning (**GCIQL**) uses expectile regression to learn a value function. Quasimetric RL (**QRL**) learns a quasimetric distance using bootstrapping under a quasimetric architecture, and constrains the distance with one-step cost in *deterministic* settings. Contrastive RL (**CRL**) uses binary cross entropy to regress the critic (defined as a dot product) towards goals that are future states and repel those that are not. Contrastive Metric Distillation (**CMD**) uses InfoNCE loss (van den Oord et al., 2019) to recover Q_β . Temporal Metric Distillation (**TMD**) (Myers et al., 2025b) use contrastive learning to learn the behavior Q-function, and then tightens the bound to optimize towards Q^* . CMD and TMD enforce the quasimetric property of successor distance architecturally.

Additionally, we compare MQE against two horizon reduction methods, n-step Goal-Conditioned Soft Actor-Critic with Behavior Cloning (**n-SAC+BC**) and Hierarchical Implicit Q learning (**HIQL**), which

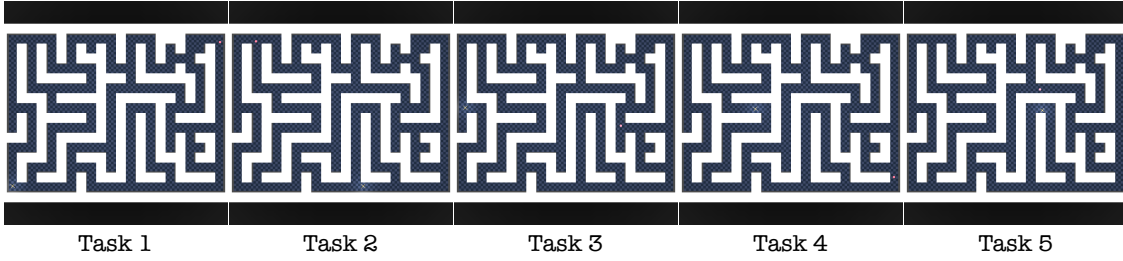


Figure 8: Task visualizations from antmaze-colossal environment. The ant occupies the starting position, and it must reach the red dot to complete the task.

Table 2: Network configuration for MQE on OGBench.

Configuration	Value
batch size	256
latent dimension size	512
encoder MLP dimensions	(512, 512, 512)
policy MLP dimensions	(512, 512, 512)
layer norm in encoder MLPs	True
visual encoder (visual- envs)	impala-small
MRN components	8
Discount (γ)	0.995
Waypoint discount (λ)	0.95
Probability p for sampling next state s'_t for waypoint	0.2 (state-based), 0.1 (pixel-based)

explicitly reduce the policy and value horizon separately. n-SAC+BC is similar to SAC+BC, but with n -step updates as described in Eq. (16) for a sampled batch \mathcal{B} .

$$\mathcal{L}_Q = \mathbb{E}_{\{s_i, a_i, \dots, s_{i+n}, a_{i+n}, g\} \sim \mathcal{B}} [\mathcal{L}_{\text{BCE}}(Q(s_h, a_h, g), \sum_{i=0}^{n-1} \gamma^i r(s_{h+i}, g) + \gamma^n \bar{Q}(s_{h+n}, \pi(s_{h+n}, g), g))] \quad (16)$$

Where $\mathcal{L}_{\text{BCE}}(x, y) \triangleq -y \log x - (1 - y) \log(1 - x)$, as it demonstrated superior performance in (Park et al., 2025b).

HIQL trains the same value function as GCIQL, but the agent extracts a hierarchical policy. All policies trained on OGBench are designed to return a multimodal Gaussian distribution $\mathcal{N}(\mu; \Sigma)$, and during inference time, the neural network produces the distribution, and the policy samples from that as action.

B.2 Task visualization

We provide the tasks used for antmaze-colossal environment on Fig. 8. The maze itself is 24 blocks in height and 18 blocks in width, which is 50% larger than the giant mazes in each dimension.

B.3 Implementation Details & Hyperparameters

Table 2 details the common hyperparameters for all methods on OGBench. Table 3

Table 3: BC coefficient α for each environment

Environment	α
antmaze-navigate	0.1
antmaze-stitch	0.03
antmaze-explore	0.003
humanoidmaze	0.01
pointmaze	0.03
{cube, puzzle, scene (play)}	1.0
{visual - {cube, puzzle, scene (play)}}	3.0
*-noisy	0.1
visual-antmaze	0.3

To regulate $\mathcal{L}_{\mathcal{I}}$, we impose a hyperparameter ζ to act as a multiplier. This ensures that across both visual and state-based environment, $\mathcal{L}_{\mathcal{I}}$ does not immediately overpower $\mathcal{L}_{\mathcal{T}_\beta}$. The final critic loss becomes:

$$\mathcal{L}_{\mathcal{Q}}(\varphi, \psi; \{s_i, a_i, s_i^w\}_{i=1}^B) = \mathcal{L}_{\mathcal{T}_\beta}(\varphi, \psi; \{s_i, a_i, s_i^w, k_i'\}_{i=1}^B) + \mathcal{L}_{\mathcal{I}}(\varphi, \psi; \{s_i, a_i\}_{i=1}^B) \quad (17)$$

We use LINEX losses (Garg et al., 2023; Parsian and Kirmani, 2002) to parameterize the Bregman divergence in $\mathcal{L}_{\mathcal{T}_\beta}$, and to prevent exploding gradients, we set the

We use a batch size of 256 for MQE, and we use NVIDIA A6000 GPUs for our experiments. For state-based environments, it takes around 2.5 hours to finish both training and evaluation. For pixel-based environments, it takes 6 hours to complete both training and evaluation.

B.4 Policy evaluation

We maintain an evaluation procedure similar to that of OGBench’s. We evaluated each policy 50 times the last 3 training epochs (800k, 900k, 1M step for state-based environments, 300k, 400k, 500k in pixel-based environments). For each of these evaluation epochs, use 8 seeds for every state-based environment and 4 seeds for every pixel-based environment.

B.5 Full Result Table

We record the full success rate of all tasks in OGBench in Table 4.

B.6 Visualizations

We provide visualizations on antmaze-large-explore to show the learned distances $d(s, g)$ for each s in the environment with Fig. 9. We calculate the distance in IQL using the learned value function $V_g(s)$ directly. For CRL, we use the following equation to calculate the distance to match the BCE formulation being used in it: $d(s, g) = -\log \sigma(\varphi(s, 0)^\top \psi(g))$, where 0 corresponds to zero vector with the same dimension as the action. Given that CMD only learns one representation $\varphi(s, a)$, we parameterize the distance as $d = d_{\text{MRN}}(\varphi(s, 0), \varphi(g, 0))$. In TMD, we use $d(s, g) = d(\psi(s), \psi(g))$, consistent with the paper.

Out of all the heatmaps, we see that both GCIQL and CMD carry features that are similar to L_2 distance, while CRL contains many visual artifacts. GCIQL also has the problem of value propagation, where only a small region around the goal actually has a low distance measure. TMD has the best visualization out of all baselines, but still suffer from minor artifacts. In contrast, MQE recovers a distance that has the desired structure, which makes it desirable for learning a good goal-reaching policy.

Table 4: OGBench Evaluation

Dataset	Methods							
	MQE	TMD	CMD	CRL	QRL	GCIQL	HIQL	n-SAC+BC
pointmaze_giant_navigate	72.8 (± 2.5)	39.9(± 5.2)	45.3(± 3.7)	27.4(± 3.4)	68.5 (± 2.8)	0.0(± 0.0)	45.9(± 3.0)	0.0(± 0.0)
pointmaze_giant_stitch	59.2 (± 3.2)	9.1(± 1.0)	8.1(± 0.6)	0.0(± 0.0)	49.7(± 2.3)	0.0(± 0.0)	0.0(± 0.0)	0.4(± 0.1)
antmaze_large_explore	67.7 (± 2.8)	0.9(± 0.2)	0.8(± 0.3)	0.3(± 0.1)	0.0(± 0.0)	0.4(± 0.1)	3.9(± 1.8)	0.2(± 0.1)
antmaze_giant_stitch	35.1 (± 1.7)	2.7(± 0.6)	2.0(± 0.5)	0.0(± 0.0)	0.4(± 0.2)	0.0(± 0.0)	1.8(± 0.6)	9.2(± 2.1)
antmaze_colossal_navigate	48.6 (± 2.4)	22.3(± 1.1)	22.5(± 3.1)	14.6(± 1.8)	0.0(± 0.0)	0.0(± 0.0)	0.0(± 0.0)	0.3(± 0.1)
antmaze_colossal_stitch	27.6 (± 2.9)	0.0(± 0.0)	0.2(± 0.1)	0.0(± 0.0)	0.0(± 0.0)	0.0(± 0.0)	0.0(± 0.0)	0.5(± 0.3)
humanoidmaze_giant_navigate	46.5 (± 2.5)	9.2(± 1.1)	5.0(± 0.8)	0.7(± 0.1)	0.4(± 0.1)	0.5(± 0.1)	12.5(± 1.5)	3.2(± 0.5)
humanoidmaze_giant_stitch	26.5 (± 1.3)	6.3(± 0.6)	0.2(± 0.1)	1.5(± 0.5)	0.4(± 0.1)	1.5(± 0.1)	3.3(± 0.7)	1.7(± 0.1)
cube_double_play	40.8 (± 1.2)	13.1(± 2.3)	0.2(± 0.1)	1.5(± 0.5)	0.4(± 0.1)	40.2 (± 1.7)	6.4(± 0.7)	19.1(± 0.3)
cube_triple_noisy	18.3 (± 2.2)	2.1(± 0.6)	1.5(± 0.5)	2.7(± 0.5)	3.4(± 0.4)	1.8(± 0.2)	2.6(± 0.4)	1.4(± 0.3)
puzzle_4x4_play	18.7(± 2.3)	10.0(± 1.4)	0.2(± 0.1)	1.5(± 0.5)	0.4(± 0.1)	25.7 (± 1.1)	7.4(± 0.7)	11.4(± 0.9)
scene_play	76.8 (± 2.1)	21.9(± 1.9)	1.2(± 0.4)	18.6(± 0.8)	5.4(± 0.3)	51.3(± 1.5)	38.2(± 0.9)	17.6(± 1.4)
scene_noisy	30.8 (± 1.6)	19.6(± 1.7)	4.0(± 0.7)	1.2(± 0.3)	9.1(± 0.7)	25.9(± 0.8)	25.2(± 1.3)	19.1(± 2.2)
visual_scene_play	38.1(± 3.2)	20.7(± 2.5)	16.1(± 2.2)	9.6(± 0.6)	5.4(± 0.3)	12.2(± 0.8)	49.9 (± 0.6)	7.1(± 1.2)
visual_cube_triple_play	19.8 (± 0.9)	17.9 (± 1.3)	18.9 (± 1.1)	16.9(± 1.1)	16.3(± 0.3)	15.2(± 0.6)	21.0 (± 0.2)	21.1 (± 2.4)
visual_cube_double_noisy	25.9(± 1.6)	14.2(± 1.3)	0.3(± 0.3)	6.0(± 1.4)	6.1(± 1.2)	21.6(± 0.9)	59.4 (± 1.6)	22.7(± 1.1)
visual_cube_triple_noisy	25.0 (± 1.2)	17.7(± 0.7)	16.1(± 0.7)	15.6(± 0.6)	8.6(± 2.1)	12.5(± 0.6)	21.0(± 0.7)	17.1(± 0.3)
visual_puzzle_4x4_play	17.9(± 1.6)	9.8(± 3.6)	7.2(± 0.4)	9.6(± 3.2)	0.0(± 0.0)	16.2(± 2.2)	60.1 (± 20.4)	10.3(± 2.6)
visual_antmaze_giant_stitch	26.9 (± 3.1)	14.5(± 2.5)	22.3 (± 1.9)	0.1(± 0.1)	0.0(± 0.0)	0.0(± 0.0)	0.2(± 0.1)	7.6(± 1.1)
Overall	36.3 (± 0.6)	13.0(± 0.5)	8.7(± 0.3)	6.2(± 0.3)	9.8(± 0.3)	11.8(± 0.2)	18.7(± 1.2)	8.5(± 0.3)

We **bold** the best performance. Success rate (%) is presented with the standard error across eight seeds for state-based environments and four seeds for pixel-based environments. All datasets contain 5 separate tasks each. We record the aggregate across all 5 tasks.

C BridgeData Experiment Details

We evaluated each policy with a total of 15 trials each for each task. For each of the pick-and-place tasks, we assign 1 points for each successful pick and place (i.e. move a desired object to the desired location). Therefore, a policy can earn a maximum of i points for each PnP task that manipulates i objects.

For open drawer and place, we assign one point if the policy opens the drawer to the extent where the mushroom can be placed, but does not pull the drawer off the base completely, and assign another point if the policy is able to put the mushroom in the drawer.

C.1 Training Configurations

We use a pretrained ResNet34 as the backbone of the policy and encoders. We do not share the actor and critic encoder for both GCIQL and MQE. We co-train the actor and the critic for a total of 500,000 total steps with a batch size of 128, which takes around 60 hours when the model is trained on 4 v4-8 TPUs. For TRA, we produce the embedding of two separate encoders ϕ, ψ , and align each other using symmetric InfoNCE loss. During inference, we use FiLM (Perez et al., 2017) to embed the learned goal representation into the actor, staying consistent with the implementation from (Myers et al., 2025a). In addition, we also describe the common hyperparameters used for BridgeData setup at Table 5.

C.2 Task Successes

Table 6 records the success rate of each task across all six tasks that we evaluate, and Fig. 10 records the task progress for each task. In Table 6, we only measure whether each task has been completed to its fullest. While it does give out a stronger signal on whether a task displays nonzero success rate, it does not provide as much information on how the task was progressing overall.

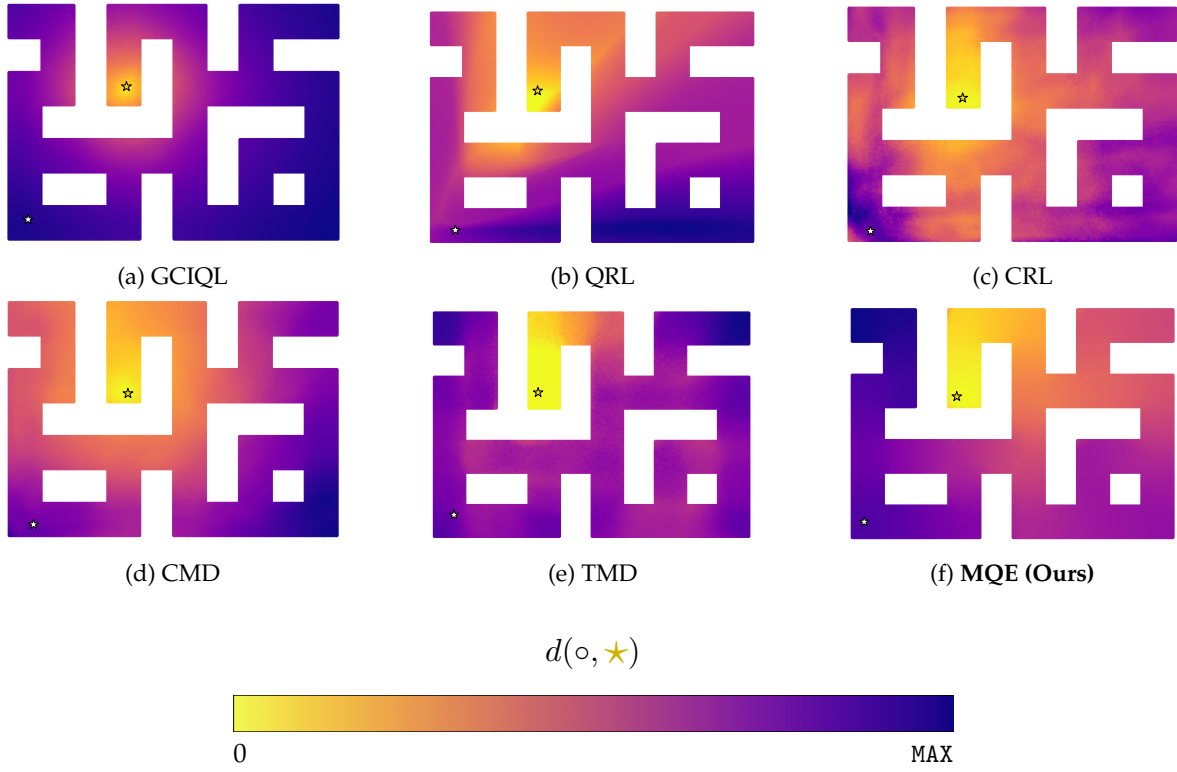


Figure 9: Comparisons of different learned distances. Brighter colors correspond to a lower distance measure. The agent starts at the position of the white star and the goal is set at the gold star. We compare especially the *structure* of the distance, as we normalize the ddpq loss in policy learning.

Table 5: Network configuration for MQE on BridgeData.

Configuration	Value
latent dimension size	256
encoder MLP dimensions	(256, 256, 256)
policy MLP dimensions	(256, 256, 256)
layer norm in encoder MLPs	True
MRN components	8
Discount (γ)	0.98
Waypoint discount (λ)	0.95
Probability p for directly imposing $\mathcal{L}_{\mathcal{T}}$	0.2

D Policy Rollout in BridgeData

We provide the rollout of `triple PnP` in Fig. 11. We especially consider TRA because it also exhibits compositional generalization, yet there is no explicit policy improvement as compared to offline RL methods such as MQE.

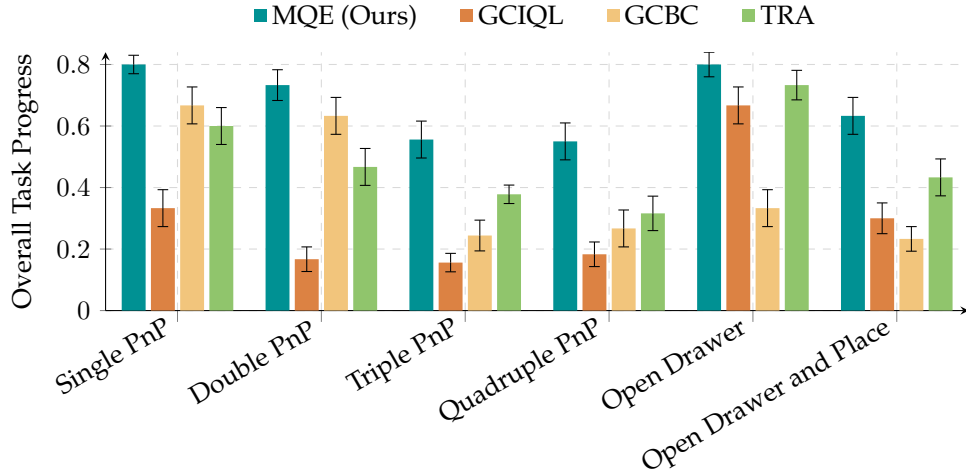


Figure 10: Task progress on BridgeData tasks; plotted with both the mean and the standard error bars.

Table 6: Binary success counts for each task.

Task	MQE (Ours)	GCBC	GCIQL	TRA
Single PnP	12/15	5/15	10/15	9/15
Double PnP	10/15	1/15	4/15	6/15
Triple PnP	4/15	0/15	0/15	1/15
Quadruple PnP	2/15	0/15	0/15	0/15
Open Drawer	12/15	10/15	5/15	11/15
Open Drawer & Place	5/15	0/15	0/15	1/15

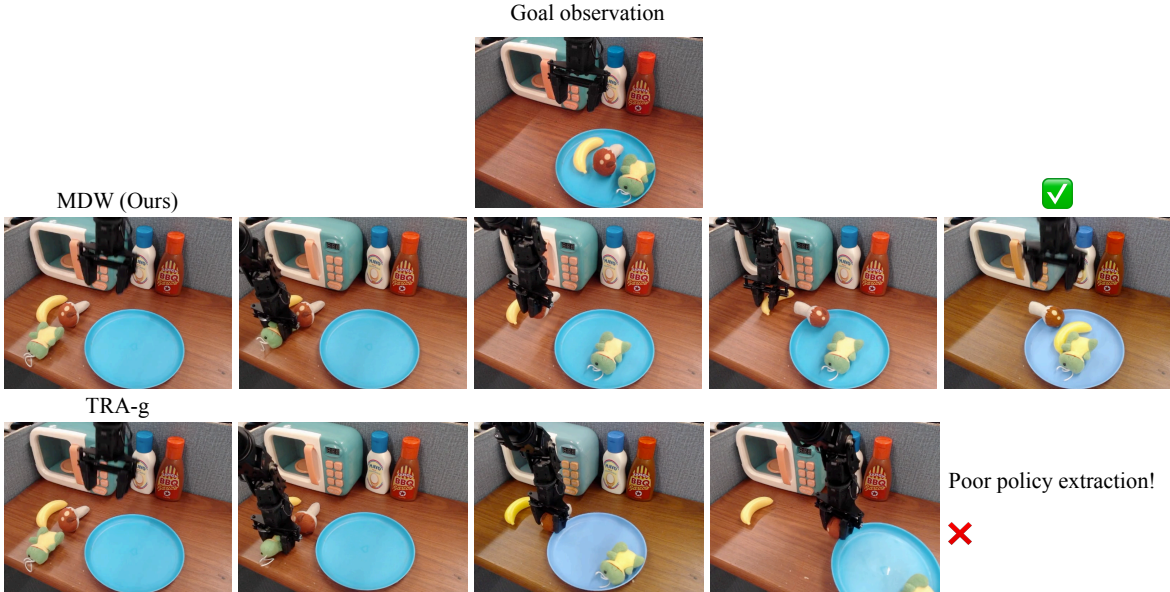


Figure 11: Inference from triple pnp task. We note that due to poor policy extraction and generalization, TRA is not able to complete the task.