How Foundational Skills Influence VLM-based Embodied Agents: A Native Perspective

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Abstract

Recent advances in vision–language models (VLMs) have shed light on human-level embodied intelligence. However, existing benchmark for VLM-driven embodied agent still rely on pre-defined high-level command or discretised action spaces—"non-native" settings that diverge markedly from the real world. Moreover, current benchmarks focus exclusively on high-level tasks, while lacking collaborative evaluation and analysis on both low- and high-level. To bridge these gaps, we present **NativeEmbodied**, a challenging benchmark for VLM-driven embodied agents that adopts a unified, native low-level action space. Built upon diverse simulated scenes, NativeEmbodied first designs three representative high-level tasks in complex scenarios to evaluate overall performance. For more detailed and comprehensive performance analysis, we further decouple the entangled skills behind complex tasks and construct four types of low-level tasks, each corresponding to a key fundamental embodied skill. This joint evaluation across task and skill granularities enables a fine-grained assessment of embodied agent. Comprehensive experiments on the best VLMs reveal pronounced deficiencies in certain fundamental embodied skills. Further analysis shows that these low-level bottlenecks severely constrain performance on high-level tasks. Our NativeEmbodied not only pinpoints the key challenges faced by current VLM-driven embodied agents, but also provides valuable insight for future development.

1 Introduction

Recent advances in Vision-Language Models (VLMs) have catalyzed significant progress in embodied intelligence Wang et al. (2024), bringing us closer to intelligent agents that can operate in the simulator or physical world Cheang et al. (2025); Wang et al. (2025); Open-X et al. (2025); Brohan et al. (2023). These VLM-based embodied agents, capable of perceiving the environment through visual inputs, and perform complex task following natural language instructions Chen et al. (2025); Tan et al. (2025); Cao et al. (2025); Long et al. (2025); Yue et al. (2025).

However, a fundamental challenge persists: How can we assess whether these models truly possess the capability to function in the real world, and which fundamental skills bottleneck their performance? This question becomes particularly important as current evaluation benchmarks for embodied agent exhibit several limitations: 1) **Non-Native Action Space**: Recent benchmarks Cheng et al. (2025); Yang et al. (2025) attempt to deploy VLM-based agents in embodied simulators and evaluate their performance through interactive tasks. They typically abstract low-level actions into high-level commands or functions that the agent can invoke directly (e.g., "look at the apple", "teleport to the desk") - what we term the "non-native" setting. This abstraction emphasizes task reasoning and planning, while eclipsing critical embodied skills such as spatial alignment and navigation, leading to a considerable gap from real world. 2) **Coupled Task Design**: Existing benchmarks focus on

Submitted to 39th Conference on Neural Information Processing Systems (NeurIPS 2025). Do not distribute.

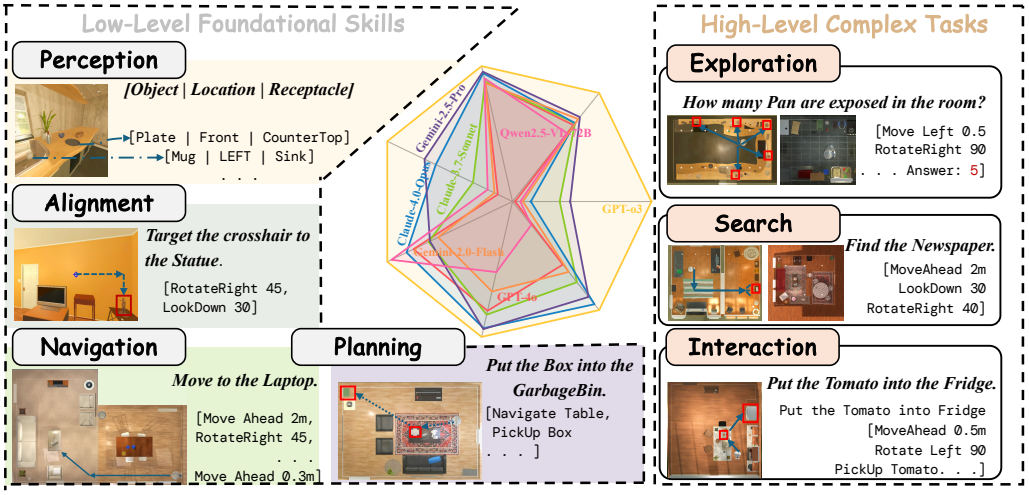


Figure 1: Our NativeEmbodied benchmark includes four low-level foundational skills (i.e., Perception, Alignment, Navigation and Planning) and three high-level complex tasks (i.e., Exploration, Interaction, and Search).

high-level tasks that entangle multiple foundational skills and measure model performance primarily by overall success rate. Such coarse-grained task formulation and evaluation hinder the diagnosis of skill-level bottlenecks, yielding assessments that are neither comprehensive nor sufficiently fine-grained. Those limitation highlights two critical questions that need to be addressed:

- Q1: Which foundational skills are truly essential for VLM-based embodied agents?
- Q2: How do these foundational skills affect the execution of higher-level tasks?

To answer the above questions, in this paper, we present **NativeEmbodied**, the first comprehensive benchmark that assesses VLMs' multidimensional embodied skills from a native perspective. The following key features set NativeEmbodied apart from the other benchmarks: **1) Native Rollout Setting.** Built on AI2THOR Kolve et al. (2022)—a widely used embodied simulator with richly detailed and populated environments—NativeEmbodied adopts a native rollout setting. During a rollout, the agent receives only the initial task instruction, action history, and the egocentric images streamed by the simulator. In each turn, the agent are allowed to specify action only from AI2THOR's primitive action set, includes parameterizable rotations and movements. In this way, the agent is free to explore and interact with the environment in a native manner, making the benchmark more closely aligned with real-world conditions compared to previous ones. **2) Decoupled Task Hierarchy.** NativeEmbodied not only designs three categories of representative high-level tasks, but also decouples four categories of low-level tasks based on them. Each of these low-level tasks corresponds to a fundamental embodied skill. The synergistic evaluation from complex high-level tasks to decoupled low-level tasks facilitates more comprehensive and granular skill assessment and bottleneck analysis.

Thereafter, we conducted extensive experiments and analyses with NativeEmbodied on 15 open-source and proprietary VLMs to explore the capabilities of existing embodied agents from a native perspective. Our contributions are summarized as follows:

- We introduce a novel multidimensional, multigranular evaluation benchmark built upon native action spaces, providing a more realistic perspective for VLM-based embodied agents.
- We present a comprehensive evaluation system for fundamental embodied skills at a more raw and native level, where high- and low-level tasks are collaboratively evaluated to reveal skill-level bottlenecks, significantly enhancing the explainability of capability assessment.
- We provide extensive experimental validation across 15 open-source and closed-source models, offering valuable insights, with all resources and implementations publicly available to facilitate further research in this field.

Table 1: Comparisons between our NativeEmbodied and previous benchmarks .

BenchMark	Size	Task Level	Multimodal	Native	Decoupled
ALFRED Shridhar et al. (2020a)	3,062	High	✔	✗	✗
ALFWorld Shridhar et al. (2020b)	274	High	✗	✗	✗
VLMbench Zheng et al. (2022)	4,760	Low	✔	✔	✗
Behavior-1k Li et al. (2023)	1,000	High	✔	✗	✗
Lota-bench Choi et al. (2024)	308	High	✗	✔	✗
GOAT-bench Khanna et al. (2024)	3,919	Low	✔	✔	✗
Embodied Agent Inferface Li et al. (2024)	438	High	✗	✗	✗
EmbodiedBench Li et al. (2024)	1,128	High&Low	✔	✗	✗
EmbodiedEval Cheng et al. (2025)	328	High	✔	✗	✗
NativeEmbodied (Ours)	1,085	High&Low	✔	✔	✔

2 Related Work

2.1 Embodied Agent Benchmarks

As shown in Table 1, recent years have witnessed a surge of benchmarks targeting vision-driven embodied agents, yet most remain domain-specific or modality-restricted. Classic benchmarks such as ALFWorld Shridhar et al. (2020b) and ALFRED Shridhar et al. (2020a) focus on high-level household tasks but ignore low-level control; conversely, VLMbench Zheng et al. (2022) and GOAT-bench Khanna et al. (2024) evaluate low-level manipulation and navigation, respectively, but are confined to isolated embodied skills. Concurrently, EmbodiedBench Yang et al. (2025) introduces a multi-domain suite spanning household, manipulation, and navigation, while relying on high-level action when dealing with high-level tasks. EmbodiedEval Cheng et al. (2025) proposes a multi-domain benchmark for VLMs, yet its limited scale (328 instances) and absence of low-level tasks highlight the need for more comprehensive benchmarks.

2.2 VLM-based Agents

VLM-based agents typically ingest an interleaved sequence of images, text instructions, and optionally past actions, then output either free-form text or discrete/continuous action functions (i.e., non-native setting) that a downstream executor maps to low-level controls Bai et al. (2023); Qin et al. (2025); Bai et al. (2025). This paradigm has powered game agents Xu et al. (2024) that generate controller commands from screen pixels and dialogue in Minecraft Jucys et al. (2024) and Pokémon Hu et al. (2024), as well as Mobile agents that navigate mobiles to book flights Lin et al. (2024); Li et al. (2025); Gu et al. (2025). When instantiated for embodied tasks, however, the agent must confront a native action space—open, close, pick up, and put down. In this paper, we hope the embodied agent can free to explore and interact with the environment in a native manner, making our benchmark more closely aligned with real-world conditions compared to previous ones.

3 NativeEmbodied Benchmark

From a native perspective, we start with the native actions an agent can take. Specifically, we collect these basic moves and build a benchmark, NativeEmbodied, that checks four low-level tasks (e.g., center alignment and navigation). Because each subtask is separate and mix-and-match, we then combine high-level tasks (e.g., search). Through this bottom-up, decoupled setup, we enable analysis of the relationships between foundational capabilities and finial task success rates, revealing critical pathways of VLM-based embodied agent.

3.1 Native Action Space

To support the native setting, we define the native action space as follows:

- MoveAhead x (meters): Move forward x meters
- MoveBack x (meters): Move backward x meters
- MoveLeft x (meters): Move left x meters

- MoveRight x (meters): Move right x meters
- RotateRight x (degrees): Rotate view right by x degrees
- RotateLeft x (degrees): Rotate view left by x degrees
- LookUp x (degrees): Tilt view upward by x degrees
- LookDown x (degrees): Tilt view downward by x degrees

The native actions described above ensure that agents can operate in the environment in a primitive and unconstrained manner. Notably, while previous benchmarks have incorporated similar action primitives for certain tasks, they either impose strict constraints on the agent's movement space through pre-built navigation graphs to simplify environmental complexity Cheng et al. (2025), or limit their application to low-level tasks with hardcoded action parameters Yang et al. (2025). Our NativeEmbodied represents the first benchmark to provide completely unrestricted native action space across both high-level and low-level tasks.

3.2 High-level Complex Tasks

We start with three representative high-level tasks that benchmark the agent's performance boundary in the native settings:

Exploration. This task poses questions related to objects in the environment, requiring agents to fully explore the environment to provide correct answers. We subdivide it into four subtypes:

- *Counting*: How many specified objects are exposed in the environment?
- *Localization*: Which receptacle does the specified object locate in?
- *Receptacle Content*: Which objects are (or aren't) on the specified receptacle?
- *Co-existence*: Which objects share a receptacle with the specified object?

Search. This task requires agents to precisely locate and target specified objects within the environment. We overlay a crosshair at the center of the agent's egocentric obseravtion image to indicate the focal point. The agent must approach the target object and align the crosshair with it to complete the task. This challenge demands that the agent not only identify the object's location but also navigate to it and execute fine-grained spatial alignment.

Interaction. The task requires the agent to interact with objects in the scene to fulfill user instructions. Concretely, we focus on the representative pick-and-place scenario: the agent must place a specified object into a specified receptacle. The target object may be exposed in the environment or stored inside a closed receptacle, and the destination receptacle may be one that does not need to be opened (e.g., a tabletop) or one that does (e.g., a refrigerator). For this task we augment the original action space with four additional interaction primitives: PickUp, PutIn, Open, and Close.

3.3 Low-level Foundational Skills

While high-level tasks reveal an agent's overall competence, they are not ideal for diagnosing specific skill deficiencies. The limitation is even starker in the native setting: here, a model's core embodied abilities are tested directly, yet the multi-skill nature of the high-level tasks masks individual bottlenecks. For better evaluation, we decompose the high-level tasks from a skill-centric perspective and introduce four classes of low-level tasks that each target a fundamental skills:

Perception. This task tests a model's perception by having it describe first-person images using a specific structured format following *[ObjectType] [Loaction] [Receptacle]*,corresponding to This approach combines visual and spatial perception, and its structured format facilitates fine-grained evaluation of each aspect, making the evaluation in this paper more intuitive and flexible.

Spatial Alignment. Similar to the search task, the agent must center its view on the object. To separate from skills like planning and navigation, we start the agent near the target, already visible. We limit actions to view adjustments only. Thus, the agent simply shifts its gaze for precise spatial alignment evaluation.

Navigation. We define the navigation task as follows: Given a target object, the agent is deemed successful upon reaching within 1 meter of that object. To ensure sufficient path complexity, the

agent is initialized at the corner of the room farthest from the target object. Meanwhile, the target object is guaranteed to remain visible within the agent's initial field of view, so that the challenge lies purely in the fundametal navigation capabilities.

Planning. The goal of this task is to evaluate an agent's task-planning ability. In essence, this ability corresponds to the brain's cognitive reasoning functions rather than the cerebellum's motor-control functions. To effectively decouple motor control from planning, we abstract the four basic motion primitives into directly callable navigation interfaces. We adopt an interactive-task framework because the explicit, multi-stage nature of its execution process is especially well-suited for fine-grained evaluation of planning capability.

3.4 Data Collection

We build the benchmark via a three-stage pipeline that combines automatic generation with human–machine collaborative filtering to ensure quality

Stage 1:Using AI2-THOR Kolve et al. (2022) and its metadata (3D coordinates, state flags, instance masks), we batch-generate candidate samples for each task. For the exploration task, we query all scene objects and their receptacles, then automatically instantiate the four predefined question types.

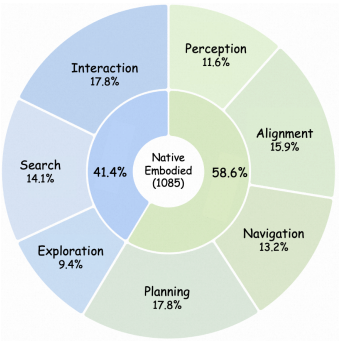
Stage 2: We deploy three advanced MLLMs, each performing three rollouts per sample, and track per-sample success rates. Samples perfectly solved by all three models are removed. Those with overall success rate greater than two-thirds, or solved perfectly by any single model, are forwarded for difficulty adjustment, while complete failures are forwarded for error checking.

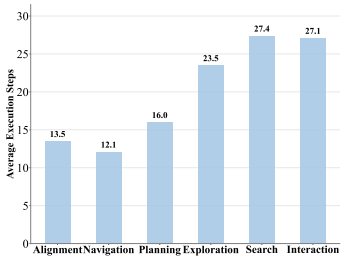
Stage 3: Human annotators manually run the complete failures to rule out environment-induced impossibility (e.g., the agent spawning in a dead end), and prune trivial high-success cases (e.g., the only apple is already in the initial view). Tasks perfectly solved by a particular model are treated as potential bias matches (e.g., consistently going to Table A). Adjusted samples are sent back to Stage 2 for reevaluation, and this loop iterates for three cycles.

More details of the data collection pipeline are provided in Appendix.

3.5 Dataset Statistics

Figure 2 show the detailed stastics of NativeEmbodied. NativeEmbodied contains 1085 high-quality samples across 3 high-level complex tasks and 4 low-level foundational skills. The 120 diverse scenes around 4 topics (including kitchen, bathroom, living-room, and bedroom) with 189 types of task-relevant object highlight the diverity of NativeEmbodied. The average execution steps of all tested models on NativeEmbodied reaches 18.7, reflecting its long-horizon nature in native setting.





Statistics	Number
Total tasks	1085
Total scene topics	4
Total scenes	120
Total objects	189
Avg. execution steps	18.7

Figure 2: The detailed Statistics of NativeEmbodied

4 Experiment

4.1 Evaluation Setup

Baselines. We evaluate 15 open-source and closed-source models, covering four model families:

- GPT family[1]: GPT-4o, GPT-4v, GPT-o3, GPT-o4-mini.
- Claude family[2]: Claude-3.5-Sonnet, Claude-3.7-Sonnet, Claude-4-Sonnet, Claude-4-Opus.
- Gemini family Gemini Team et al. (2024): Gemini-2.0-flash, Gemini-2.5-flash, Gemini-2.5-pro.
- Qwen family[3]: Qwen-2.5-VL-72B, Qwen-2.5-VL-32B, Qwen-2.5-VL-7B, Qwen-2.5-VL-3B.

Environment. During each agent–environment interaction, the agent receives an egocentric image from the simulator, which is rendered at 640 × 480 resolution with a 90-degree field of view, as input and returns a single action with specified parameters chosen from the action space. The rollout step limit is set to 15 for alignment and navigation tasks, 20 for planning tasks, and 30 for the three catogories of high-levek tasks. We employ a truncation mechanism to keep the interaction history to no more than 20 turns.

Evaluation Metrics. To obtain a more comprehensive and fine-grained picture of an agent's performance, we report the following metrics in addition to **Success Rate (SR)**:

- **Average Steps (AS):** The mean number of steps taken in successful episodes, reflecting how efficiently the agent completes a task.
- **Weighted Average Steps (WAS):** For each successful trajectory we use its *actual* length, whereas for each failed trajectory we assign a penalised length equal to the task's predefined maximum number of steps T plus a penalty factor $\alpha > 0$ (set to 1 in our experiment). Formally, let $\mathcal{S}$ and $\mathcal{F}$ be the sets of successful and failed episodes, s_i the number of steps taken in the i-th successful episode. The WAS is,

$$\text{WAS} = \frac{\sum_{i \in \mathcal{S}} s_i + \sum_{j \in \mathcal{F}} (\alpha + T)}{|\mathcal{S}| + |\mathcal{F}|}. \tag{1}$$

  A smaller WAS indicates that the agent not only succeeds frequently but also does so efficiently.
- **Average Closest Distance (ACD):** The shortest Euclidean distance between the agent and the target object across the trajectories.
- **Average Closest Pixel Distance (ACPD):** The mean of the minimum pixel distance between the target object and the view center across the trajectories.

We report **Precision**, **Recall**, and **F1** score for *Perception*.

4.2 Main Results

High-level tasks in native settings pose significant challenges for VLMs. Table 2 shows the performance of various VLMs on the three categories of high-level tasks. We find that even the most powerful VLMs generally struggle with high-level tasks under native settings. This is particularly evident in Search tasks, where the best-performing model GPT-o3 achieves only a 34.64% success rate, while Claude-4-Sonnet—despite being one of the most advanced proprietary models—fails to complete even a single task successfully. The same pattern holds for Interaction and Exploration tasks, with the highest success rates being merely 52.43% and 38.34% respectively. This indicates that in native embodied environments, current VLMs are still far from being capable of effectively executing complex tasks.

VLMs show varied performance on different low-level tasks. As shown in Table 3, we find that models demonstrate clear differentiation in performance across different task types. First, VLMs display generally excellent performance on perception tasks, indicating strong visual recognition abilities. Second, in planning tasks, VLMs similarly demonstrate strong capabilities, with proprietary models generally achieving success rates exceeding 50%. However, when tasks involve fine-grained operations in embodied environments, model performance shows a significant decline. In navigation tasks, more than half of the models achieve success rates below 50%, with the worst-performing proprietary model achieving only 27.78% success rate. Even more surprisingly are the results for

[1]https://openai.com/index/

[2]https://www.anthropic.com/news/claude-3-5-sonnet

[3]https://help.aliyun.com/zh/model-studio/developer-reference/use-qwen-by-calling-api

Table 2: Performance of closed-source and open-source LVLMs on the three high-level tasks: Exploration, Search and Interaction. For metrics, ↑ / ↓ mean "higher is better" / "lower is better".

Model	Exploration			Search				Interaction		
	Acc↑	AS↓	WAS↓	SR↑	ACPD↓	AS↓	WAS↓	SR↑	AS↓	WAS↓
Closed-Source Large Vision Language Models										
GPT-4o	36.89	12.32	24.11	0.65	131.29	25.0	30.96	22.28	12.25	26.84
GPT-4v	36.89	10.42	23.41	3.27	112.53	12.60	30.35	37.31	**12.07**	**24.03**
GPT-o3	**52.43**	11.06	20.54	**34.64**	**32.94**	15.60	**25.67**	**38.34**	13.35	24.25
GPT-o4-mini	40.78	5.48	20.59	17.64	37.93	13.07	27.84	26.42	13.33	28.27
Claude-3.5-sonnet	31.07	9.78	24.41	3.27	103.27	14.60	30.46	19.69	13.19	27.58
Claude-3.7-sonnet	37.86	14.67	24.81	11.76	68.13	14.33	29.04	28.50	12.93	26.17
Claude-4-sonnet	37.86	12.59	24.03	0	95.88	-	31.00	30.01	13.59	27.44
Claude-4-opus	37.86	12.72	24.08	4.58	84.17	**6.86**	29.82	36.27	12.48	24.87
Gemini-2.5-pro	40.78	**4.71**	**20.28**	14.38	35.89	7.91	27.68	33.68	12.17	24.67
Gemini-2.5-flash	40.78	6.40	20.97	12.42	58.49	11.58	28.59	32.64	14.46	25.98
Gemini-2.0-flash	39.81	11.51	23.24	2.61	90.83	14.75	30.58	24.87	13.53	26.79
Open-Source Large Vision Language Models										
Qwen2.5-VL-72B	33.01	11.82	24.67	1.96	130.40	7.00	30.69	8.29	13.63	28.37
Qwen2.5-VL-32B	31.07	14.63	25.41	1.31	129.93	23.00	30.83	6.74	13.15	29.61
Qwen2.5-VL-7B	28.16	11.61	26.14	0	131.26	-	31.00	1.55	25.00	30.83
Qwen2.5-VL-3B	25.24	8.13	26.03	0	131.68	-	31.00	0	-	31.00

Table 3: Performance of selected LVLMs on four low-level tasks: Perception, Spatial Alignment, Navigation and Planning. ↑ / ↓ denote "higher is better" / "lower is better".

Model	Perception			Spatial Alignment				Navigation				Planning		
	P↑	R↑	F1↑	SR↑	ACPD↓	AS↓	WAS↓	SR↑	ACD↓	AS↑	WAS↓	SR↑	AS↓	WAS↓
Closed-Source Large Vision Language Models														
GPT-4o	75.14	73.15	74.28	7.51	86.85	3.91	15.07	50.00	2.16	6.87	11.42	58.55	9.63	14.82
GPT-4v	79.51	78.11	78.83	6.94	66.81	3.23	15.12	55.56	2.23	7.81	11.43	62.18	9.25	14.04
GPT-o3	**83.15**	**84.51**	**83.97**	**64.16**	**22.73**	7.28	**10.4**	**63.19**	2.02	8.34	11.08	72.54	10.71	13.87
GPT-o4-mini	74.67	75.16	74.92	45.09	27.45	6.34	11.57	35.42	2.68	8.11	13.24	66.32	10.23	14.36
Claude-3.5-sonnet	76.59	72.33	73.82	9.83	63.38	**2.82**	14.72	47.92	2.01	7.83	12.12	55.44	10.40	15.55
Claude-3.7-sonnet	76.76	73.27	74.35	20.23	60.91	4.01	13.62	42.36	2.14	7.92	12.55	60.62	11.47	15.84
Claude-4-sonnet	77.51	73.58	74.77	36.41	29.39	6.63	11.83	27.78	2.43	4.39	12.76	67.36	10.33	14.30
Claude-4-opus	81.21	81.14	79.59	39.31	28.74	7.87	11.28	53.47	**1.72**	**4.11**	**9.74**	67.88	10.35	14.16
Gemini-2.5-pro	80.15	80.87	80.53	45.09	26.01	4.49	10.72	41.67	2.40	7.26	12.41	68.39	9.50	13.67
Gemini-2.5-flash	77.98	79.47	78.42	35.84	30.36	7.41	12.93	38.19	2.65	7.67	12.78	52.33	10.54	16.35
Gemini-2.0-flash	72.71	74.33	73.39	9.25	84.46	3.93	14.91	37.50	2.81	8.21	13.32	48.19	10.41	16.91
Open-Source Large Vision Language Models														
Qwen2.5-VL-72B	77.86	74.34	76.42	12.72	80.58	4.93	14.61	61.11	2.21	6.19	10.03	37.82	9.78	17.16
Qwen2.5-VL-32B	73.51	72.15	72.86	7.51	85.32	4.14	14.93	36.11	2.36	7.28	12.32	25.39	9.47	18.32
Qwen2.5-VL-7B	71.61	70.74	71.01	5.78	86.14	3.33	15.12	25.00	2.71	7.21	12.81	12.95	10.28	19.56
Qwen2.5-VL-3B	68.61	66.59	67.12	4.05	88.93	3.01	15.21	19.44	2.95	8.34	13.82	3.63	7.38	20.83

alignment tasks—these seemingly simple operations in daily life have become a major challenge for VLMs. Most models, except GPT-4o, fail to exceed a 50% success rate. Some closed-source models report single-digit success rates, highlighting deficiencies in spatial alignment capabilities. These findings suggest that while VLMs have advanced in certain areas, they lack essential skills for dynamic spatial interactions in specific tasks.

Mainstream VLMs exhibit distinct behavioral spectra in native setting. The contrast between high- and low-level tasks not only reveals the limitations of each model but also allows them to demonstrate distinct strategic tendencies in embodied environments.In the Navigation task, GPT-o3 leads with the highest success rate, yet at the cost of significantly longer average step counts, revealing a robust and conservative path-planning preference. In contrast Claude-4-Opus maintains over 50% success rate with less than half the steps of GPT-o3, and leads in both ACD and WAS metrics, reflecting a more aggressive, efficiency-first exploration style. In the Exploration tasks, GPT-o4-mini and Gemini-2.5-Pro have significantly fewer average steps than other models, yet still achieve high accuracy rates second only to GPT-o3, indicating that both are more agile and confident in collecting and utilizing environmental information.

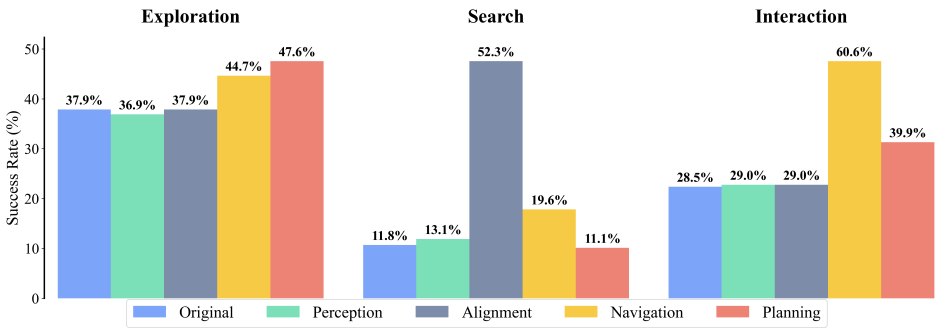


Figure 3: Results from the skill-oriented ablation study, aimed to precisely identify the key atomic skills that limit model performance.

4.3 Ablation Study of Foundational Skills

The main experimental results in Section 4.2 demonstrate that current VLMs exhibit significant limitations when executing complex tasks in native settings. To precisely identify the key foundational skills limiting model performance, we conducted systematic skill-oriented ablation experiments:

- Perception: We use AI2THOR's API to extract instance segmentation from each egocentric image, converting it into text descriptions through predefined templates as supplementary to the model.
- Alignment: A "LookAt" is provied for the agent to aim view into the target object if visible.
- Navigation: A "Navigate" is provided for the agent to teleport to the target object if visible.
- Planning: High-level tasks are decomposed into subtask sequences and executed step-by-step.

We selected Claude-3.5-Sonnet as our experimental subject, as this model demonstrates moderate performance in benchmark tests, offering good representativeness that facilitates more generalizable conclusions. As shown in Figure 3, the experimental results reveal three important insights:

Mature Perception Capabilities. The introduction of ground-truth perception information failed to significantly improve model performance,indicating current advanced VLMs already possess sufficient visual capabilities.

Dual Bottlenecks in Long-Horizon Tasks In Exploration and Interaction tasks, ablation on both planning and navigation yield significant improvements, indicating that both cognitive-level decision-making abilities (planning) and action-level execution abilities (navigation) are key bottlenecks for long-horizon tasks.

Fine-Grained Spatial Requirements in Search Tasks In Search tasks, improvements to navigation and alignment capabilities (particularly alignment) showed significant effects, while planning capability had limited impact. This reflects the unique characteristics of search tasks: their immediate-response nature reduces dependence on complex planning, but demands extremely high precision in spatial positioning and viewpoint control.

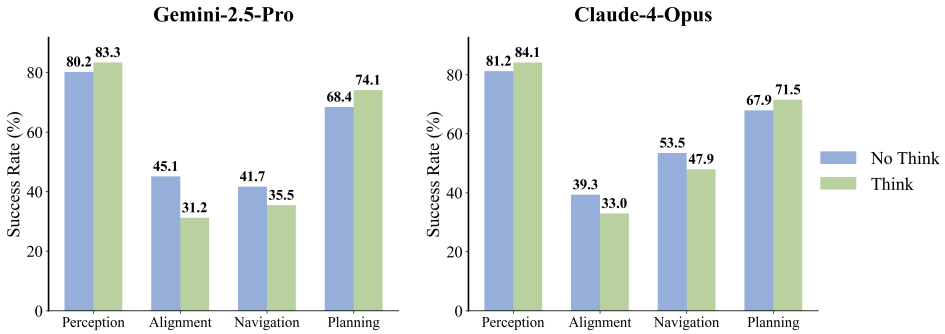


Figure 4: Ablation study of think mode, aimed to explore the capabilities of reasoning models.

4.4 Ablation Study of Think Mode

Reasoning models' improved problem-solving skills Huang et al. (2025); Liu et al. (2025); Gu et al. (2025), spark curiosity about whether this capability could boost embodied intelligence. To explore its potential, we selected two specialized reasoning models: Gemini-2.0-Flash-Thinking and Claude-3.5-Sonnet to think[4], then select an action, in each round of rollout. The experimental results are shown in Figure 4, from which we can draw the following insights:

Thinking enhances cognitive abilities for embodied environments. After enabling thinking mode, success rates for both perception and planning tasks increased, indicating that the reasoning process helps models better understand environmental states, identify key information, and formulate more reasonable action strategies. This improvement is particularly pronounced in tasks requiring complex reasoning and long-term planning.

Thinking may interfere with basic action execution. After engaging in thinking mode, success rates for tasks that require precise action, actually decreased significantly, such as alignment and navigation. This decline might be attributed to excessive reasoning processes, which can introduce unnecessary complexity and interfere with the intuitive execution of basic action.

These findings show that reasoning in embodied agents is a double-edged sword: it boosts cognitive skills but may disrupt motor control. This indicates a need for careful balance between "cerebrum" (cognitive reasoning) and "cerebellum" (action control) when designing these embodied agents.

4.5 Error Case Analysis

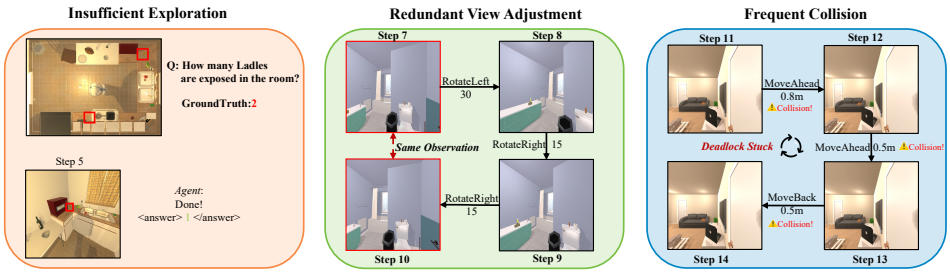


Figure 5: Case study of common error trajectories .

Figure 5 exhibited three categories of common errors during evaluation in NativeEmbodied:

- **Insufficient Exploration**: Agents fail to explore the environment thoroughly, prematurely drawing conclusions based solely on partial information, demonstrating overconfidence.
- **Redundant View Adjustment**: Agents frequently perform repetitive and unnecessary view adjustments within a considerable number of valid steps, severely reducing efficiency. Worse still, the resulting repetitive observations can sometimes lead agents into dead loops.
- **Frequent Collision**: Agents exhibit poor perception and response to environmental collisions, unable to make effective adjustments. This issue is particularly severe when agents are in confined spaces such as corners, where they easily become stuck and unable to escape.

5 Conclusion

In this work, we presented NativeEmbodied benchmark, a comprehensive benchmark for evaluating VLM-driven embodied agents using a unified, native low-level action space. Through systematic evaluation of both low-level and high-level tasks across 15 open-source and closed-source VLMs, we identified significant limitations in fundamental embodied capabilities that directly impact performance on complex tasks. Our findings not only highlight the current challenges in VLM-driven embodied intelligence but also provide valuable guidance for future development in this field.

[4]Notably, for reasoning models, we enable their reasoning mode; for non-reasoning models, we request them to output their thinking process in the prompt

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6 Appendix

We provide the evaluation samples of NativeEmbodied, evaluation scripts, and raw sample generation code at the following link: https://anonymous.4open.science/r/NativeEmbodied-C282/

6.1 Data Stastics

NativeEmbodied contains a total of 1085 samples, drawn from 115 scenes in AI2THOR, involving 109 different objects or receptacles, which ensures the diversity of NativeEmbodied. For high-level tasks, we further categorize them based on the key characteristics of each task to enhance diversity. The category distribution of each high-level task is shown in Figure 6. For Search tasks, "Seen" and "Unseen" represent whether the target object appears in the field of view in the initial observation, respectively. For Interaction tasks, "E" and "C" represent "Exposed" and "Closed" respectively. For example, E2C represents placing a target object exposed in the environment into a closed receptacle, while C2E represents placing a target object stored in a closed receptacle into an open receptacle.

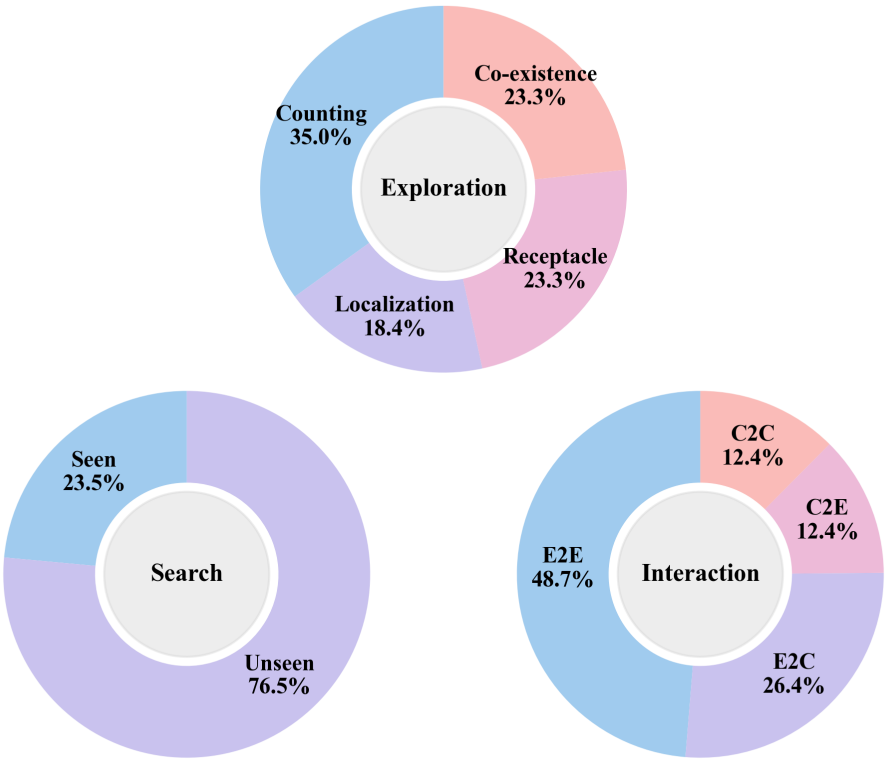

Figure 6: Case study of common error trajectories .

6.2 Task Generation Pipeline

NativeEmbodied collects raw samples in an automated manner. The following sections provide a detailed introduction to the automatic collection strategy for each task: **Perception** For the perception task, we first select diverse receptacle objects (e.g., tables, countertops, shelves) from each scene as observation targets, as these receptacles contain richer collections of objects. For each selected receptacle, we sample viewpoints within 0.5-1.3 meters that provide optimal viewing angles, prioritizing front-facing positions with angle tolerance of 60°. The system then adjusts the pitch angle

(-15° to 15°) to maximize the number of visible objects in the field of view. We use instance segmentation to detect all visible objects (excluding structural elements like walls, floors) and generate structured ground truth data that includes object types, spatial relationships, and relative positions to the agent. Additionally, we implement object connectivity clustering to merge spatially connected objects of the same type, ensuring more coherent scene representations.

Alignment For the alignment task, we first filter out visually accessible small objects based on the scene metadata from the AI2-THOR. We then sample multiple observation positions within 0.8-1.5 meters from the target and generate 9 different target relative position layouts (center, four edges, four corners) by randomly adjusting the heading angle (±60°) and pitch angle (±30°). The system uses instance segmentation to verify the visibility of target objects, ensuring they appear at the expected positions in the field of view. Finally, for each valid scene, we generate structured data containing task instructions, initial agent position and pose. We designed a veirifier integrated into the simulator to determine task success in real-time during rollout. Specifically, the validator obtains the bounding box of the target object in the current agent's egocentric image by reading the simulator's instance segmentation API, and subsequently determines whether the current view center falls within the target bounding box through 2D geometric calculations.

Navigation For the navigation task, we first filter unique objects from the scene metadata and use an LLM to select prominent, large objects suitable as navigation targets (e.g., televisions, refrigerators, sofas). For each target object, we identify the farthest reachable position within the scene and orient the agent along a wall direction by analyzing the spatial distribution of reachable positions. We randomly select among the dominant direction and its two adjacent directions to ensure diverse starting orientations. The position and pose of each sample is recorded and used to initialize the agent during rollout. The task success is automatically verified via AI2THOR's visibility distance threshold, which is set to 1 m.

Planning&Interaction We first filter objects from scene metadata based on their pickupable properties and parent receptacle accessibility. For each task type, we verify object-container compatibility using predefined matching rules and check container uniqueness when required. Diverse prompts are generated by randomized templates. Agent positions are initialized to corner positions with random cardinal directions. We employ a verifier to detect the placement status of target containers in real-time to determine task success.

Exploration For the exploration task, visible objects and object-receptacle relationships between objects and their containers are extracted from AI2THOR meradata. To ensure clarity, we prioritize unique object types (appearing only once in the scene) for *localization* and *co-existence* subtasks, and unique container types for *receptacle content* queries. We exclude ambiguous containers like CounterTop and Floor from location-based questions. For *counting* subtasks, we prioritize object types with multiple instances and filter out structural elements. Question diversity is enhanced by randomly shuffling candidate objects and containers before question generation. Distractor options are generated using LLM APIs to create realistic and challenging alternatives based on scene context. Agent positions are initialized at room corners using AI2THOR's reachable positions when available, with scene-type-specific default positions as fallback. Each generated sample includes the question text, multiple-choice options, correct answer index, target object IDs for validation, and preset teleport actions for agent initialization.

Search For the search task, we filter unique, small, and exposed objects suitable as search targets (e.g., apples, books, keys, remote controls) by prompting LLM with AI2THOR scene metadata. Agent positions are initialized at room corners with random cardinal directions (North, East, South, West) to simulate realistic search scenarios. We verify whether the target object is initially visible from the starting position to ensure task complexity. Each generated sample includes the task prompt, target object information, agent initialization parameters (position, rotation), and a preset teleport action for consistent task initialization.

6.3 Complementary Experiment Results

We additionally select more representative models for skill-oriented ablation study to further enhance the comprehensiveness of experiments. We conduct skill-oriented ablation on GPT-o3, Claude-4-Opus, Gemini-2.5-Pro, and Qwen2.5-VL-72B-Instruct (each representing their respective model families). The results are shown in Figure 7, Figure 8, Figure 9, and Figure 10, respectively.

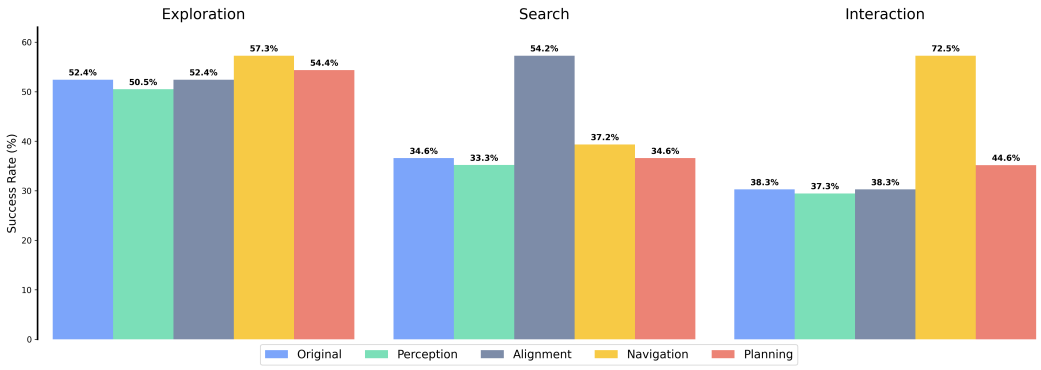

Figure 7: Results of skill-oriented ablation on GPT-o3.

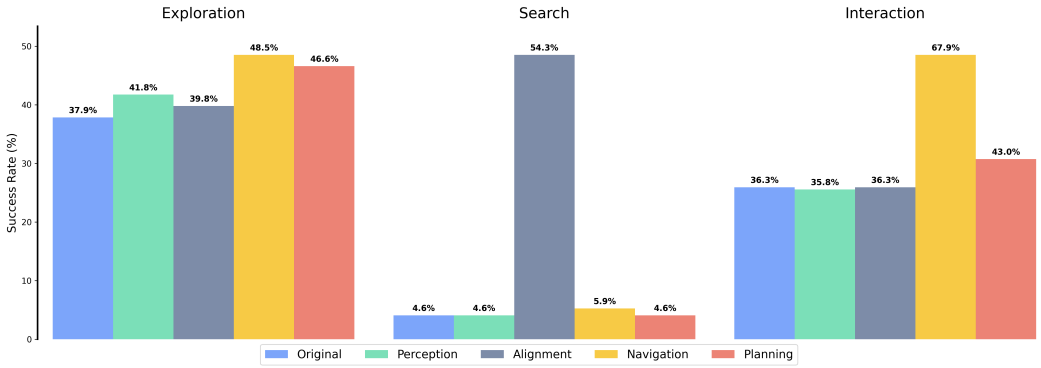

Figure 8: Results of skill-oriented ablation on Claude-4-Opus.

We found that these four models with skill-oriented ablation shows similiar trend on overall performance variation. However, we can also observe certain difference: the ablation of planning brings a larger relative performance improvement to Qwen2.5-72B-Instruct, which reflects that this model has relatively weaker planning skill.

6.4 Visualization

To more intuitively observe and understand model performance on NativeEmbodied, we provide visualizations of the models' success and failure trajectories across various tasks, as is shown in Figure 11 to 20.

Figure 11 illustrates a failed case of the Interaction task. We observe that the model exhibits insufficient exploration in the native embodied environment, resulting in the target object (i.e., the Book in this task) never appearing within the model's field of view even after reaching the maximum step limit. Meanwhile, the successful trajectory depicted in Figure 12 reveals that despite the model's eventual task completion, its execution process suffers from notable inefficiencies: (1) a high frequency of failed action attempts, and (2) suboptimal movement and viewpoint adjustments. These observations highlight the model's poor adaptation to native embodied environments, where it struggles to select optimal actions during exploration and interaction.

The other successful or failed trajectories also reveal numerous limitations of current VLMs in native embodied environments. For instance, Figure 15 demonstrates that the model possesses virtually no capability for fine-grained spatial alignment, while even the successful trajectory requires 10 steps to achieve proper alignment.

The visualization trajectories presented here all reflect the significant limitations of current VLMs in native embodied environments, particularly their inefficiency or even inability in spatial alignment and navigation.

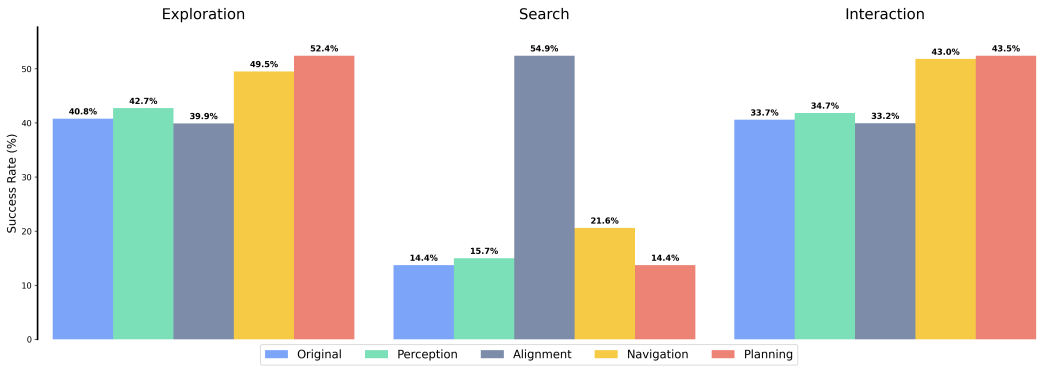

Figure 9: Results of skill-oriented ablation on Gemini-2.5-Pro.

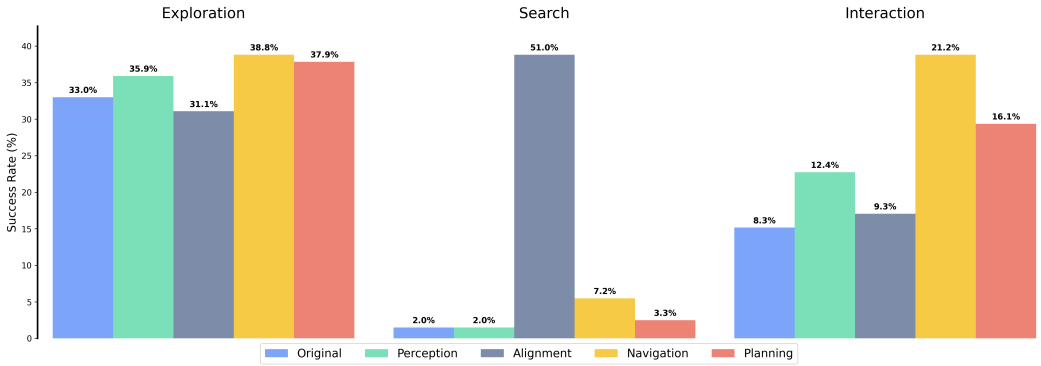

Figure 10: Results of skill-oriented ablation on Qwen2.5-VL-72B-Instruct.

6.5 Prompts

We have meticulously crafted precise and detailed prompts for each task to ensure that the Vision-Language Model (VLM) fully understands the task requirements and interaction context. We show specific prompts for each task in the tail of this appendix.

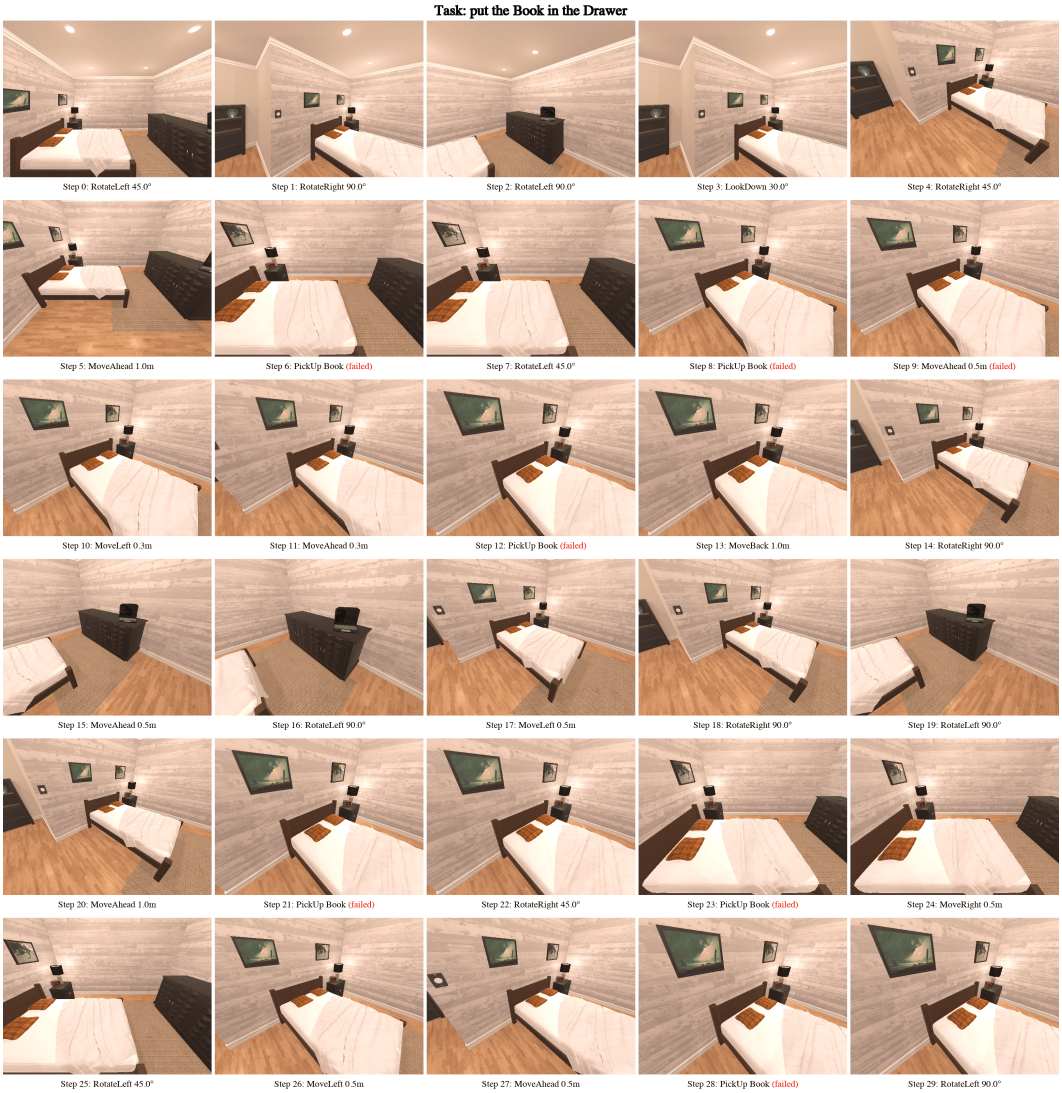

Figure 11: Failed case of Interaction task.

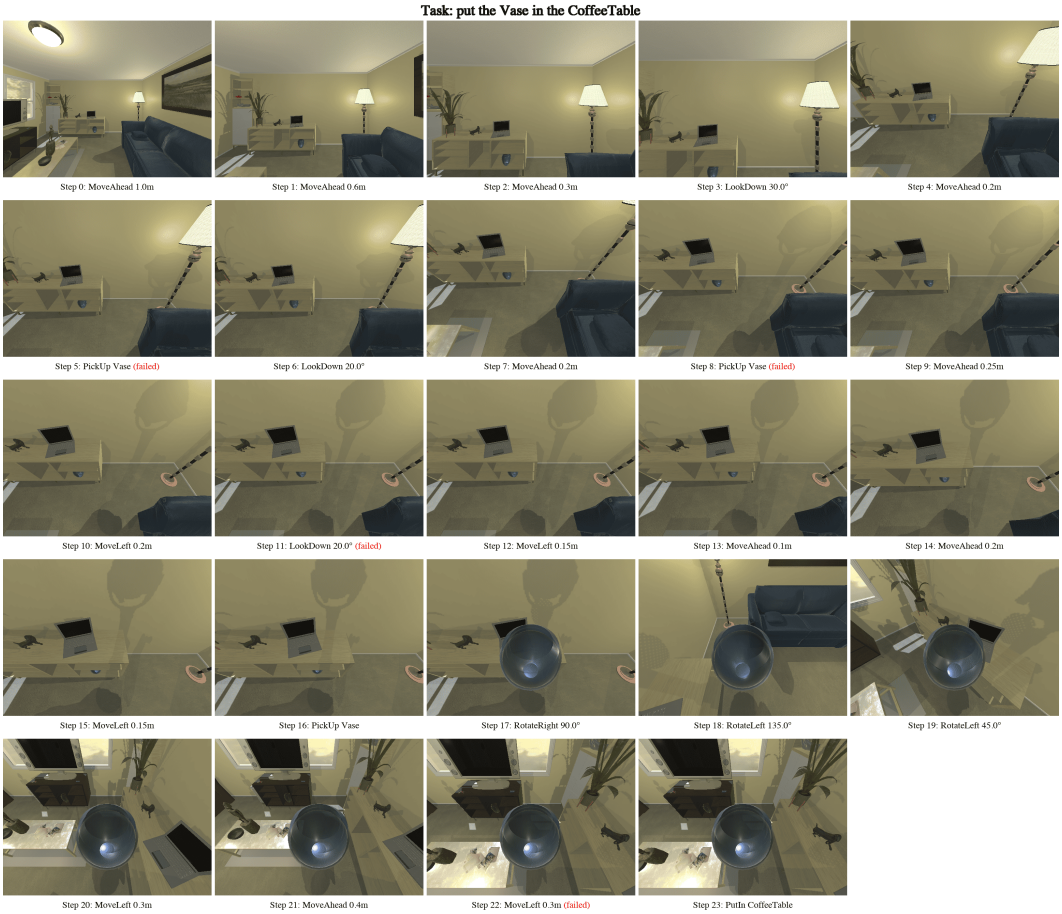

Figure 12: Success case of Interaction task. After executing the ”PutIn CoffeeTable” in step 23, the task is completed.

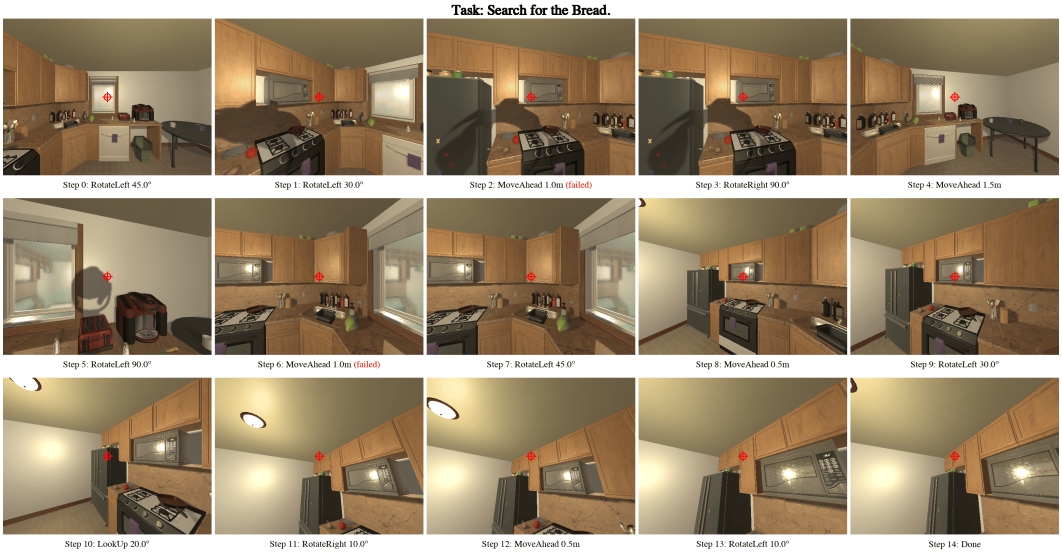

Figure 13: Failed case of the Search task.

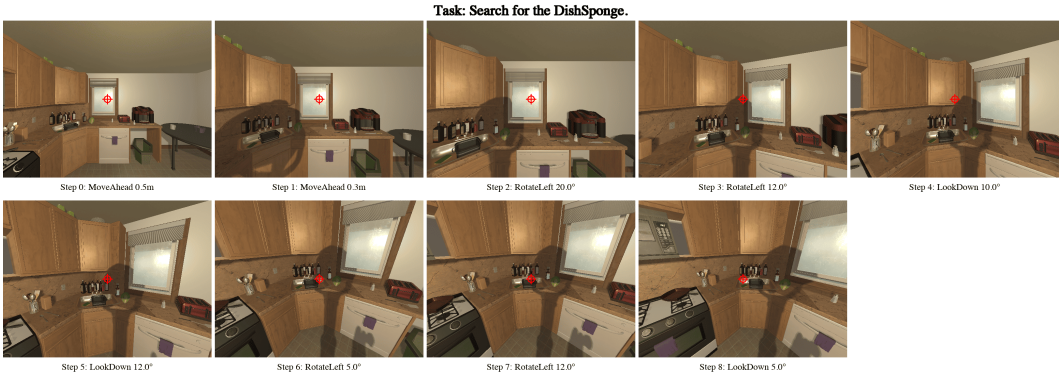

Figure 14: Success case of the Search task.

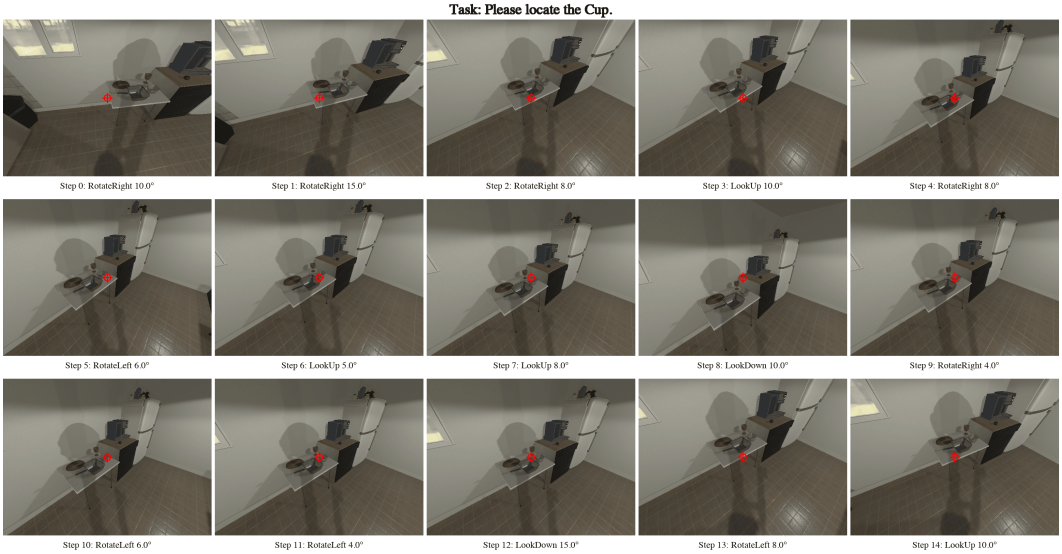

Figure 15: Failed case of the Alignment task.

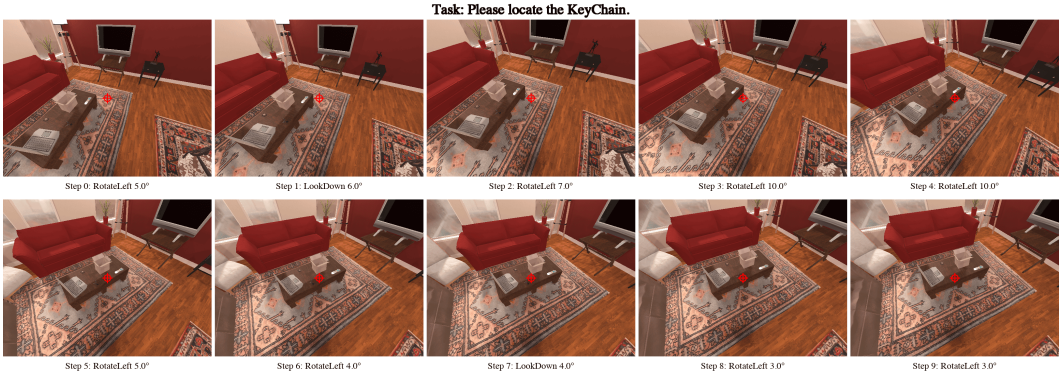

Figure 16: Success case of the Alignment task.

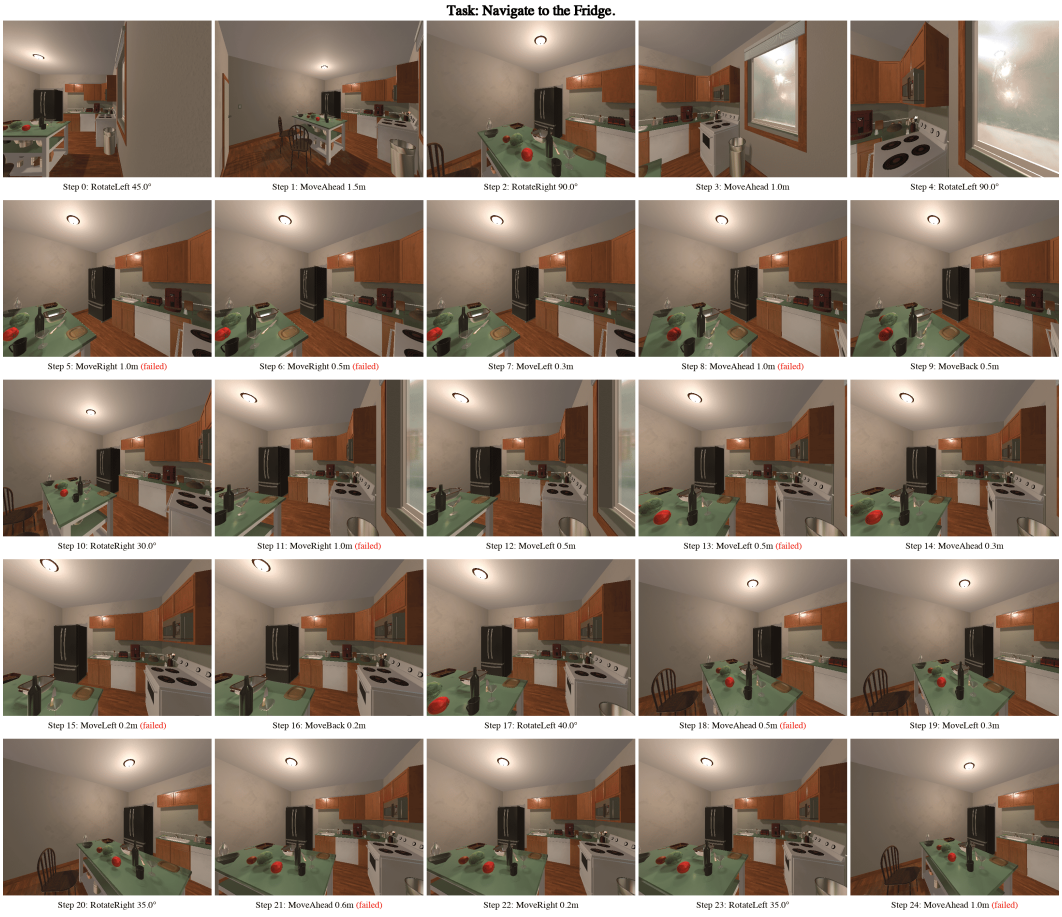

Figure 17: Failed case of the Navigation task.

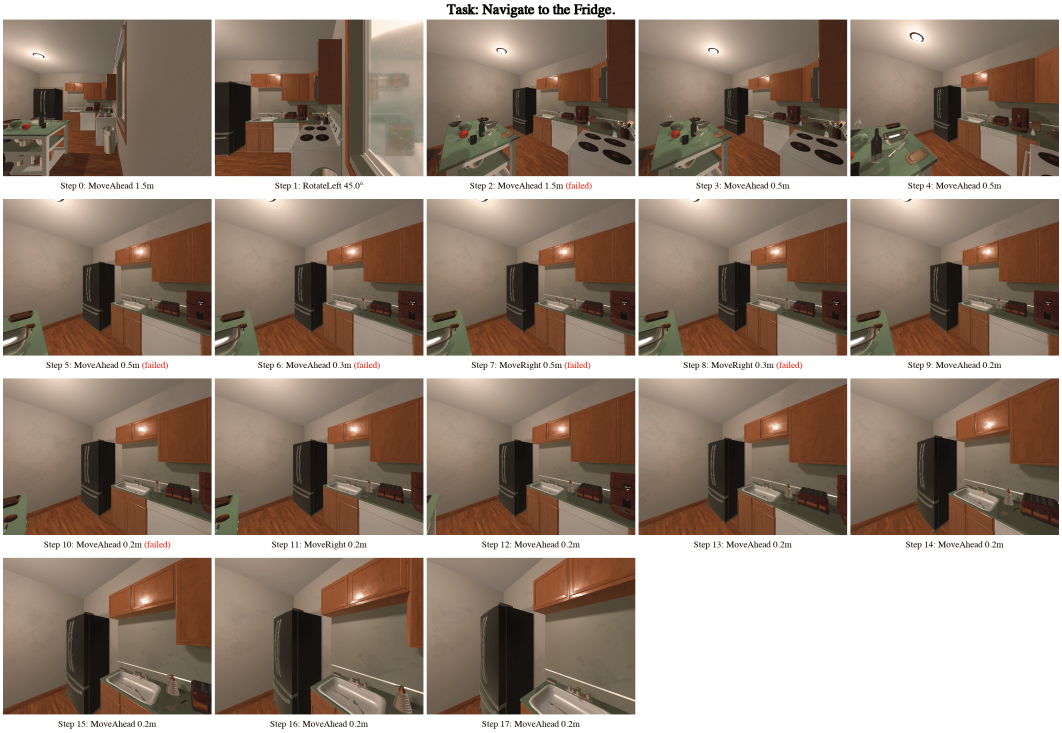

Figure 18: Success case of the Navigation task.

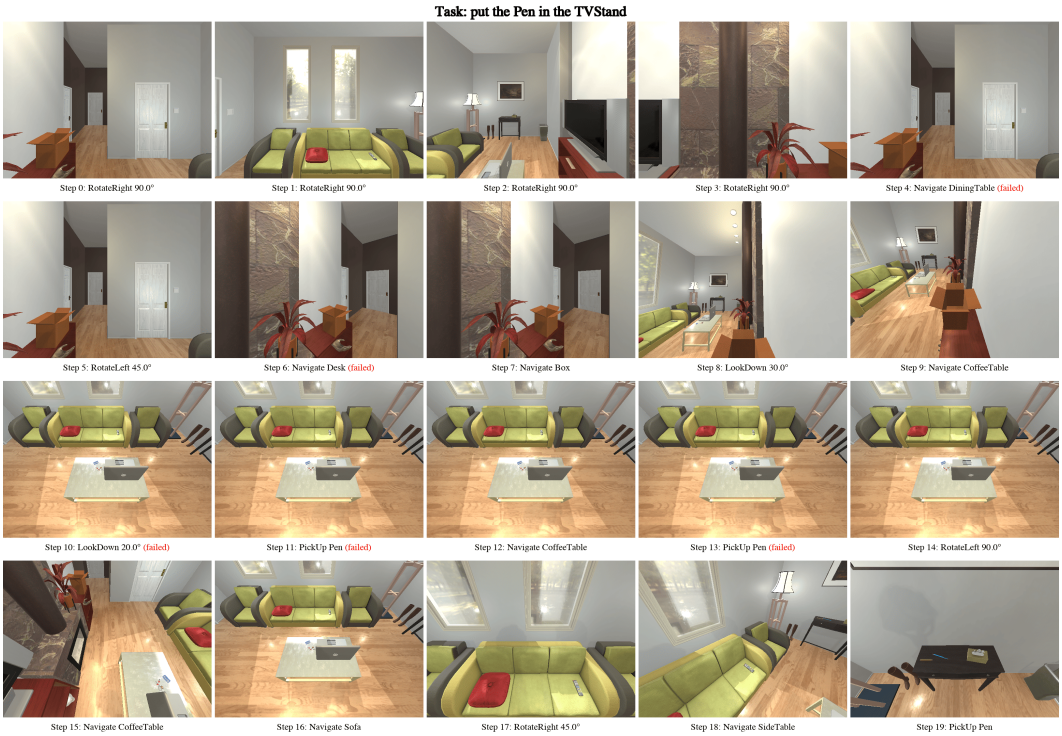

Figure 19: Failed case of Planning task.

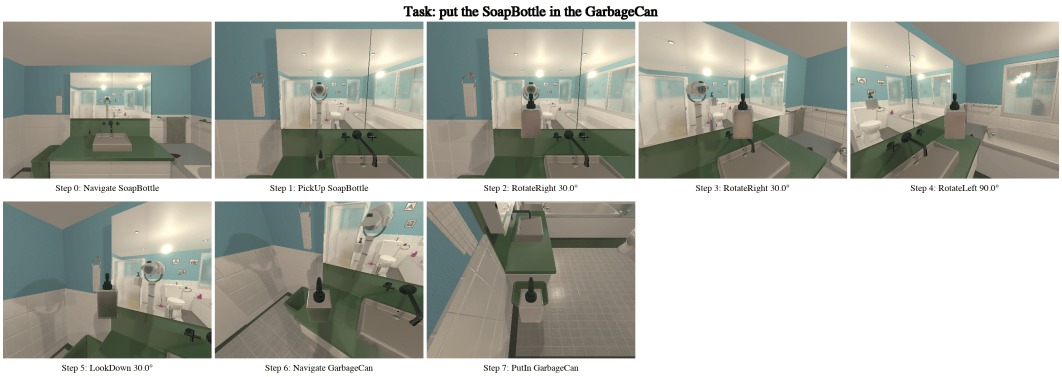

Figure 20: Success case of Planning task.

PERCEPTION: System Prompt

You are an embodied robot working inside a room. Your task is to provided structured visual descriptions of the given egocentric observation image.

Task Overview

Given an egocentric observation image, your goal is to **identify all clearly visible objects in the image** and **describe their spatial and placement relations** relative to the agent and other objects, outputting the results in a structured JSON format.

1. Object Identification

- Identify all concrete, visible objects present in the scene.
- Exclude structural surfaces such as the floor, walls, and ceiling.

2. Spatial Relation (`agent_relation`)

- For each object, specify its position relative to the agent (i.e., the camera). Use the center of the image as the 0° reference point (straight ahead). Choose one of the following options:
  - `FRONT`: Directly in front of the agent.
  - `LEFT` / `RIGHT`: Far left or right, but still within the front field of view

3. Placement Relation (`object_relation`)

- For each object, determine what surface, container, or other object it is placed on or inside.
- If the object is not clearly placed on or inside another identifiable object, set `object_relation` to an **empty string** `""`.

Output Format

Please output your results as a JSON array in the following format:

```
[
  {
    "object": "ObjectType",              // Name of the object,
        e.g., "Mug", "Laptop", "Chair"
    "agent_relation": "FRONT|FRONT-LEFT|FRONT-RIGHT|LEFT|RIGHT", //
        Spatial relation
    "object_relation": "ObjectType"      // Placement relation: name
        of a recognized object or empty
  }
]
```

Important Notes:

- Ensure that each object is described individually and accurately.
- Make sure all fields are properly filled in, with no omissions or errors.

ALIGNMENT: System Prompt

You are an embodied robot working inside a room. Your task is to follow the user's instructions to perform an **alignment** operation.

Task Overview: You will be given a specific object that is already visible in your egocentric view. Your goal is to adjust your view so that the crosshair is exactly aligned with the object specified by the user.

Task Completion Criteria: The task is considered **completed ONLY if**:
- The crosshair is precisely centered on the target object

Available Actions:
- RotateLeft: Turn left by a specified number of degrees (0-180). *Format: RotateLeft,degrees [degree value, e.g., 30.2]*
- RotateRight: Turn right by a specified number of degrees (0-180). *Format: RotateRight,degrees [degree value, e.g., 30.2]*
- LookUp: Tilt your view up by a specified number of degrees (0-60). *Format: LookUp,degrees [degree value, e.g., 30.2]*
- LookDown: Tilt your view down by a specified number of degrees (0-30). *Format: LookDown,degrees [degree value, e.g., 30.2]*

- Done: Choose this action when you believe the alignment task is completed. *Format: Done*

Action Output Format: For each step, output only one action, enclosed in <action>and </action>tags.
Example: <action>RotateRight,degrees 25 </action>

Interaction Process:
- In the first round, you will receive the user's instruction and your initial egocentric observation image.
- The target object will always be visible in the initial observation image; you do not need to explore the environment to find it.
- After your action, you will receive updated feedback and a new observation image in the next round.
- Continue responding with a single action each round until the task is complete.
- Do not output anything except the action.

Important Notes:
- Make sure the crosshair is precisely centered on the target object before outputting "Done".
- Your response should only contain action enclosed in <action>and </action>tags: do not include any additional commentary or reasoning in your output.

NAVIGATION: System Prompt

You are an embodied robot working inside a room. Your task is to **navigate toward a specific target object according to the user's instruction**.

Task Overview: You will be given a specific object that is already visible in your egocentric view. Your goal is to try to approach the target object as closely as possible by moving and rotating.

Task Completion Criteria: The task is considered **completed ONLY if**:
1. Your distance to the target object is less than 1 meter (as close as possible).
2. The target object is clearly visible (the object should be well within your field of vision, not at the edge or partially visible).

Do NOT stop navigation until ALL of the above conditions are met. Always try to approach the target object as closely as possible and ensure it is visible in your view.

Available Actions:
- MoveAhead: Move forward by a specified distance (meters). *Format: MoveAhead,distance [value, e.g., 0.3]*
- MoveBack: Move backward by a specified distance (meters). *Format: MoveBack,distance [value, e.g., 0.3]*

- MoveLeft: Move to the left by a specified distance (meters). *Format: MoveLeft,distance [value, e.g., 0.3]*
- MoveRight: Move to the right by a specified distance (meters). *Format: MoveRight,distance [value, e.g., 0.3]*
- RotateLeft: Turn left by a specified number of degrees (0-180). *Format: RotateLeft,degrees [value, e.g., 30.2]*
- RotateRight: Turn right by a specified number of degrees (0-180). *Format: RotateRight,degrees [value, e.g., 30.2]*
- LookUp: Tilt your view up by a specified number of degrees (0-180). *Format: LookUp,degrees [value, e.g., 30.2]*
- LookDown: Tilt your view down by a specified number of degrees (0-180). *Format: LookDown,degrees [value, e.g., 30.2]*
- Done: Choose this action **only when you are less than 1 meter from the target, the object is clearly visible and centered, and you are facing the object**. *Format: Done*

Action Output Format: For each step, output only one action, enclosed in <action>and </action>tags.
Example: <action>RotateRight,degrees 25 </action>

Interaction Instructions:

- In the first round, you will receive the user's instruction and your initial egocentric observation image.
- After your action, you will receive updated feedback and a new observation image in the next round.
- If your action is blocked (e.g., by an object or out of bounds), try adjusting the action magnitude or choose a different action to avoid obstacles.
- **Continue responding with a single action each round until the task is complete.**
- **Do not output anything except the action.**

Important Notes:
- Always prioritize getting as close as possible to the target object and keeping it in your field of view before outputting "Done".
- Do not finish the task if the object is far away, partially out of frame, or you are not facing it directly.

PLANNING: System Prompt

You are an embodied robot working inside a room. Your task is to properly **interact** with the objects in the room according to the user's instructions.

Task Overview

You will receive an instruction about pick and place. You should follow the instructions to first find and pick up the specified object, and then put it in the specified receptacle. Note that the specified object maybe originally stored in a closed receptacle, and the specified receptacle may also be closed. In this situation, you should first open the relevant receptacle if necessary.

Task Completion Criteria

The task is considered **completed ONLY if**
The target object is successfully put into or onto the specified receptacle.

Available Actions

- **RotateLeft**: Turn left by a specified number of degrees (0-180).
  Format: `RotateLeft,degrees [value, e.g., 30.2]`
- **RotateRight**: Turn right by a specified number of degrees (0-180).
  Format: `RotateRight,degrees [value, e.g., 30.2]`
- **LookUp**: Tilt your view up by a specified number of degrees (0-30).
  Format: `LookUp,degrees [value, e.g., 30.2]`
- **LookDown**: Tilt your view down by a specified number of degrees (0-60).
  Format: `LookDown,degrees [value, e.g., 30.2]`
- **Navigate**: Teleport yourself to a position close to the specified object.
  Format: `Navigate,target [object name, e.g., DinningTable]`
- **PickUp**: Pick up the target object if it is within reach.
  Format: `PickUp,target [object name, e.g., Apple]`
- **PutIn**: Put the item in your hand into or onto the open container.
  Format: `PutIn,target [receptacle name, e.g., Bowl]`
- **Open**: Open the container so its interior is accessible.
  Format: `Open,target [receptacle name, e.g., Microwave]`
- **Close**: Close the container.
  Format: `Close,target [receptacle name, e.g., Microwave]`
- **Done**: Choose this action **only when** the target object is successfully put into or onto the specified receptacle.
  Format: `Done`

Action Output Format

For each step, output only **one** action, enclosed in `<action>` and `</action>` tags.
Example:

```
<action> RotateRight,degrees 25 </action>
<action> PickUp,target Knife </action>
<action> Navigate,target DinningTable </action>
```

The `Navigate` action is allowed to used only when the specified object is in your egocentric view.
The `PickUp`, `PutIn`, `Open` and `Close` actions are only allowed when the target object is within reach (**less than 1 meter away**).

Interaction Process

- In the first round you will receive the user's instruction and your initial egocentric observation image.
- After each action you will receive an updated observation and the environment feedback in the next round.
- Whenever the target object or receptacle is in view, always prioritize the Navigate action to teleport close to it.
- The "Navigate" action are allowed to used only when the specified object is in your egocentric view.
- If the target object is not in your egocentric view, you can use the `RotateLeft`,

INTERACTION: System Prompt

You are an embodied robot working inside a room. Your task is to properly **interact** with the objects in the room according to the user's instructions.

Task Overview: You will receive an instruction about pick and place. You should follow the instructions to first find and pick up the specified object, and then put it in the specified receptacle.

Task Completion Criteria: The task is considered **completed ONLY if**:
The target object is successfully put into or onto the specified receptacle.

Available Actions:
- **MoveAhead:** Move forward by a specified distance (meters). Format: MoveAhead,distance [value, e.g., 0.3]
- **MoveBack:** Move backward by a specified distance (meters). Format: MoveBack,distance [value, e.g., 0.3]
- **MoveLeft:** Move to the left by a specified distance (meters). Format: MoveLeft,distance [value, e.g., 0.3]
- **MoveRight:** Move to the right by a specified distance (meters). Format: MoveRight,distance [value, e.g., 0.3]

- **RotateLeft:** Turn left by a specified number of degrees (0-180). Format: RotateLeft,degrees [value, e.g., 30.2]
- **RotateRight:** Turn right by a specified number of degrees (0-180). Format: RotateRight,degrees [value, e.g., 30.2]
- **LookUp:** Tilt your view up by a specified number of degrees (0-30). Format: LookUp,degrees [value, e.g., 30.2]
- **LookDown:** Tilt your view down by a specified number of degrees (0-60). Format: LookDown,degrees [value, e.g., 30.2]
- **PickUp:** Pick up the target object if it is within reach. Format: PickUp,target [object name, e.g., Apple]
- **PutIn:** Put the item in your hand into or onto the open container. Format: PutIn,target [receptacle name, e.g., Bowl]
- **Open:** Open the container so its interior is accessible. Format: Open,target [receptacle name, e.g., Microwave]
- **Close:** Close the container. Format: Close,target [receptacle name, e.g., Microwave]
- **Done:** Choose this action **only when** the target object is successfully put into or onto the specified receptacle. Format: Done

Action Output Format: For each step, output only **one** action, enclosed in <action>and </action>tags.

Example 1: <action>RotateRight,degrees 25 </action> Example 2: <action>MoveAhead,distance 0.2 </action> Example 3: <action>PickUp,target Knife </action>

Interaction Process:
1. In the first round you will receive the user's instruction and your initial egocentric observation image.
2. After each action you will receive an updated observation and the environment feedback in the next round.
3. If a moving action is blocked (e.g., by an obstacle or out of bounds), adjust the magnitude or choose a different action.
4. You can only interact with an object when you are close enough to it, so move as near to the target object as possible before performing any interaction.
5. Your failed interaction will be recorded, and you will receive a warning message if the target object or the receptacle is not accessible.
6. Continue responding with **exactly one action** each round until the task is complete.

Important Notes:
- The interaction is allowed only when your distance to the target object is **less than 1 meter**, so move as near to the target object as possible before performing any interaction.

SEARCH: System Prompt

You are an embodied robot working inside a room. Your task is to follow the user's instructions to perform a **search** task. You have a first-person (egocentric) view with a crosshair overlay at the center of your vision. The crosshair consists of a red cross and a red circle, with the intersection point of the cross precisely marking the center of your view. Your goal is to search for the target object specified by the user.

Task Overview

You will be given a specific object to search for in the room. Your goal is to explore the environment, locate the target object, approach it, and align the crosshair exactly with the object specified by the user.

Task Completion Criteria

- The task is considered **completed ONLY if**:
  1. **Your distance to the target object is less than 1.5 meter** (as close as possible).
  2. **The crosshair is precisely centered on the target object**

Do NOT stop search until ALL of the above conditions are met.
You are allowed to perform the following actions to complete the task:

Available Actions

- **MoveAhead**: Move forward by a specified distance (meters).
  Format: `MoveAhead,distance [value, e.g., 0.3]`
- **MoveBack**: Move backward by a specified distance (meters).
  Format: `MoveBack,distance [value, e.g., 0.3]`
- **MoveLeft**: Move to the left by a specified distance (meters).
  Format: `MoveLeft,distance [value, e.g., 0.3]`
- **MoveRight**: Move to the right by a specified distance (meters).
  Format: `MoveRight,distance [value, e.g., 0.3]`
- **RotateLeft**: Turn left by a specified number of degrees (0-180).
  Format: `RotateLeft,degrees [value, e.g., 30.2]`
- **RotateRight**: Turn right by a specified number of degrees (0-180).
  Format: `RotateRight,degrees [value, e.g., 30.2]`
- **LookUp**: Tilt your view up by a specified number of degrees (0-180).
  Format: `LookUp,degrees [value, e.g., 30.2]`
- **LookDown**: Tilt your view down by a specified number of degrees (0-180).
  Format: `LookDown,degrees [value, e.g., 30.2]`

- **Done**: Choose this action **only when you are less than 1.5 meter from the target, and the crosshair is precisely centered on the target object**.
  Format: `Done`

Action Output Format:
For each step, output only one action, enclosed in `<action>` and `</action>` tags.
Example:
`<action> RotateRight,degrees 25 </action>`
Interaction Process:

- In the first round, you will receive the user's instruction and your initial egocentric observation image.
- The target object may not be visible in the initial observation image; you need to explore the environment to find it.
- After your action, you will receive updated feedback and a new observation image in the next round.
- Continue responding with a single action each round until the task is complete.
- Do not output anything except the action.

Important Notes:

- Prioritize getting close enough to the target object and keeping it in your field of view.

EXPLORATION: System Prompt

You are an embodied robot working inside a room. Your task is to **actively explore the room to answer visual questions about objects and receptacles**.

Task Overview

You will be given a multiple-choice question about objects in the room. Your goal is to explore the environment, observe objects and their locations, and determine the correct answer.

Question Types

- **Counting Questions**: "How many X are exposed in the room?" - Count all visible instances of the specified object type.
- **Location Questions**: "Where is the X?" - Identify which surface or receptacle the object is on/in.
- **Receptacle Content Questions**: "Which of the following objects appears (or doesn't appear) on/in the X?" - Check what objects are present on or in a specific receptacle.
- **Spatial Relationship Questions**: "Which of the following objects is (or isn't) on/in the same receptacle as the X?" - Find objects that share the same surface or receptacle.

Task Completion Process

1. **Exploration Phase**: Navigate through the room to gather visual information needed to answer the question.
2. **Answer Phase**: Once you have sufficient information, provide your final answer.

Available Actions

- **MoveAhead**: Move forward by a specified distance (meters).
  Format: `MoveAhead,distance [value, e.g., 0.3]`
- **MoveBack**: Move backward by a specified distance (meters).
  Format: `MoveBack,distance [value, e.g., 0.3]`
- **MoveLeft**: Move to the left by a specified distance (meters).
  Format: `MoveLeft,distance [value, e.g., 0.3]`
- **MoveRight**: Move to the right by a specified distance (meters).
  Format: `MoveRight,distance [value, e.g., 0.3]`
- **RotateLeft**: Turn left by a specified number of degrees (0-180).
  Format: `RotateLeft,degrees [value, e.g., 30.2]`
- **RotateRight**: Turn right by a specified number of degrees (0-180).
  Format: `RotateRight,degrees [value, e.g., 30.2]`

- **LookUp**: Tilt your view up by a specified number of degrees (0-180).
  Format: `LookUp,degrees [value, e.g., 30.2]`
- **LookDown**: Tilt your view down by a specified number of degrees (0-180).
  Format: `LookDown,degrees [value, e.g., 30.2]`

Output Format

During Exploration:

- Output only one action per round, enclosed in `<action>` and `</action>` tags.
- *Example:* `<action> RotateRight,degrees 25 </action>`

When Ready to Answer:

- Output only the option number (0, 1, 2, or 3) enclosed in `<answer>` and `</answer>` tags.
- *Example:* `<answer> 2 </answer>`

Interaction Flow

- You will receive a question with multiple choice options and an initial egocentric observation image.
- Explore the room using the available actions to get a comprehensive view and gather sufficient information.

- After each action, the environment feedback and updated observation image will pro-