

Figure S1. Scene 1 of additional evaluation materials. I) shows the scene in CoppeliaSim. II) shows the preferred state for the instrumental experiments. This is chosen as the final observation from the epistemic experiment. III) Shows the epistemic experiment, in which (a) represents the epistemic value for potential viewpoints. (b) represent the imagined observations from the potential future viewpoints. (c) Shows the last observed value by the agent. IV) Shows both the epistemic (a) and instrumental (b) values for the robot manipulator. (c) shows the categorical distribution over potential future viewpoints. (d) represents the imagined observations from the potential viewpoints. (e) Shows the last observed value. V) Shows the experiment for 3 degrees of freedom, in which the agent looks for the preferred state from II).

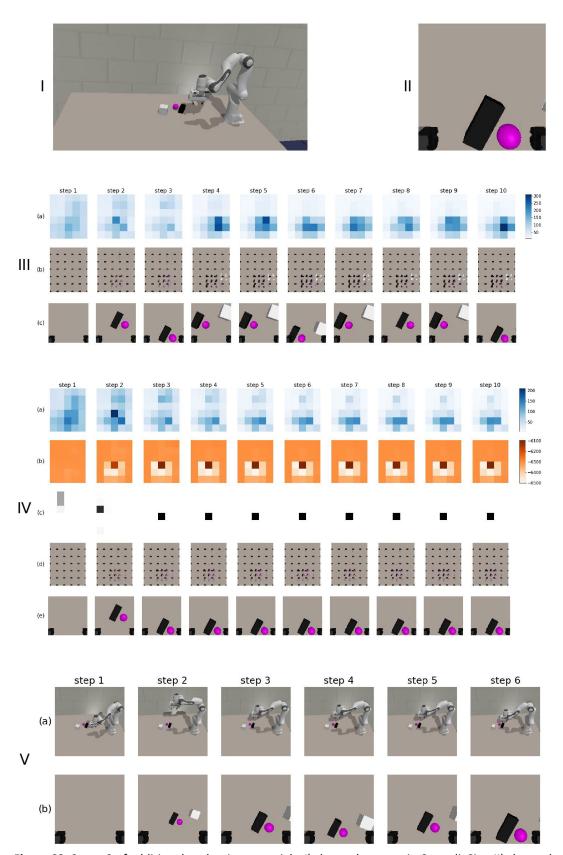


Figure S2. Scene 2 of additional evaluation materials. I) shows the scene in CoppeliaSim. II) shows the preferred state for the instrumental experiments. This is chosen as the final observation from the epistemic

experiment. III) Shows the epistemic experiment, in which (a) represents the epistemic value for potential viewpoints. (b) represent the imagined observations from the potential future viewpoints. (c) Shows the last observed value by the agent. IV) Shows both the epistemic (a) and instrumental (b) values for the robot manipulator. (c) shows the categorical distribution over potential future viewpoints. (d) represents the imagined observations from the potential viewpoints. (e) Shows the last observed value. V) Shows the experiment for 3 degrees of freedom, in which the agent looks for the preferred state from II).