

Tutorial Setup

Optional steps to follow along

ROS

<http://wiki.ros.org/kinetic/Installation/Ubuntu> (ros-kinetic-desktop-full)

```
sudo apt install ros-kinetic-turtlebot-stage
```

Set up Workspace

```
mkdir -p catkin_ws/src; cd catkin_ws/src  
Catkin_init_workspace
```

ROSPlan

<https://github.com/kcl-planning/rosplan> (follow instructions to install)

https://github.com/kcl-planning/rosplan_demos

```
git clone https://github.com/clearpathrobotics/occupancy\_grid\_utils  
catkin build #or (cd ..; catkin_make)
```

https://github.com/KCL-Planning/ROSPlan/blob/gh-pages/_demos/conference_pages/icaps2019.tar.gz

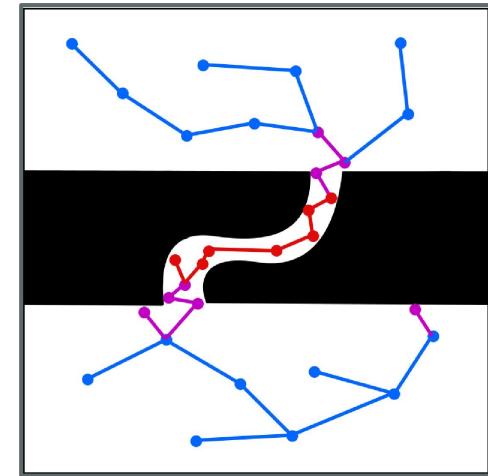
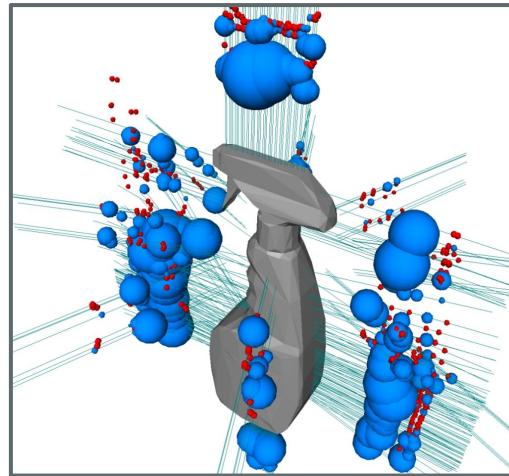
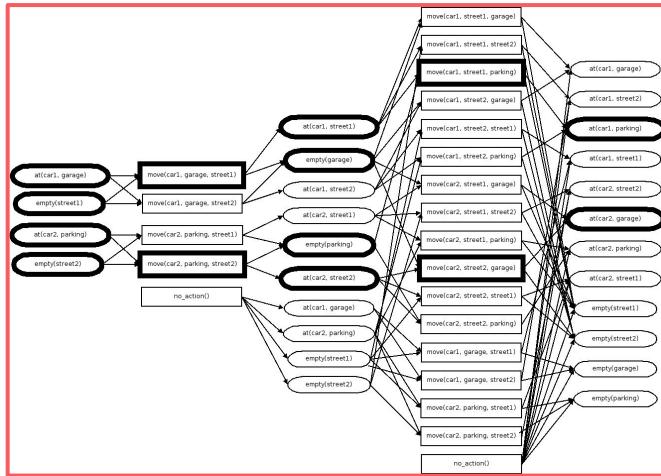


AI Planning for Robotics with ROSPlan

ICAPS 12/07/19
Michael Cashmore, Daniele Magazzeni

Disclaimer

“Planning” is many things.



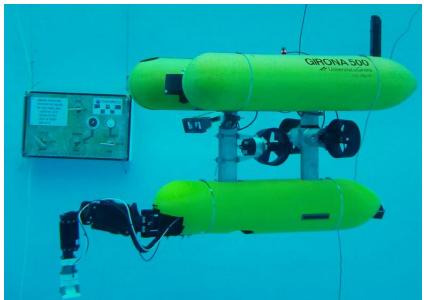
In this tutorial planning is “Task Planning”

We focus on planning for real applications:

- In robotics
 - Autonomous underwater vehicles.
 - Probabilistic planning with service robots.
 - Strategic-Tactical planning for long-term missions.
- With humans
 - XAIP
 - Human-robot teaming.
- In domains with complex dynamics
 - Energy technology.
 - Smart buildings.
 - Urban traffic control.

Our research in robotics:

PANDORA



Planning long-term inspection and maintenance missions for Autonomous Underwater Vehicles.



*Toward Persistent Autonomous Intervention in a Subsea Panel.
Autonomous Robots. (2016)*

Opportunistic Planning in Autonomous Underwater Missions. IEEE Transactions on Automation Science and Engineering. (2017)

AUV mission control via temporal planning. IEEE international conference on robotics and automation (ICRA 2014)

Planning Inspection Tasks for AUVs. Proceedings of the MTS/IEEE Oceans 2013 Conference, San Diego (OCEANS 2013)

Our research in robotics:

SQUIRREL



“Clearing clutter bit-by-bit”

Planning to explore environments, tidy areas, and interact with children in a clutter home or kindergarten environment.



On-the-fly detection of novel objects in indoor environments
IEEE International Conference on Robotics and Biomimetics (ROBIO 2017)

Short-Term Human Robot Interaction through Conditional Planning and Execution (ICAPS 2017)

Strategic Planning for Autonomous Systems over Long Horizons. Proceedings of the 4th ICAPS Workshop on Planning and Robotics (PlanRob 2016)

ROSPlan: Planning in the Robot Operating System. Proceedings of the 25th International Conference on Automated Planning and Scheduling (ICAPS 2015)

Task Planning and Robotics

From (Ingrand & Ghallab, 2017)

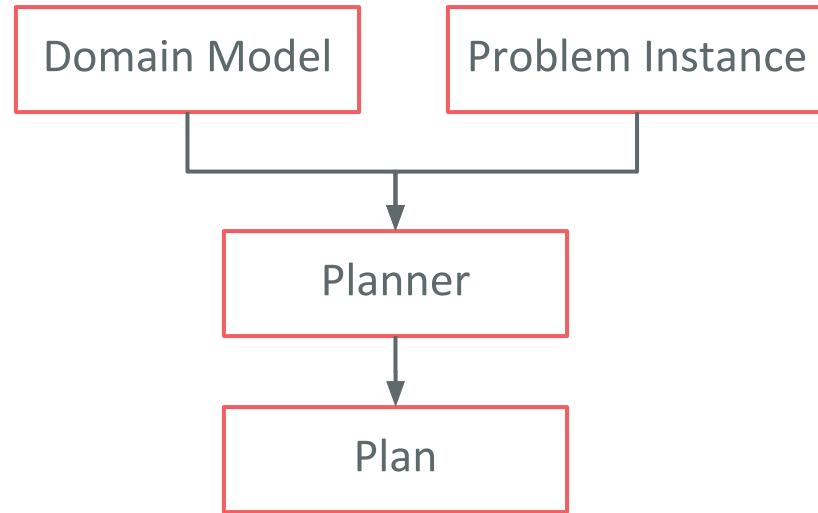
- Planning
- Acting
- Observing
- Monitoring
- Goal reasoning
- Learning

Task Planning and Robotics

From (Ingrand & Ghallab, 2017)

- Planning
- Acting
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- Monitoring
- Goal reasoning
- Learning

*Organising actions to achieve goals,
before starting to execute them.*



Task Planning and Robotics

Planning

- uses a model of the world in order to predict and anticipate its behaviour in order to choose actions that will lead to desirable states.
- assumes the world can be modelled as a finite collection of state variables and that actions cause changes in the values of those variables.

Given such a model including *actions*, an *initial state*, and *goal*. Planning will find actions (a *plan*) that when applied from the initial state, is predicted to achieve the goals.

Robots can follow a plan.

Task Planning and Robotics

Planning will find actions (*a plan*) that when applied from the initial state, is predicted to achieve the goals.

A robot can follow that plan

- ACTION 1
- ACTION 2
- ACTION 3



Task Planning and Robotics

Planning will find actions (*a plan*) that when applied from the initial state, is predicted to achieve the goals.

A robot can follow that plan until...

- It can't because the model was wrong.
- It can't because the model was not accurate enough.
- The state is too mismatched with reality.
It just doesn't want to any more.

- ACTION 1
- ACTION 2
- ACTION 3



Task Planning and Robotics

- Planning online: deciding when to plan and how long to plan.
- Detecting plan failure during execution.
- Handling risk.
- Planning in response to partial information.
- Planning with nondeterminism.
- Reaction to unexpected events.
- Recovering the state.
- Integration with control (e.g. task and motion planning).
- Replanning (online).
- Planning and execution with imperfect communication.
- Humans.

Task Planning and Robotics

From (Ingrand & Ghallab, 2017)

- Planning
- Acting
- Observing
- Monitoring
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Acting: Executing the chosen actions, often through closed-loop reactive functions.

Observing: Collecting data from sensors, and using data collected from sensors to update the current state description.

Monitoring: Comparing the current state description and system state with what was predicted by the model.

Task Planning and Robotics

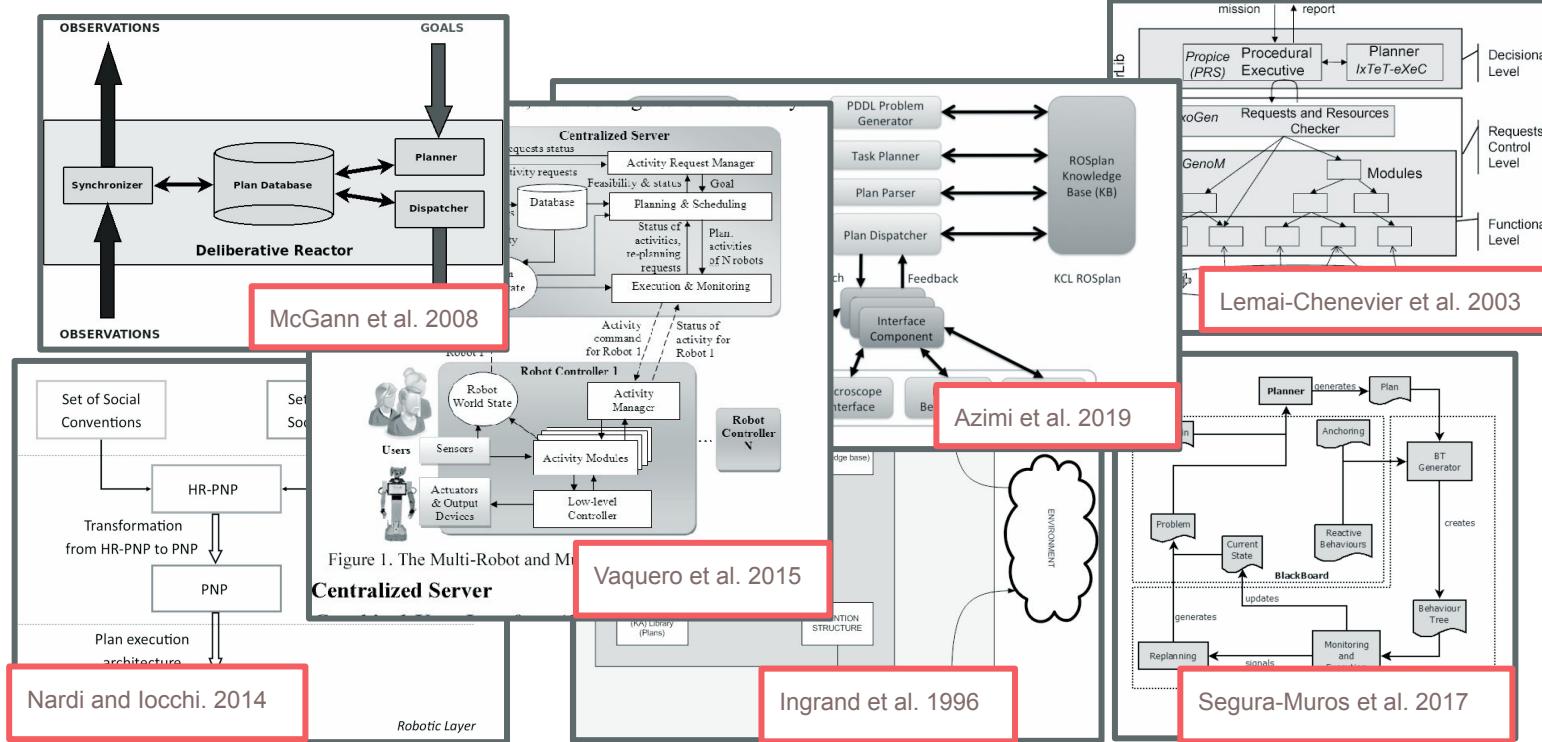
| Systems | Associated components | Deliberation Functions | Knowledge Representation | Robotic Domains | Architecture | Main Additional Features |
|-----------------|---|------------------------|--|--|--------------------|--|
| DS1/RAX [157] | PS [110] EXEC Livingstone [227] | PAMGO | State Variables time-points Qualitative model Transition automata with probabilities and costs | Autonomous Spacecraft | Layered (RA) | Time management Resource management Diagnostic and recovery |
| IxTeT/PRS [108] | IxTeT [90] Exec [137] Reco [65] PRS [106] GenoM [76] | PAMO | State Variables, time-points Chronicles Procedures | Exploration & rescue robots | Layered (LAAS) | Time management Resource management Verification and validation (functional layer) |
| IDEA [155] | IDEA EUROPA [79] | PA | State Variables, intervals | Exploration robots | Agent-based (IDEA) | Time management Integrated knowledge representation Refinement with lookahead |
| T-REX | T-REX [147] EUROPA [79] APSI[81] | PA | State Variables, intervals | AUV Service and domestic robots | Teleo reactive | Time management Integrated knowledge representation Refinement with lookahead |
| RMPL[225] | Titan [226] Burton [228] Kirk [224] Drake [52] Pike [140] | PAM | Probabilistic Timed hierarchical automata Temporal Plan Networks Probabilistic TPNs, TPNs with Uncertainty | Exploration & rescue robots Autonomous Spacecraft | Specific | Time management Diagnostic and recovery Integrated knowledge representation Refinement with lookahead Handling of uncertainty |
| WITAS [63] | TALPlanner [133] DyKnow [101] | PAMO | Temporal Action Logic Stream, policy Chronicles | Autonomous aerial vehicles | Layered [62] | Time management Resource management Integrated knowledge representation Explicit handling of uncertainty Verification and validation |
| ASPEN/ CASPER | ASPEN [178] CASPER [43] TCA [200] TDL [201] Plexil [216] | PA | State Variables Intervals Programs | Exploration & rescue robots | Layered | Time management Resources management |
| XFRM | XFRM [16] RPL [15] SRC [14] SRP [17] CRAM [18] | PAL | RPL, CRAM Plan Language Prolog | Service and domestic robots | Open world (CRAM) | Integrated knowledge representation Refinement with lookahead Open models |
| Cypress [223] | Sipe [222] PRS [158] CPEF [159] | PAG | ACT Formalism | Military | | Time management Resource management Integrated knowledge representation Refinement with lookahead |

Table 2: Analyzed systems, clustered into approaches and associated components, with their main deliberation functions (P: planning, A: acting, M: monitoring, O: observing, G: goal reasoning, L: learning) and other features.

Survey of systems for planning and robotics
(part 1 of 2)
[Ingrand & Ghallab, 2017]

Task Planning and Robotics

A wealth of system architectures.



AI Planning for Robotics with ROSPlan

How to connect planning and robotics?

AI Planning for Robotics with ROSPlan

How to connect planning and robotics?

- Reusing existing software.
Many existing systems and algorithms to be leveraged.

AI Planning for Robotics with ROSPlan

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Many existing systems and algorithms to be leveraged.

- Without restricting the system.

Completely new architectures can be built, incorporating existing components.

AI Planning for Robotics with ROSPlan

How to connect planning and robotics?

- Reusing existing software.

Many existing systems and algorithms to be leveraged.

- Without restricting the system.

Completely new architectures can be built, incorporating existing components.

- In a straightforward (easy) way.

Time should be spent on the part of the system that is interesting.

(Disclaimer 2: This is a tutorial and aims to be accessible.)

AI Planning for Robotics with ROSPlan

ROSPlan: Connecting standards: PDDL* and ROS

- **ROS**
- **ROSPlan**
- **Using ROSPlan**
 - Planning
 - Acting and Monitoring
 - Observing and more Monitoring
- **Simulation Examples**

* PDDL, PDDL2.1, PDDL+, PPDDL, and RDDL

Part 1: ROS

What is ROS?

A set of software libraries and tools that help you build robot applications.

- A ROS system is distributed into *nodes*.
- A system is configured by *parameters*, and then all the nodes are *launched*.
- Nodes talk by publishing *messages* and calling *services*.

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ROS tutorials online:

<http://wiki.ros.org/ROS/Tutorials>

Nodes

/rgbd_camera

/face_recognition

/collision_avoidance

A node is its own separate program.

It is usually one process, but it can be multiple processes.

Nodes have:

- A node type.
- A unique name.
- Launch parameters.

Parameters

/rgb_camera

/face_recognition

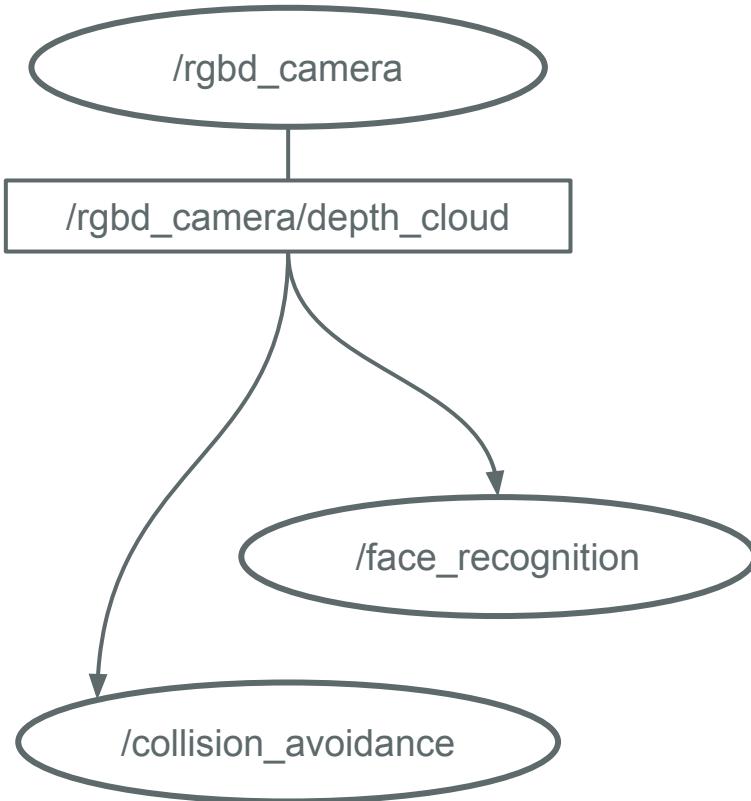
/collision_avoidance

A parameter server keeps track of parameters, which can be accessed by name.

Parameters are intended to be fairly static values that do not change.

They are well suited for initial configuration.

Messages



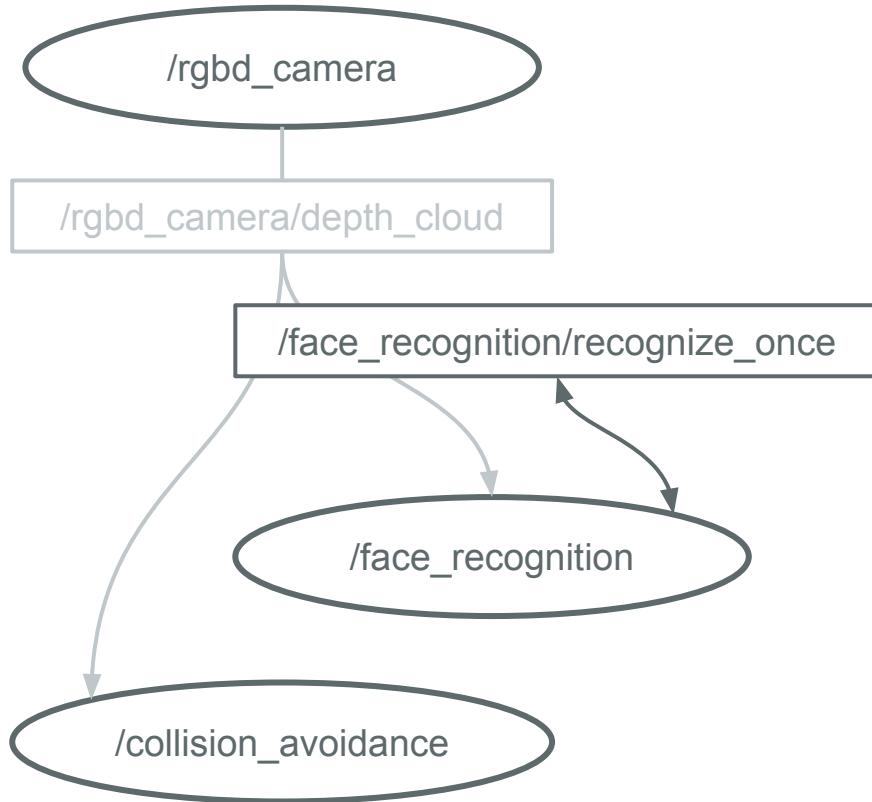
Nodes talk to one another through ROS messages.

A ROS message is published on a topic. Every node subscribed to that topic will receive the message.

Each Topic has:

- A list of publishers and subscribers.
- A message type.
- A globally unique name.

Services



Some nodes provide a remote procedure call, called a service.

Services have:

- a globally unique topic name.
- A single service provider.
- A request and response type.

They are different from messages:

- Calling a service is blocking.
- Services have a return value.

Nodes (and launch files)

```
<launch>
  <node name="listener" pkg="rospy_tutorials" type="listener.py" output="screen"/>
  <node name="talker" pkg="rospy_tutorials" type="talker.py" output="screen"/>
</launch>
```

```
> rosrun rospy_tutorials talker_listener.launch
```

```
> rostopic list
```

```
> rostopic info /talker
```

Parameters

```
<launch>
  <node name="listener" pkg="rospy_tutorials" type="listener.py" output="screen"/>
  <node name="talker" pkg="rospy_tutorials" type="talker.py" output="screen"/>
</launch>
```

> rosparam list

> rosparam get /run_id

Messages

```
<launch>
  <node name="listener" pkg="rospy_tutorials" type="listener.py" output="screen"/>
  <node name="talker" pkg="rospy_tutorials" type="talker.py" output="screen"/>
</launch>
```

> rostopic list

> rostopic info /chatter

> rostopic echo /chatter -n 5

Services

```
<launch>
  <node name="listener" pkg="rospy_tutorials" type="listener.py" output="screen"/>
  <node name="talker" pkg="rospy_tutorials" type="talker.py" output="screen"/>
</launch>
```

```
> rosservice list
```

```
> rosservice info /talker/get_loggers
```

```
> rosservice call /talker/get_loggers "{}"
```

Part 2: ROSPlan

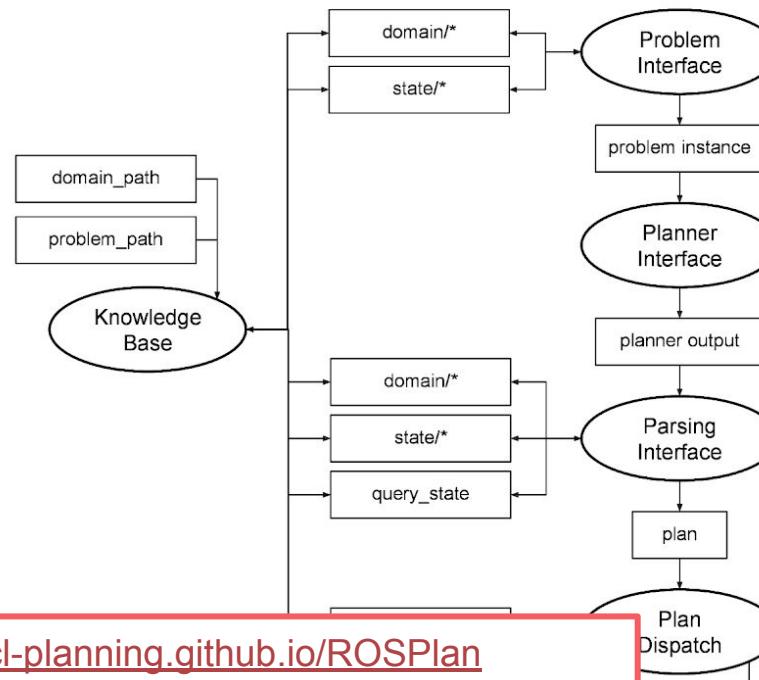
Nodes, Parameters, and Launch

ROSPlan

[Home](#)[Documentation & Tutorials](#)[Virtual Machine](#)[Demos and Conferences](#)[Publications](#)[View on GitHub](#)[Contact](#)

ROSPlan Overview

The ROSPlan framework provides a collection of tools for AI Planning in a ROS system. ROSPlan has a variety of nodes which encapsulate planning, problem generation, and plan execution.



<https://kcl-planning.github.io/ROSPlan>

Main
[Documentation Home](#)

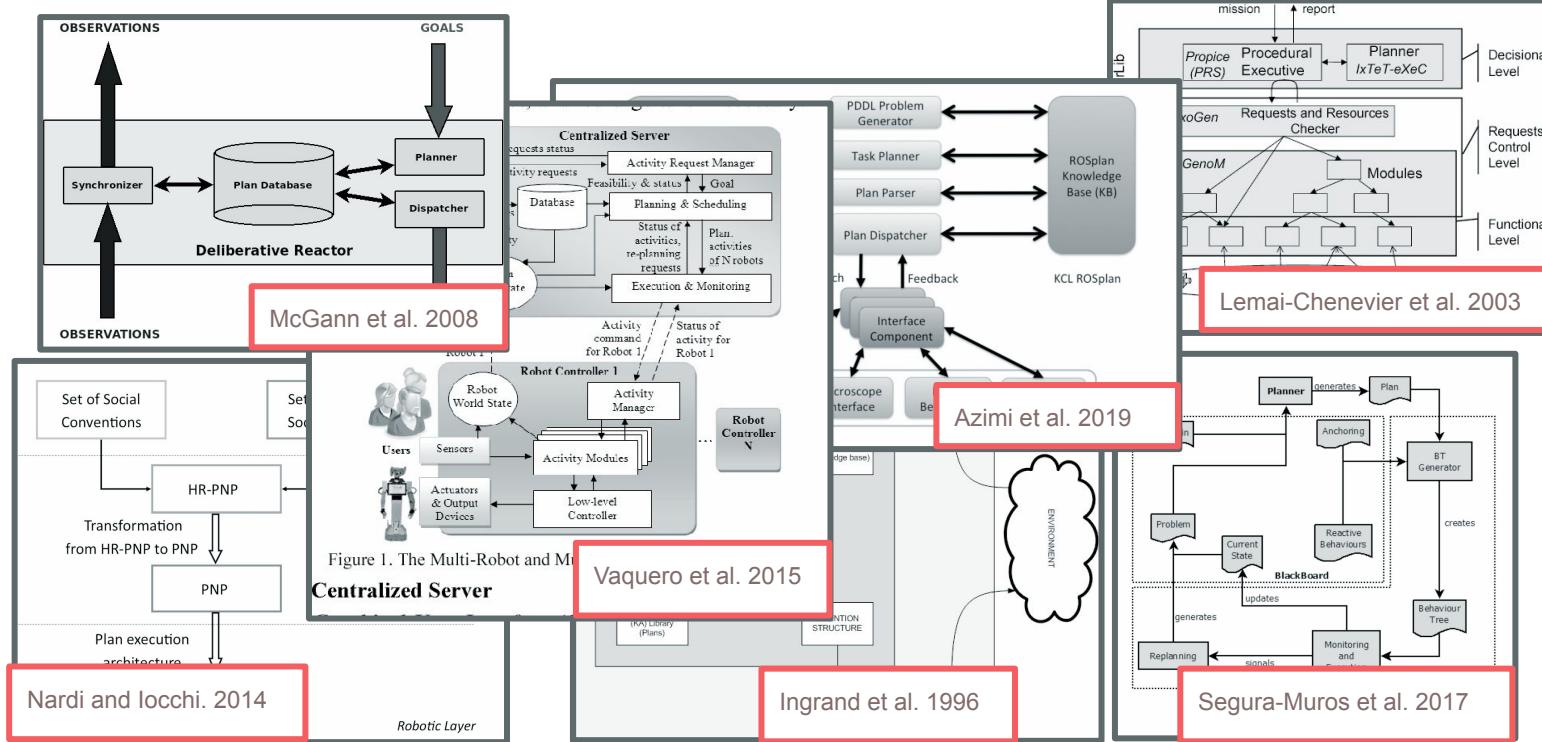
Tutorials
[Tutorial 01 Problem Generation](#)
[Tutorial 02 Planning](#)
[Tutorial 03 Plan Execution I](#)
[Tutorial 04 Simulated Actions](#)
[Tutorial 05 Plan Execution II](#)
[Tutorial 06 Knowledge Base I](#)
[Tutorial 07 Knowledge Base II](#)
[Tutorial 08 Knowledge Base III](#)
[Tutorial 09 Knowledge Base IV](#)
[Tutorial 10 Action Interface](#)

Planning and Execution
[Problem Interface](#)
[Planner Interface](#)
[Parsing Interface](#)
[Plan Dispatch](#)

Knowledge Management
[Knowledge Base Launch](#)
[Message 01 Domain Messages](#)
[Message 02 KnowledgeItem](#)
[Message 03 Numeric Expressions](#)

Task Planning and Robotics

A wealth of system architectures.



Task Planning and Robotics

A wealth of system architectures.

What components (or interfaces) are:

- Common to all system architectures?
- Atomic (perform a single function that cannot be broken down)?

Task Planning and Robotics

A wealth of system architectures.

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- Atomic (perform a single function that cannot be broken down)?

The following nodes can be combined in different ways to form a variety of system architectures.

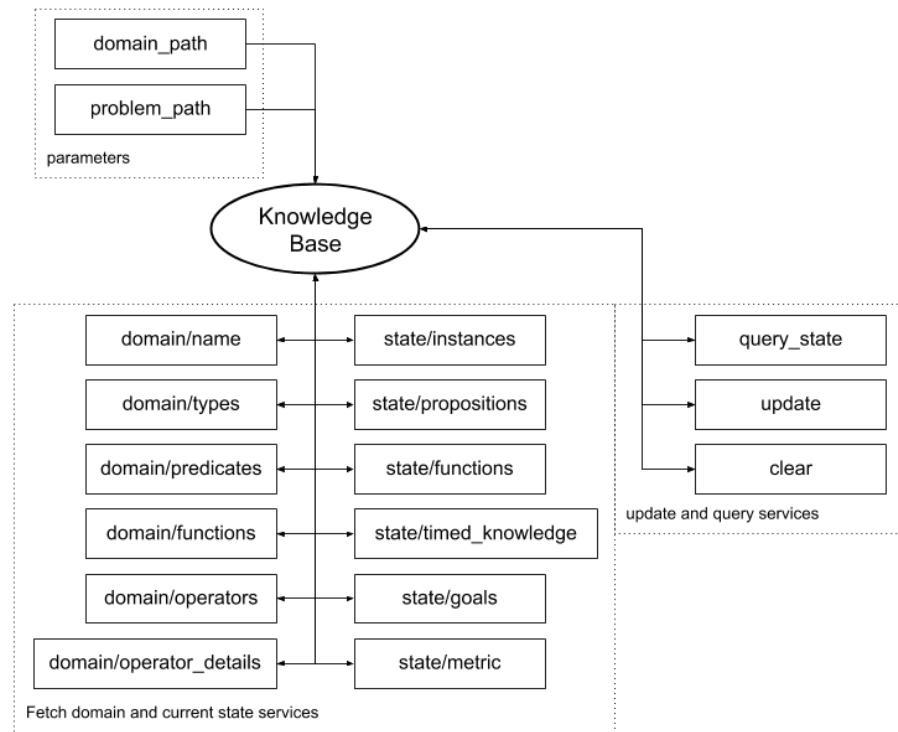
Each performs a single function and can be replaced by more sophisticated methods, or used alone within a custom framework.

Knowledge Management System

The KMS stores the domain model and the current state.

The node is launched with a domain file parameter, and an optional problem file parameter, which specifies the initial state.

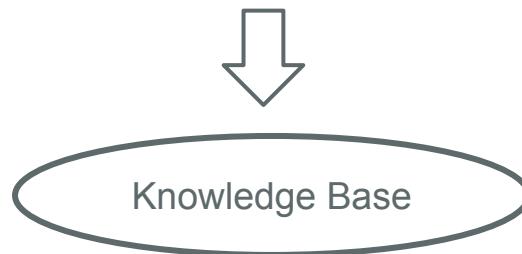
There are many services for fetching domain details, the current state, and performing queries.



Knowledge Management System

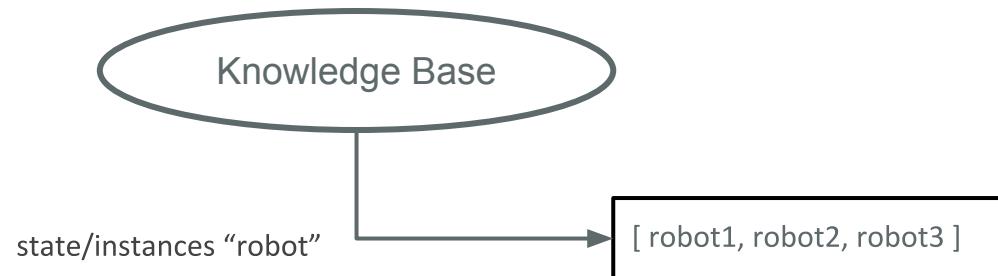
The Knowledge Base node is used to access a domain and state from any node.

```
(define (domain turtlebot)
  (:types waypoint robot - object)
  (:predicates
    (robot_at ?v - robot ?wp - waypoint)
    (undocked ?v - robot)
    (docked ?v - robot)
    (localised ?v - robot)
    (dock_at ?wp - waypoint))
  ...)
```



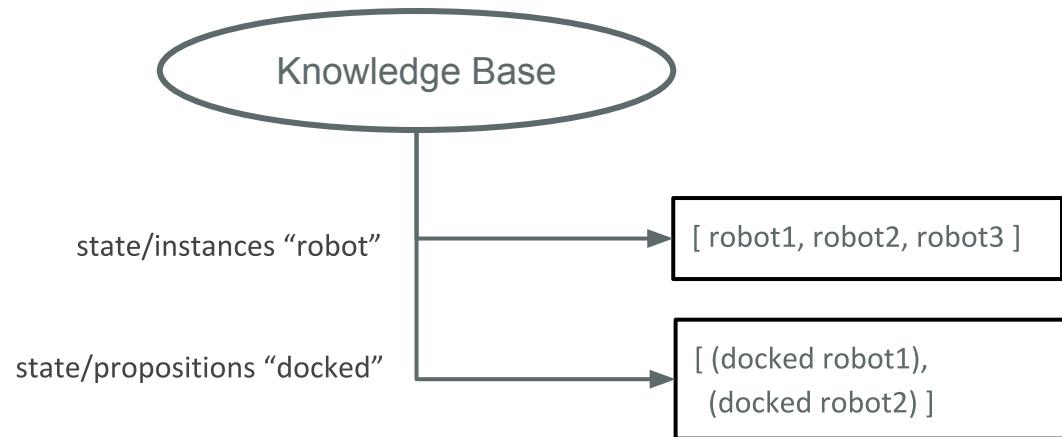
Knowledge Management System

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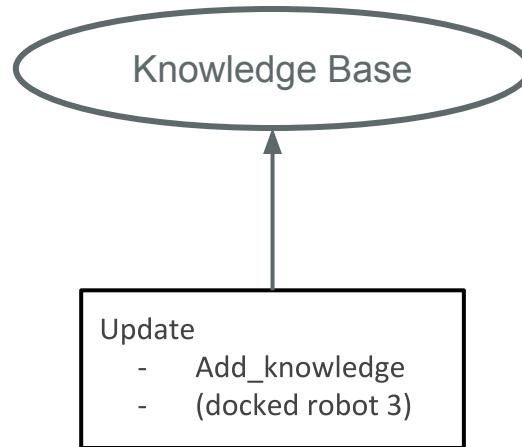


Knowledge Management System

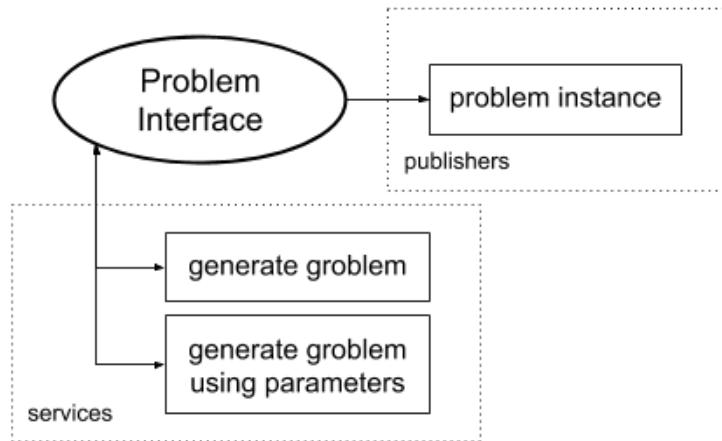
The Knowledge Base node is used to access a domain and state from any node.

The Knowledge Base can be updated based on sensed data to represent the current state.

A persistent state is built from **observations** over time and is essential for online planning.



Problem Interface

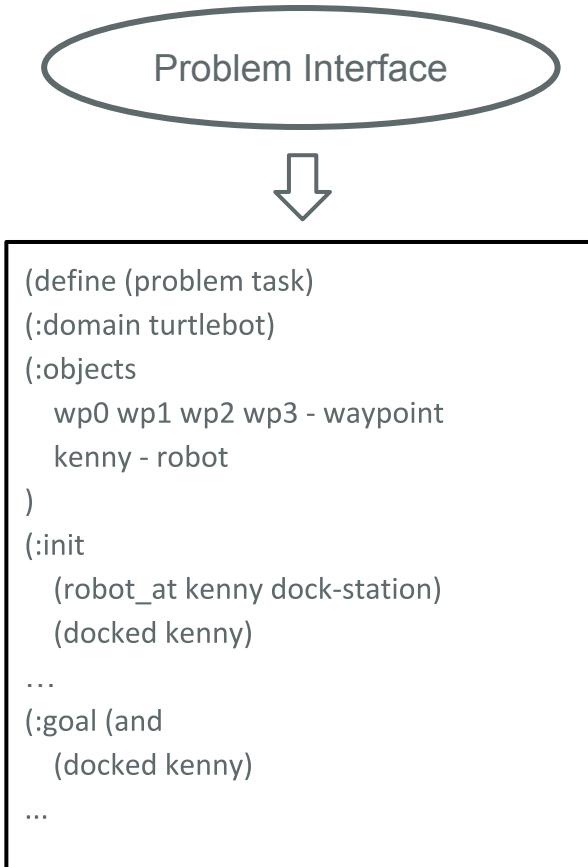


This node is used to generate a problem instance.

It fetches the domain details and current state through service calls to the KMS.

The problem instances can be written to a file and/or published as a ROS message.

Problem Interface



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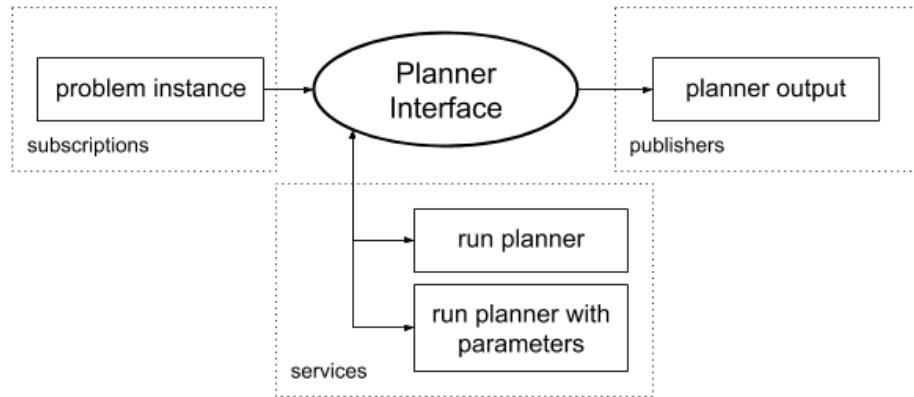
The problem instances can be written to a file and/or published as a ROS message.

Planner Interface

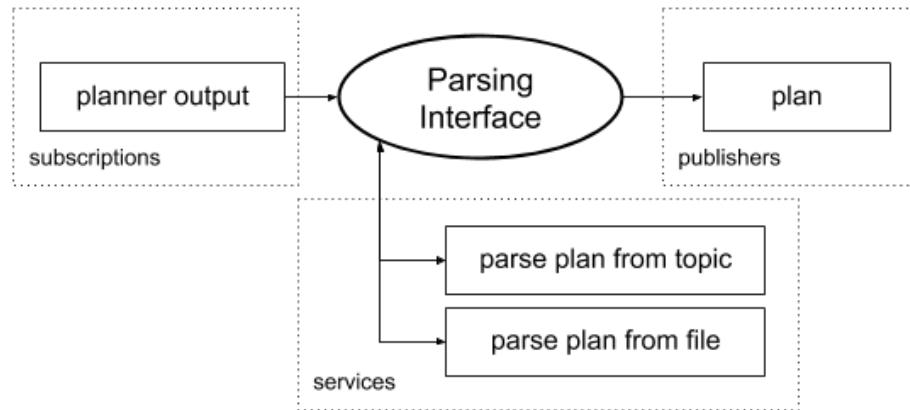
This node is a wrapper for the AI Planner. The *run planner* service returns true if a solution is found by the planner.

The command line used to run the planner is specified by a launch parameter.

The resulting solution, if one was found, can be written to a file and/or published as a ROS message.



Parsing Interface



This node is used to convert planner output into a representation for execution.

A ROS message is created for each individual action.

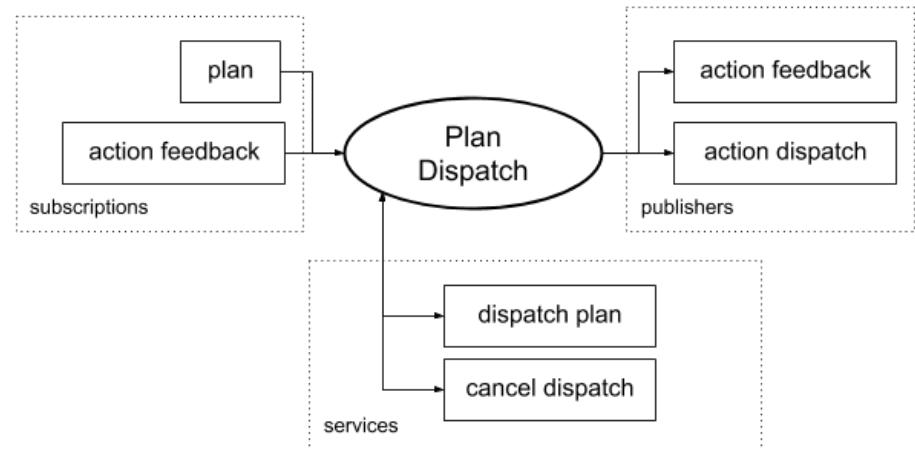
The ROS messages are stored together in one plan message, which can also describe how the plan should be executed.

Plan Dispatch

This node is responsible for executing a plan message by publishing the action messages at the right times.

The Plan Dispatch node is closely tied to the Parsing Interface. They must use the same plan representation.

The plan is executed as a service, whose response includes whether the plan was executed without errors, and achieved the goal.



```
<?xml version="1.0"?>
<launch>


<arg name="domain_path"      default="$(find rosplan_demos)/common/domain_turtlebot.pddl" />
<arg name="problem_path"     default="$(find rosplan_demos)/common/problem_turtlebot.pddl" />
<arg name="autom_gen_problem_path" default="$(find rosplan_demos)/common/problem.pddl" />


<node name="rosplan_knowledge_base" pkg="rosplan_knowledge_base" type="knowledgeBase" respawn="false" output="screen">
    <param name="domain_path" value="$(arg domain_path)" />
    <param name="problem_path" value="$(arg problem_path)" />
    <!-- conditional planning flags -->
    <param name="use_unknowns" value="false" />
</node>


<include file="$(find rosplan_planning_system)/launch/includes/problem_interface.launch">
    <arg name="knowledge_base" value="rosplan_knowledge_base" />
    <arg name="domain_path" value="$(arg domain_path)" />
    <!-- problem_path: pddl problem will be automatically generated and placed in this location -->
    <arg name="problem_path" value="$(arg autom_gen_problem_path)" />
    <arg name="problem_topic" value="problem_instance" />
</include>

</launch>
```

```

(define (domain turtlebot)

(:requirements :strips :typing :fluents :disjunctive-preconditions :durative-actions)

(:types
  waypoint
  robot
)

(:predicates
  (robot_at ?v - robot ?wp - waypoint)
  (visited ?wp - waypoint)
  (undocked ?v - robot)
  (docked ?v - robot)
  (localised ?v - robot)
  (dock_at ?wp - waypoint)
)

;; Move to any waypoint, avoiding terrain
(:durative-action goto_waypoint
  :parameters (?v - robot ?from ?to - waypoint)
  :duration (= ?duration 60)
  :condition (and
    (at start (robot_at ?v ?from))
    (at start (localised ?v))
    (over all (undocked ?v)))
  :effect (and
    (at end (visited ?to))
    (at end (robot_at ?v ?to))
    (at start (not (robot_at ?v ?from)))))
)

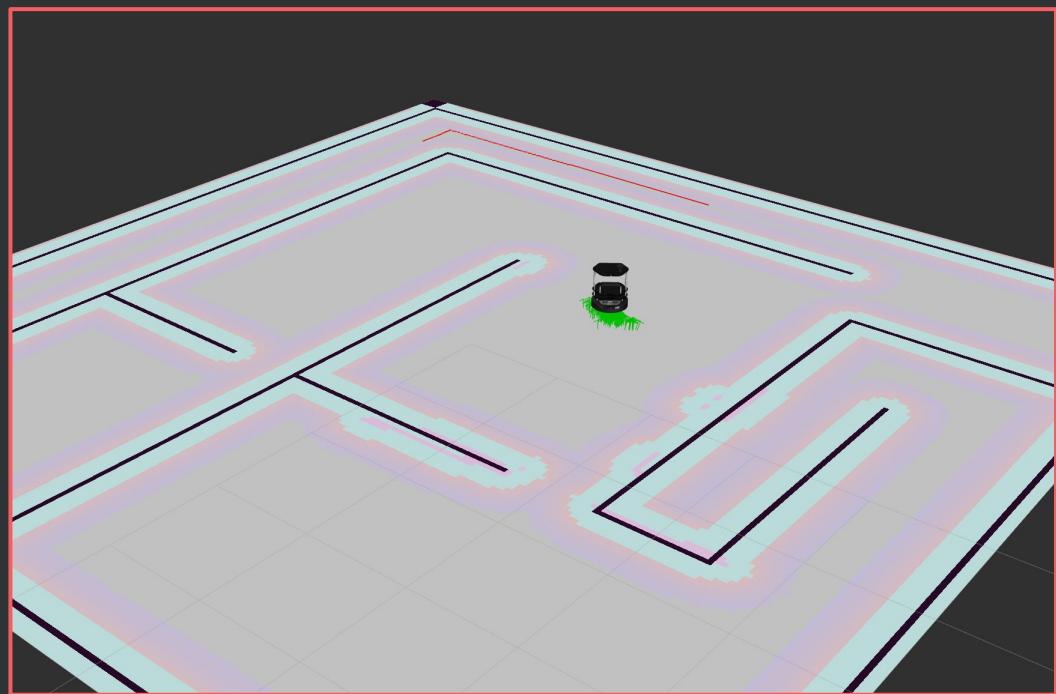
;; Localise
(:durative-action localise
  :parameters (?v - robot)
  :duration (= ?duration 60)
  :condition (over all (undocked ?v))
  :effect (at end (localised ?v))
)

;; Dock to charge
(:durative-action dock
  :parameters (?v - robot ?wp - waypoint)
  :duration (= ?duration 30)
  :condition (and
    (over all (dock_at ?wp))
    (at start (robot_at ?v ?wp)))
    (at start (undocked ?v)))
  :effect (and
    (at end (docked ?v))
    (at start (not (undocked ?v))))
  )

(:durative-action undock
  :parameters (?v - robot ?wp - waypoint)
  :duration (= ?duration 10)
  :condition (and
    (over all (dock_at ?wp))
    (at start (docked ?v)))
  :effect (and
    (at start (not (docked ?v)))
    (at end (undocked ?v))))
  )
)

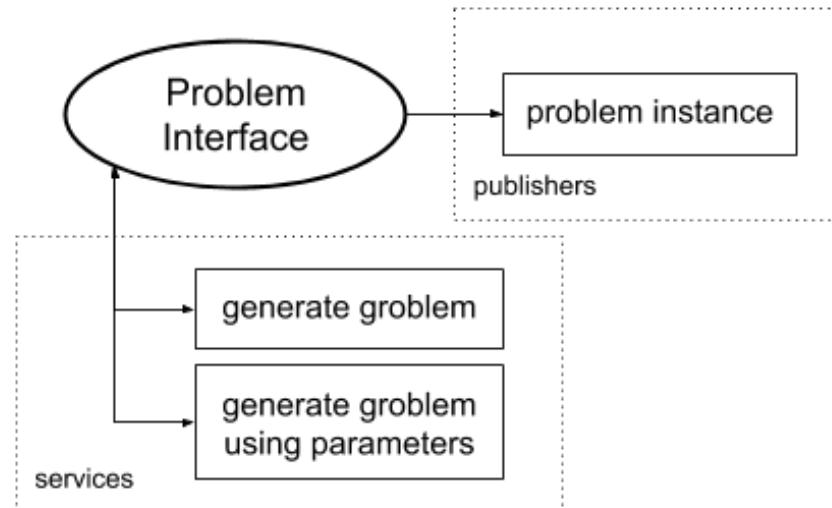
```

```
(define (problem task)
  (:domain turtlebot)
  (:objects
    wp0 wp1 wp2 wp3 wp4 - waypoint
    kenny - robot
  )
  (:init
    (robot_at kenny wp0)
    (docked kenny)
    (dock_at wp0)
  )
  (:goal (and
    (visited wp0)
    (visited wp1)
    (visited wp2)
    (visited wp3)
    (visited wp4)
    (docked kenny)
  )))
))
```



Problem Generator

Problem Generation



```
<?xml version="1.0"?>
<launch>


<arg name="domain_path"      default="$(find rosplan_demos)/common/domain_turtlebot.pddl" />
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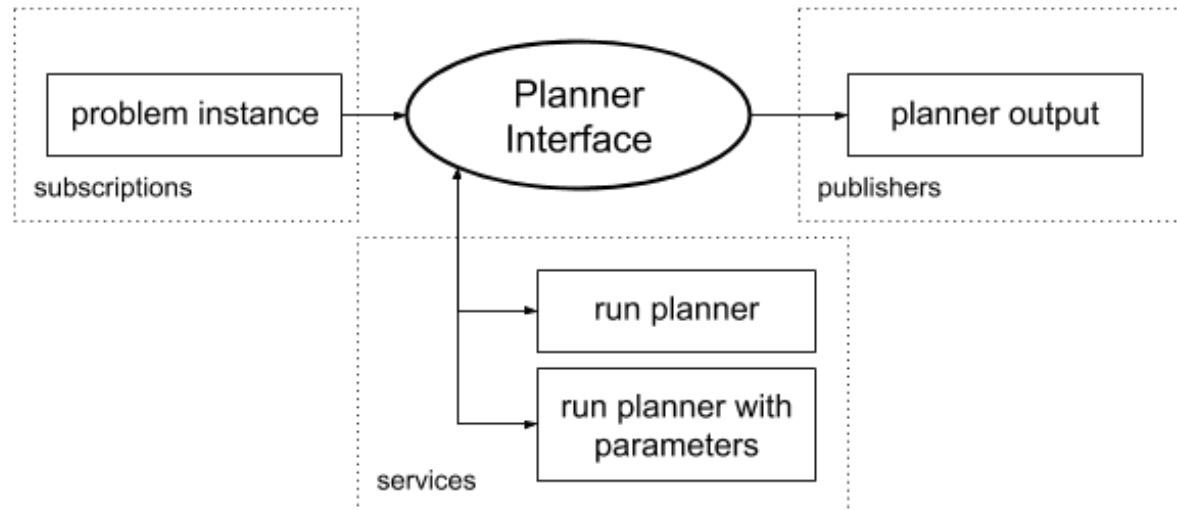

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Planner Interface

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  <arg name="knowledge_base" value="rosplan_knowledge_base" />
  <arg name="domain_path" value="$(arg domain_path)" />
  <!-- problem_path: pddl problem will be automatically generated and placed in this location -->
  <arg name="problem_path" value="$(arg autom_gen_problem_path)" />
  <arg name="problem_topic" value="problem_instance" />
</include>


<include file="$(find rosplan_planning_system)/launch/includes/planner_interface.launch">
  <arg name="use_problem_topic" value="true" />
  <arg name="problem_topic" value="/rosplan_problem_interface/problem_instance" />
  <arg name="planner_topic" value="planner_output" />
  <arg name="domain_path" value="$(arg domain_path)" />
  <arg name="problem_path" value="$(arg autom_gen_problem_path)" />
  <arg name="data_path" value="$(find rosplan_demos)/common/" />
  <arg name="planner_command" value="timeout 10 $(find rosplan_planning_system)/common/bin/popf DOMAIN PROBLEM" />
</include>
</launch>
```

```

<?xml version="1.0"?>
<launch>

<!-- arguments -->
<arg name="domain_path"      default="$(find rosplan_demos)/common/domain_turtlebot.pddl" />
<arg name="problem_path"     default="$(find rosplan_demos)/common/problem_turtlebot.pddl" />
<arg name="autom_gen_problem_path" default="$(find rosplan_demos)/common/problem.pddl" />

<!-- knowledge base -->
<node name="rosplan_knowledge_base" pkg="rosplan_knowledge_base" type="knowledgeBase" respawn="false" output="screen">
    <param name="domain_path" value="$(arg domain_path)" />
    <param name="problem_path" value="$(arg problem_path)" />
    <!-- conditional planning flags -->
    <param name="use_unknowns" value="false" />
</node>

<!-- problem generation -->
<include file="$(find rosplan_planning_system)/launch/includes/problem_interface.launch">
    <arg name="knowledge_base" value="rosplan_knowledge_base" />
    <arg name="domain_path" value="$(arg domain_path)" />
    <!-- problem_path: pddl problem will be automatically generated and placed in this location -->
    <arg name="problem_path" value="$(arg autom_gen_problem_path)" />
    <arg name="problem_topic" value="problem_instance" />
</include>

<!-- planner interface -->
<include file="$(find rosplan_planning_system)/launch/includes/planner_interface.launch">
    <arg name="use_problem_topic" value="true" />
    <arg name="problem_topic" value="/rosplan_problem_interface/problem_instance" />
    <arg name="planner_topic" value="planner_output" />
    <arg name="domain_path" value="$(arg domain_path)" />
    <arg name="problem_path" value="$(arg autom_gen_problem_path)" />
    <arg name="data_path" value="$(find rosplan_demos)/common/" />
    <arg name="planner_command" value="timeout 10 $(find rosplan_planning_system)/common/bin/popf DOMAIN PROBLEM" />
</include>
</launch>

```

```
<?xml version="1.0"?>
<launch>


<arg name="domain_path"      default="$(find rosplan_demos)/common/domain_turtlebot.pddl" />
<arg name="problem_path"     default="$(find rosplan_demos)/common/problem_turtlebot.pddl" />
<arg name="autom_gen_problem_path" default="$(find rosplan_demos)/common/problem.pddl" />


<node name="rosplan_knowledge_base" pkg="rosplan_knowledge_base" type="knowledgeBase" respawn="false" output="screen">
    <param name="domain_path" value="$(arg domain_path)" />
    <param name="problem_path" value="$(arg problem_path)" />
    <!-- conditional planning flags -->
    <param name="use_unknowns" value="false" />
</node>


<include file="$(find rosplan_planning_system)/launch/includes/problem_interface.launch">
    <arg name="knowledge_base" value="rosplan_knowledge_base" />
    <arg name="domain_path" value="$(arg domain_path)" />
    <!-- problem_path: pddl problem will be automatically generated and placed in this location -->
    <arg name="problem_path" value="$(arg autom_gen_problem_path)" />
    <arg name="problem_topic" value="problem_instance" />
</include>


<include file="$(find rosplan_planning_system)/launch/includes/planner_interface.launch">
    <arg name="use_problem_topic" value="true" />
    <arg name="problem_topic" value="/rosplan_problem_interface/problem_instance" />
    <arg name="planner_topic" value="planner_output" />
    <arg name="domain_path" value="$(arg domain_path)" />
    <arg name="problem_path" value="$(arg autom_gen_problem_path)" />
    <arg name="data_path" value="$(find rosplan_demos)/common/" />
    <arg name="planner_command" value="timeout 10 $(find rosplan_planning_system)/common/bin/popf DOMAIN PROBLEM" />
</include>
</launch>
```

```
<?xml version="1.0"?>
<launch>


<arg name="domain_path"      default="$(find rosplan_demos)/common/domain_turtlebot.pddl" />
<arg name="problem_path"     default="$(find rosplan_demos)/common/problem_turtlebot.pddl" />
<arg name="autom_gen_problem_path" default="$(find rosplan_demos)/common/problem.pddl" />

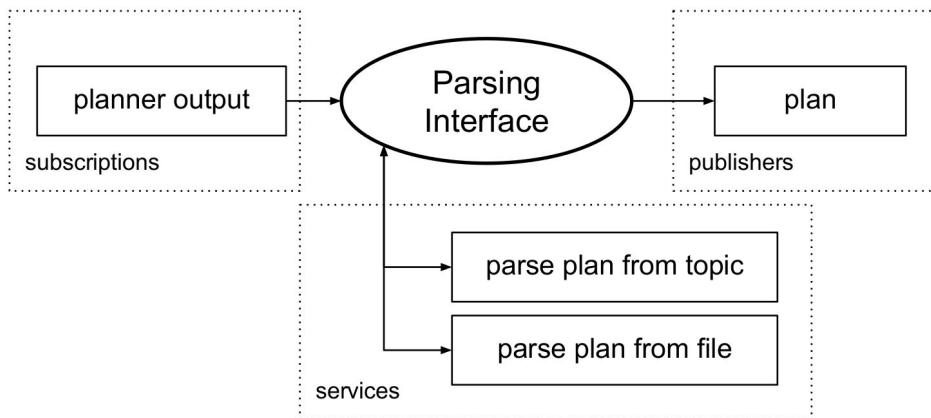

<node name="rosplan_knowledge_base" pkg="rosplan_knowledge_base" type="knowledgeBase" respawn="false" output="screen">
    <param name="domain_path" value="$(arg domain_path)" />
    <param name="problem_path" value="$(arg problem_path)" />
    <!-- conditional planning flags -->
    <param name="use_unknowns" value="false" />
</node>


<include file="$(find rosplan_planning_system)/launch/includes/problem_interface.launch">
    <arg name="knowledge_base" value="rosplan_knowledge_base" />
    <arg name="domain_path" value="$(arg domain_path)" />
    <!-- problem_path: pddl problem will be automatically generated and placed in this location -->
    <arg name="problem_path" value="$(arg autom_gen_problem_path)" />
    <arg name="problem_topic" value="problem_instance" />
</include>


<include file="$(find rosplan_planning_system)/launch/includes/planner_interface.launch">
    <arg name="use_problem_topic" value="true" />
    <arg name="problem_topic" value="/rosplan_problem_interface/problem_instance" />
    <arg name="planner_topic" value="planner_output" />
    <arg name="domain_path" value="$(arg domain_path)" />
    <arg name="problem_path" value="$(arg autom_gen_problem_path)" />
    <arg name="data_path" value="$(find rosplan_demos)/common/" />
    <arg name="planner_command" value="timeout 10 $(find rosplan_planning_system)/common/bin/popf DOMAIN PROBLEM" />
</include>
</launch>
```

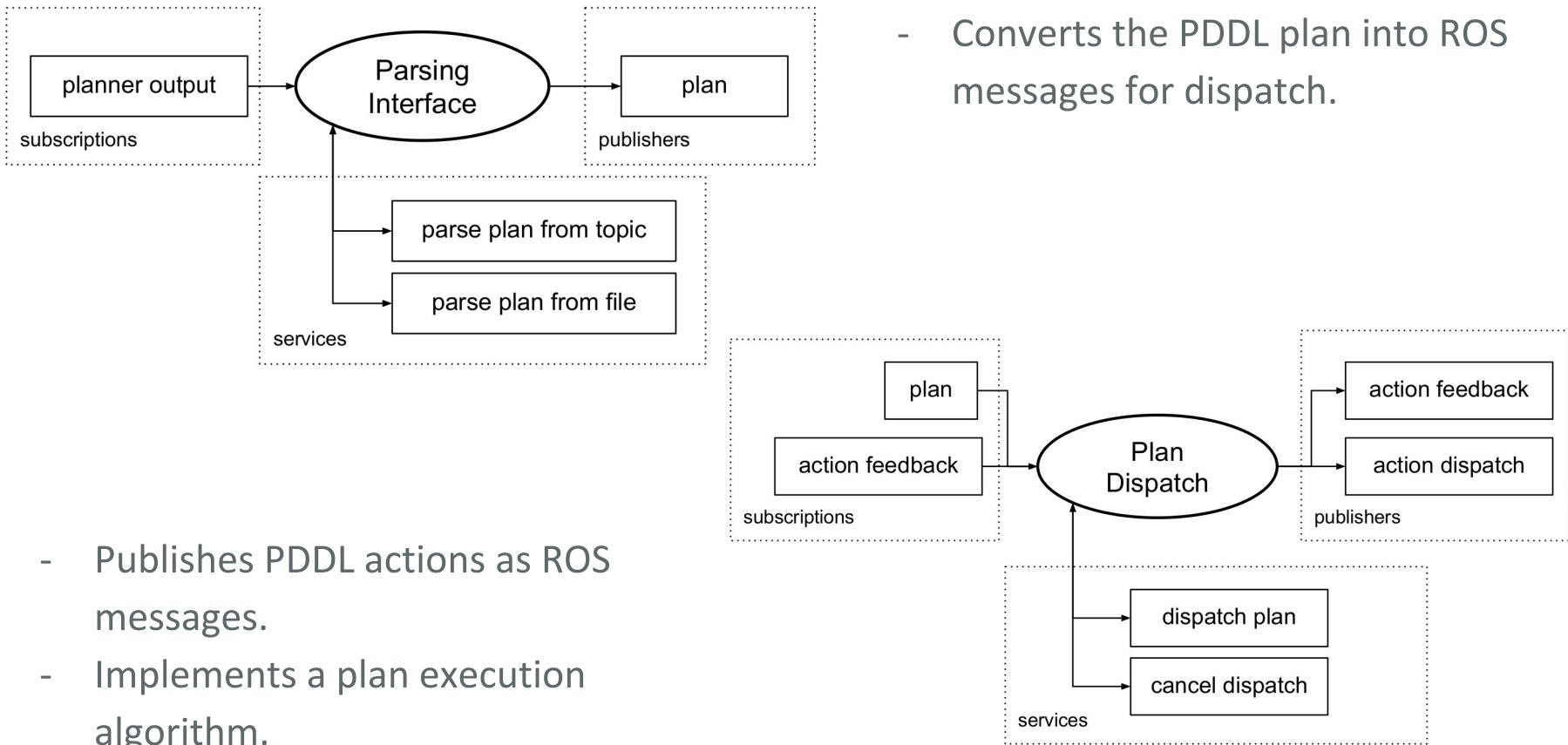
Plan Execution 01

Plan Execution



- Converts the PDDL plan into ROS messages for dispatch.

Plan Execution



```
<!-- planner interface -->
<include file="$(find rosplan_planning_system)/launch/includes/planner_interface.launch">
  <arg name="use_problem_topic" value="true" />
  <arg name="problem_topic" value="/rosplan_problem_interface/problem_instance" />
  <arg name="planner_topic" value="planner_output" />
  <arg name="domain_path" value="${arg domain_path}" />
  <arg name="problem_path" value="${arg autom_gen_problem_path}" />
  <arg name="data_path" value="$(find rosplan_demos)/common/" />
  <arg name="planner_command" value="timeout 10 $(find rosplan_planning_system)/common/bin/popf DOMAIN PROBLEM" />
</include>

<!-- plan parsing -->
<node name="rosplan_parsing_interface" pkg="rosplan_planning_system" type="pddl_simple_plan_parser" respawn="false" output="screen">
  <param name="knowledge_base" value="rosplan_knowledge_base" />
  <param name="planner_topic" value="/rosplan_planner_interface/planner_output" />
  <param name="plan_topic" value="complete_plan" />
</node>

<!-- plan dispatching -->
<node name="rosplan_plan_dispatcher" pkg="rosplan_planning_system" type="pddl_simple_plan_dispatcher" respawn="false" output="screen">
  <param name="knowledge_base" value="rosplan_knowledge_base" />
  <param name="plan_topic" value="/rosplan_parsing_interface/complete_plan" />
  <param name="action_dispatch_topic" value="action_dispatch" />
  <param name="action_feedback_topic" value="action_feedback" />
</node>
```

Plan Execution 02

Simulated Actions

Action Interfaces

A ROS message representing a PDDL action must be connected to the implementation of that action.

- To an existing library through ROS service(s).
- To an existing library through ROS actionlib message topics.
- To a custom implementation.
- Or to a combination of the above.

Action Interfaces

```
(goto_waypoint robot_10 wp3 wp9)
```



Action Interfaces

```
(goto_waypoint robot_10 wp3 wp9)
```

- Is the arm already stowed for movement?
- What are the coordinates of the waypoint?
- What is the orientation of the waypoint - is it correct for the next action?
- Does the action have its own timeout?
- Can the action be preempted?



Action Interfaces

```
(goto_waypoint robot_10 wp3 wp9)
```

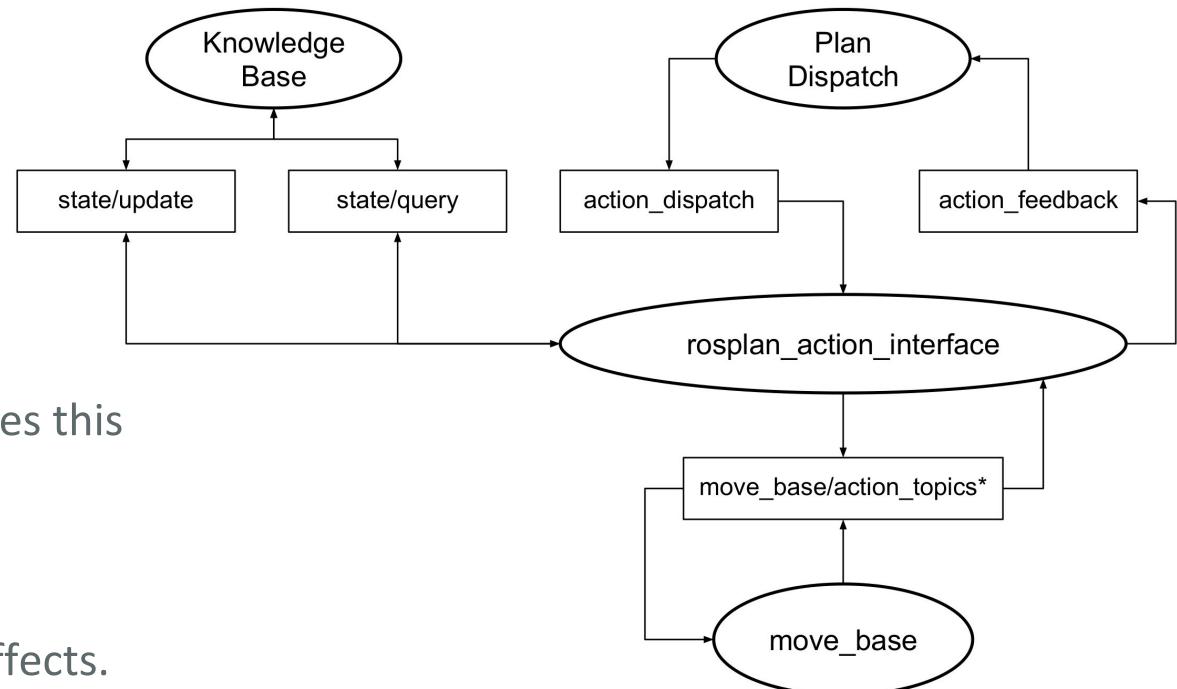
- Are all the effects of the action possible to sense?



Action Interfaces

- Subscribes to PDDL actions.
- Calls execution.
- (Optionally) updates the Knowledge Base with action effects.

Action Interfaces



The action interface node makes this simpler to implement.

- Checks PDDL parameters.
- Updates KB with action effects.
- Subscription to monitor action cancellation.
- **Calls abstract execution method.**
- Returns action feedback.

```

<!-- planner interface -->
<include file="$(find rosplan_planning_system)/launch/includes/planner_interface.launch">
  <arg name="use_problem_topic" value="true" />
  <arg name="problem_topic" value="/rosplan_problem_interface/problem_instance" />
  <arg name="planner_topic" value="planner_output" />
  <arg name="domain_path" value="${arg domain_path}" />
  <arg name="problem_path" value="${arg autom_gen_problem_path}" />
  <arg name="data_path" value="$(find rosplan_demos)/common/" />
  <arg name="planner_command" value="timeout 10 $(find rosplan_planning_system)/common/bin/popf DOMAIN PROBLEM" />
</include>

<!-- plan parsing -->
<node name="rosplan_parsing_interface" pkg="rosplan_planning_system" type="pddl_simple_plan_parser" respawn="false" output="screen">
  <param name="knowledge_base" value="rosplan_knowledge_base" />
  <param name="planner_topic" value="/rosplan_planner_interface/planner_output" />
  <param name="plan_topic" value="complete_plan" />
</node>

<!-- plan dispatching -->
<node name="rosplan_plan_dispatcher" pkg="rosplan_planning_system" type="pddl_simple_plan_dispatcher" respawn="false" output="screen">
  <param name="knowledge_base" value="rosplan_knowledge_base" />
  <param name="plan_topic" value="/rosplan_parsing_interface/complete_plan" />
  <param name="action_dispatch_topic" value="action_dispatch" />
  <param name="action_feedback_topic" value="action_feedback" />
</node>

<!-- sim actions -->
<include file="$(find rosplan_planning_system)/launch/includes/simulated_action.launch" >
  <arg name="pddl_action_name" value="undock" />
</include>
<include file="$(find rosplan_planning_system)/launch/includes/simulated_action.launch" >
  <arg name="pddl_action_name" value="dock" />
</include>
<include file="$(find rosplan_planning_system)/launch/includes/simulated_action.launch" >
  <arg name="pddl_action_name" value="localise" />
</include>
<include file="$(find rosplan_planning_system)/launch/includes/simulated_action.launch" >
  <arg name="pddl_action_name" value="goto_waypoint" />
</include>

```

```
<!-- simulated action -->
<node name="rosplan_interface_${arg pddl_action_name}" pkg="rosplan_planning_system" type="simulatedAction" respawn="false" output="screen">
  <param name="knowledge_base" value="$(arg knowledge_base)" />
  <param name="pddl_action_name" value="$(arg pddl_action_name)" />
  <param name="action_duration" value="$(arg action_duration)" />
  <param name="action_duration_stddev" value="$(arg action_duration_stddev)" />
  <param name="action_probability" value="$(arg action_probability)" />
  <param name="action_dispatch_topic" value="$(arg action_dispatch_topic)" />
  <param name="action_feedback_topic" value="$(arg action_feedback_topic)" />
</node>
```

The simulated action node

Extends the action interface, implementing the action execution by sleeping. Useful for simulation and testing a system!

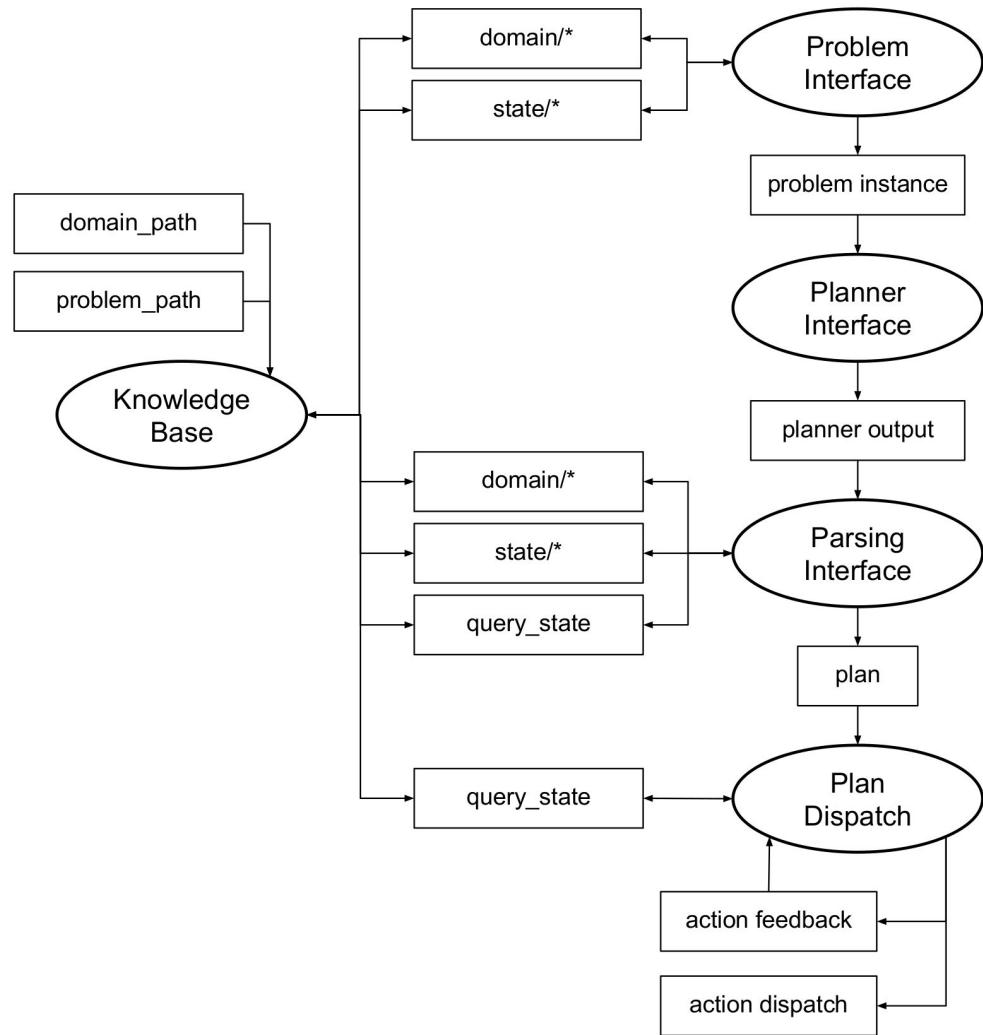
Parameters:

- Action success probability
- Fixed action duration.
- Action duration normal distribution.

Plan Execution 03

Example System

All of the nodes required to perform a simple replanning system.



```
<!-- plan parsing -->
<node name="rosplan_parsing_interface" pkg="rosplan_planning_system" type="pddl_simple_plan_parser" respawn="false" output="screen">
  <param name="knowledge_base" value="rosplan_knowledge_base" />
  <param name="planner_topic" value="/rosplan_planner_interface/planner_output" />
  <param name="plan_topic" value="complete_plan" />
</node>

<!-- plan dispatching -->
<node name="rosplan_plan_dispatcher" pkg="rosplan_planning_system" type="pddl_simple_plan_dispatcher" respawn="false" output="screen">
  <param name="knowledge_base" value="rosplan_knowledge_base" />
  <param name="plan_topic" value="/rosplan_parsing_interface/complete_plan" />
  <param name="action_dispatch_topic" value="action_dispatch" />
  <param name="action_feedback_topic" value="action_feedback" />
</node>
```

```
<!-- plan parsing -->
<node name="rosplan_parsing_interface" pkg="rosplan_planning_system" type="pddl_simple_plan_parser" respawn="false" output="screen">
    <param name="knowledge_base" value="rosplan_knowledge_base" />
    <param name="planner_topic" value="/rosplan_planner_interface/planner_output" />
    <param name="plan_topic" value="complete_plan" />
</node>

<!-- plan dispatching -->
<node name="rosplan_plan_dispatcher" pkg="rosplan_planning_system" type="pddl_simple_plan_dispatcher" respawn="false" output="screen">
    <param name="knowledge_base" value="rosplan_knowledge_base" />
    <param name="plan_topic" value="/rosplan_parsing_interface/complete_plan" />
    <param name="action_dispatch_topic" value="action_dispatch" />
    <param name="action_feedback_topic" value="action_feedback" />
</node>
```

```
<!-- plan parsing -->
<include file="$(find rosplan_planning_system)/launch/includes/parsing_interface.launch">
    <arg name="knowledge_base" value="rosplan_knowledge_base" />
    <arg name="planner_topic" value="/rosplan_planner_interface/planner_output" />
    <arg name="plan_topic" value="complete_plan" />
</include>

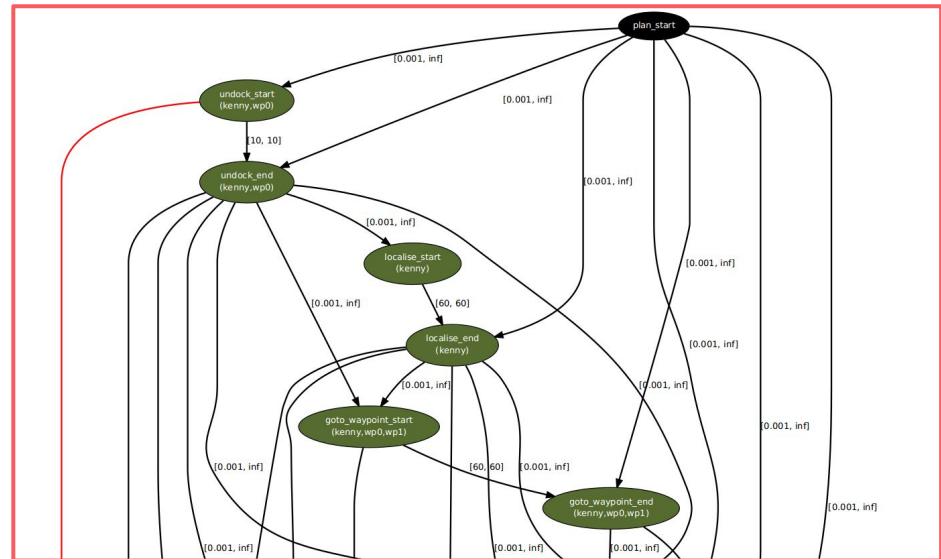
<!-- plan dispatch -->
<include file="$(find rosplan_planning_system)/launch/includes/dispatch_interface.launch">
    <arg name="knowledge_base" value="rosplan_knowledge_base" />
    <arg name="plan_topic" value="/rosplan_parsing_interface/complete_plan" />
    <arg name="action_dispatch_topic" value="action_dispatch" />
    <arg name="action_feedback_topic" value="action_feedback" />
    <arg name="display_edge_type" value="true" />
</include>
```

Plan Execution Algorithms

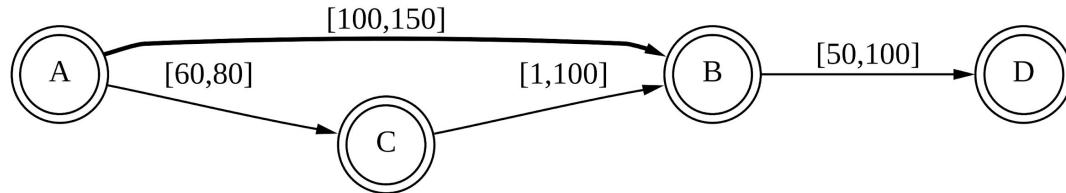
Simple Plan Dispatcher

0.000: (undock kenny wp0) [10.000]
10.001: (localise kenny) [60.000]
70.002: (goto_waypoint kenny wp0 wp0) [60.000]
130.003: (goto_waypoint kenny wp0 wp1) [60.000]
190.004: (goto_waypoint kenny wp1 wp0) [60.000]
250.005: (goto_waypoint kenny wp0 wp2) [60.000]
310.006: (goto_waypoint kenny wp2 wp0) [60.000]
370.007: (goto_waypoint kenny wp0 wp3) [60.000]
430.008: (goto_waypoint kenny wp3 wp0) [60.000]
490.009: (goto_waypoint kenny wp0 wp4) [60.000]
550.010: (goto_waypoint kenny wp4 wp0) [60.000]
610.011: (dock kenny wp0) [30.000]

Esterel Plan Dispatcher



STNU Dispatch



1. $A = \text{Set of all control points}; \text{current_time} = 0$
2. Arbitrarily pick a control point TP in A that is live and enabled in all boundary projections.
3. Set TP execution time to current_time, and remove TP from A (propagate constraints). Halt if A is now empty.
4. Advance current time, propagating all updates until some point in A is live and enabled.
5. Go to 2.

[Morris and Muscettola 1999, 2000]

```
<!-- plan dispatching -->
<node name="$(arg node_name)" pkg="rosplan_planning_system" type="pddl_estereol_plan_dispatcher" respawn="false" output="screen">
    <param name="knowledge_base" value="$(arg knowledge_base)" />
    <param name="plan_topic" value="$(arg plan_topic)" />
    <param name="action_dispatch_topic" value="$(arg action_dispatch_topic)" />
    <param name="action_feedback_topic" value="$(arg action_feedback_topic)" />
    <param name="display_edge_type" value="$(arg display_edge_type)" />
    <param name="timeout_actions" value="$(arg timeout_actions)" />
    <param name="action_timeout_fraction" value="$(arg action_timeout_fraction)" />
</node>
```

```
<!-- plan dispatching -->
<node name="$(arg node_name)" pkg="rosplan_planning_system" type="pddl_esterel_plan_dispatcher" respawn="false" output="screen">
    <param name="knowledge_base" value="$(arg knowledge_base)" />
    <param name="plan_topic" value="$(arg plan_topic)" />
    <param name="action_dispatch_topic" value="$(arg action_dispatch_topic)" />
    <param name="action_feedback_topic" value="$(arg action_feedback_topic)" />
    <param name="display_edge_type" value="$(arg display_edge_type)" />
    <param name="timeout_actions" value="$(arg timeout_actions)" />
    <param name="action_timeout_fraction" value="$(arg action_timeout_fraction)" />
</node>
```

Not all problems have deadlines:

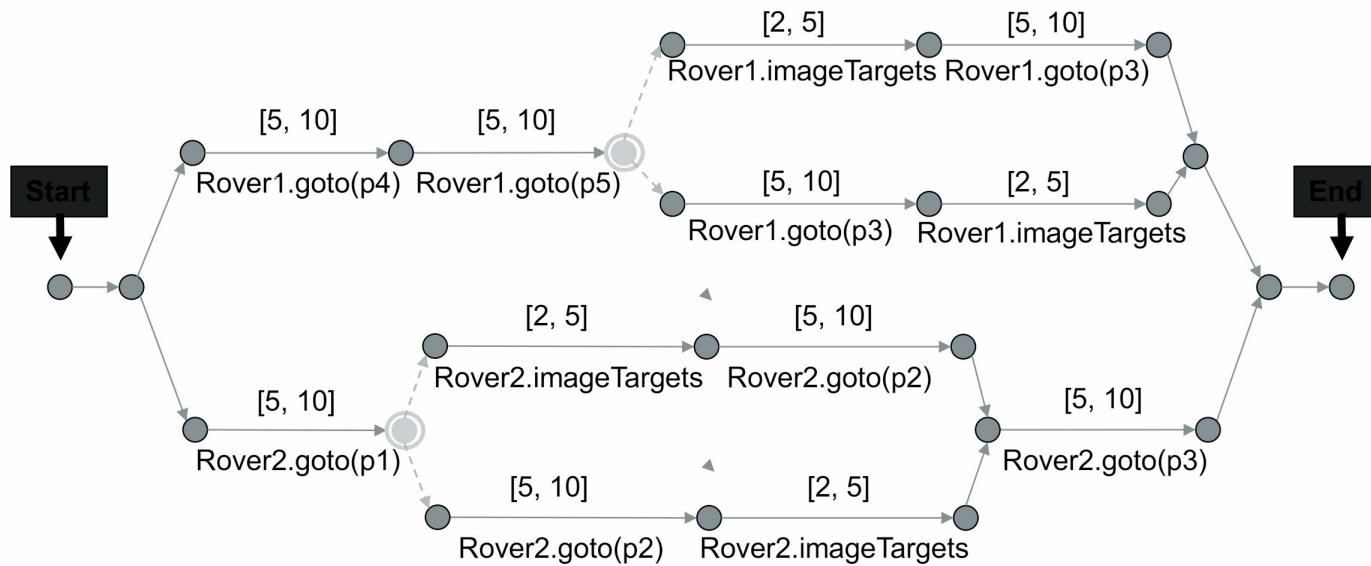
Timeout actions: when action durations are elapsed, fail the plan.

Action timeout fraction x: time out an action after

$$action_timeout_duration * duration$$

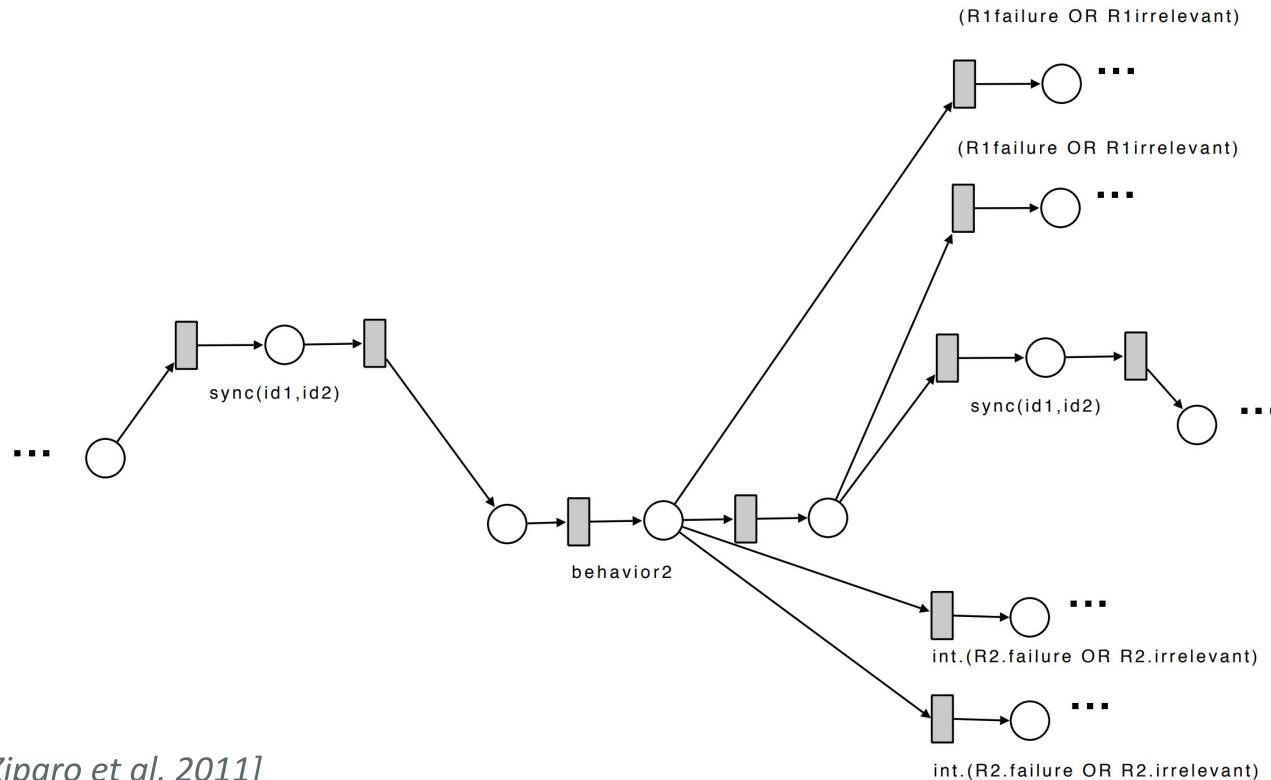
seconds.

Reactive Model-based Programming Language



[Ingham et al. 2001]

Petri-Net-Plans

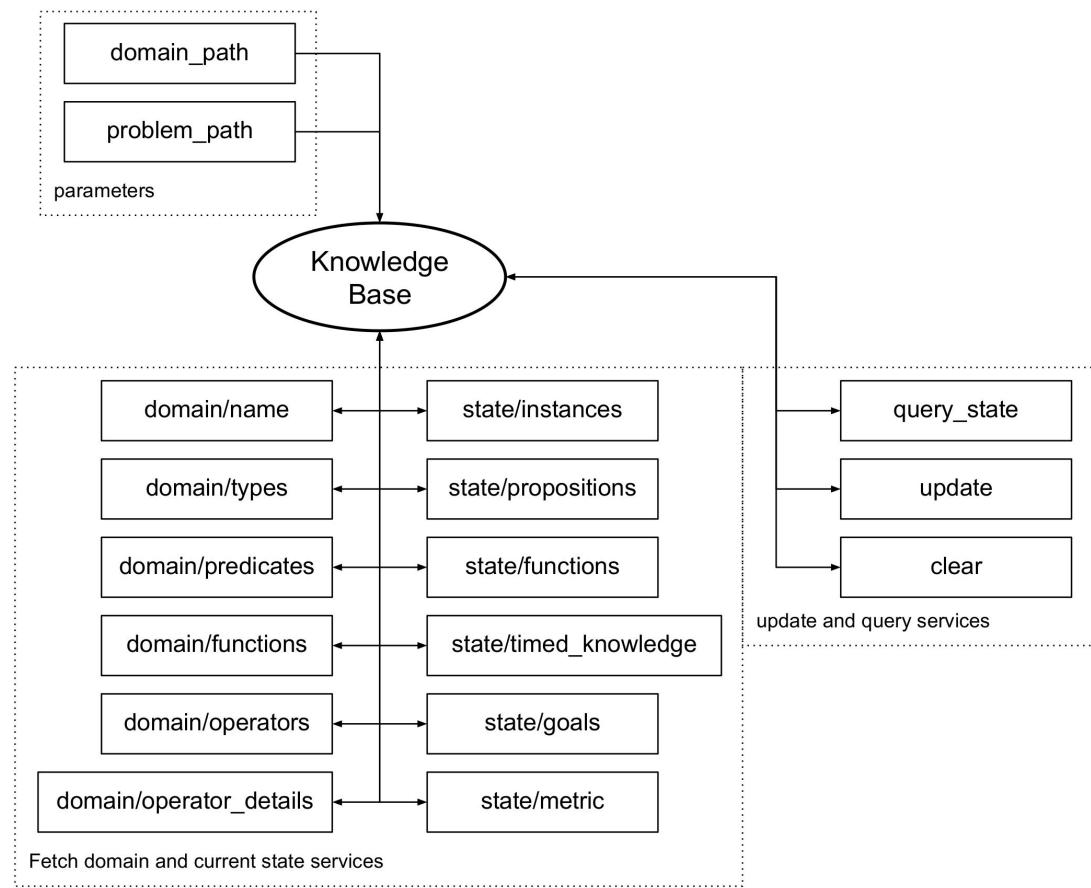


[Ziparo et al. 2011]

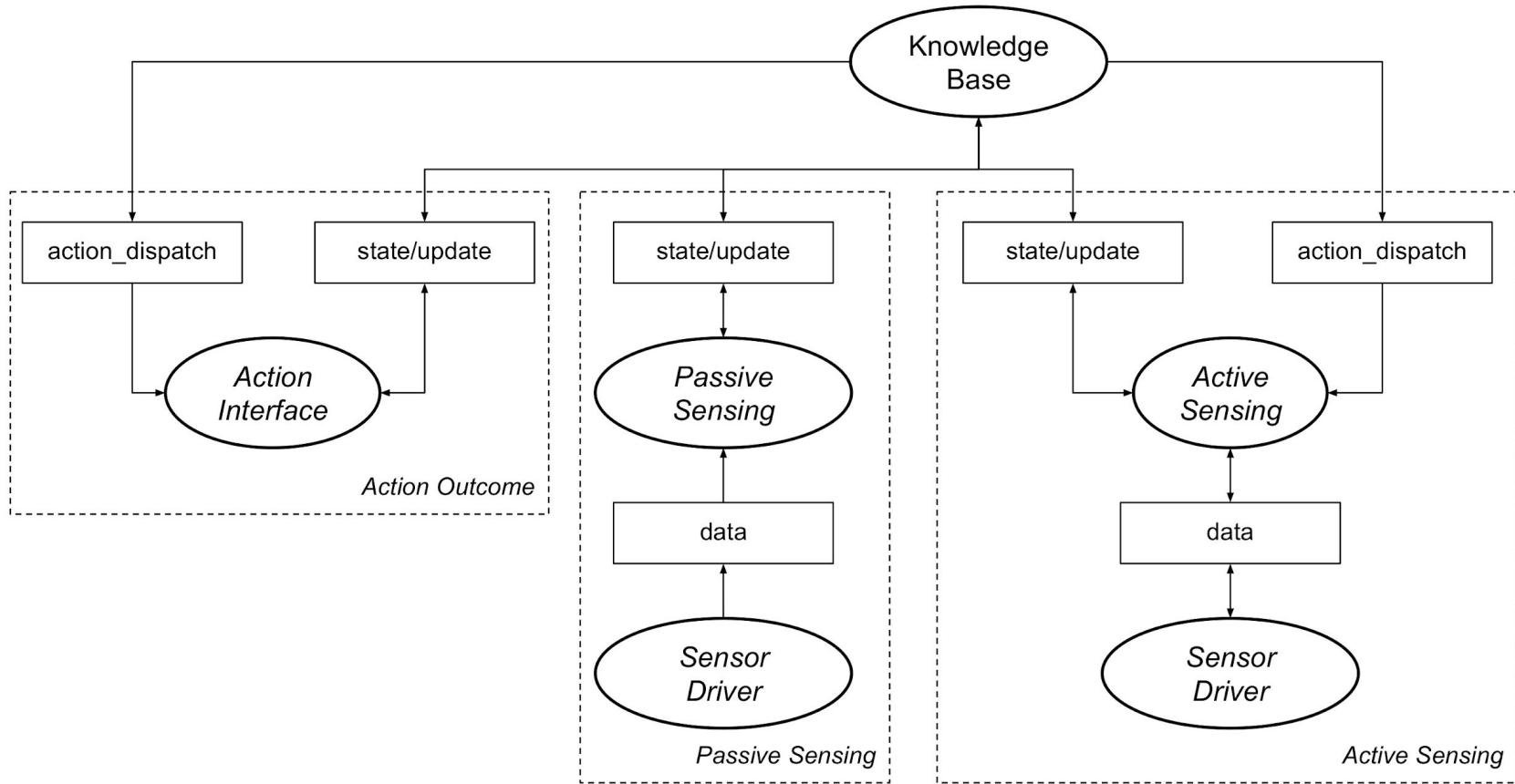
Knowledge Base

Knowledge Base

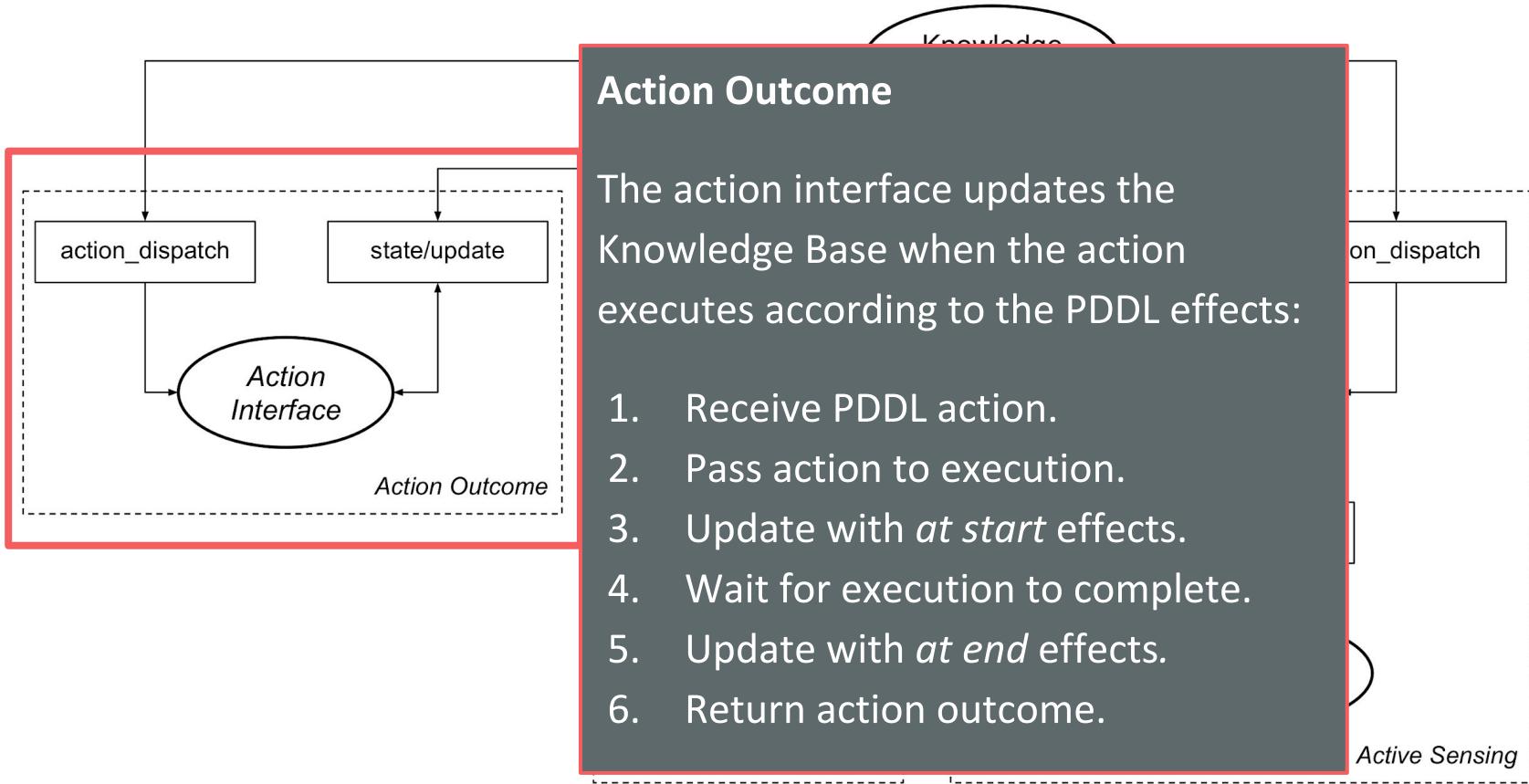
- Services for fetching domain and state.
- Services for updating current state.
- Service for query.



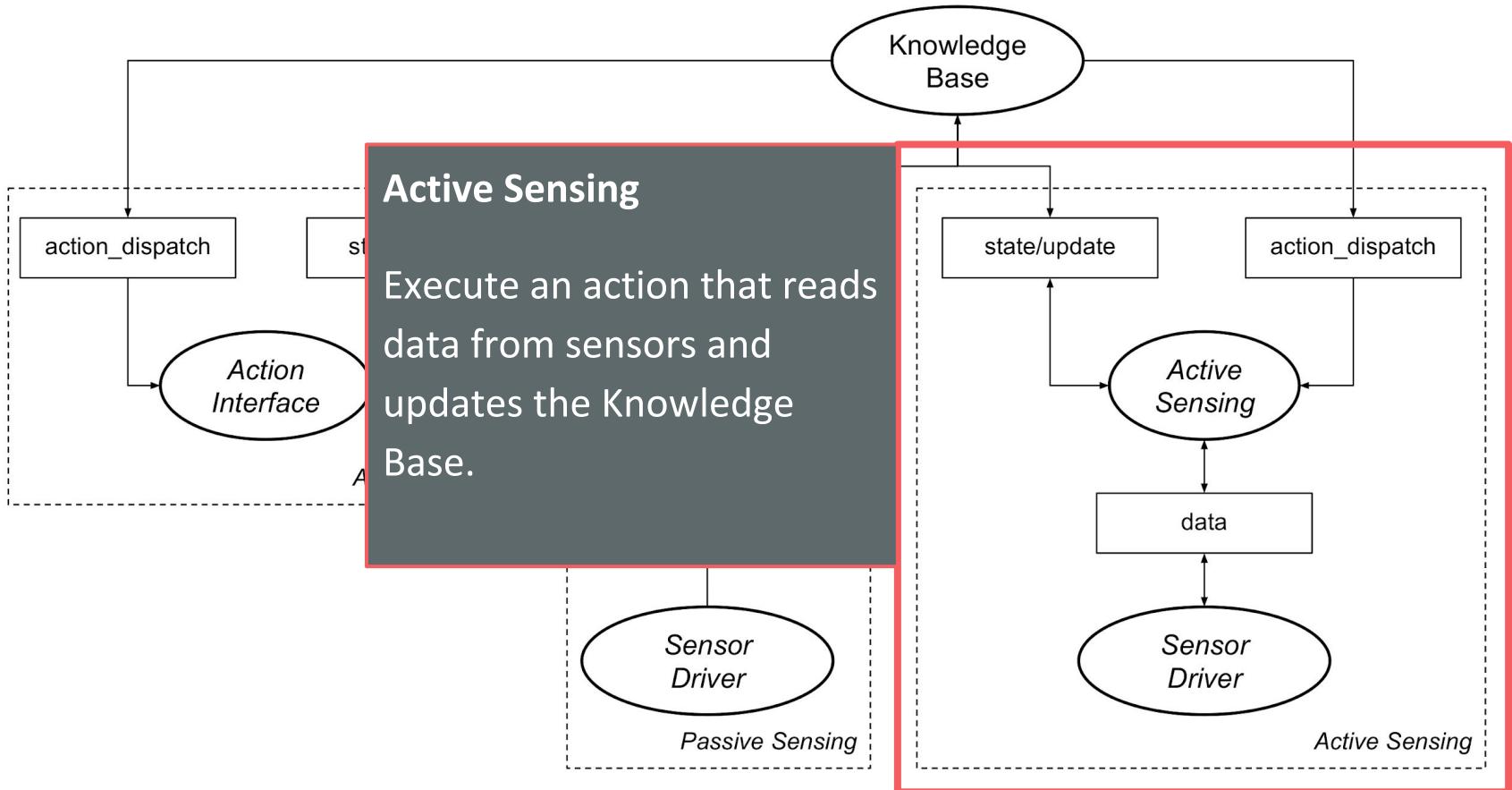
Updating the Knowledge Base



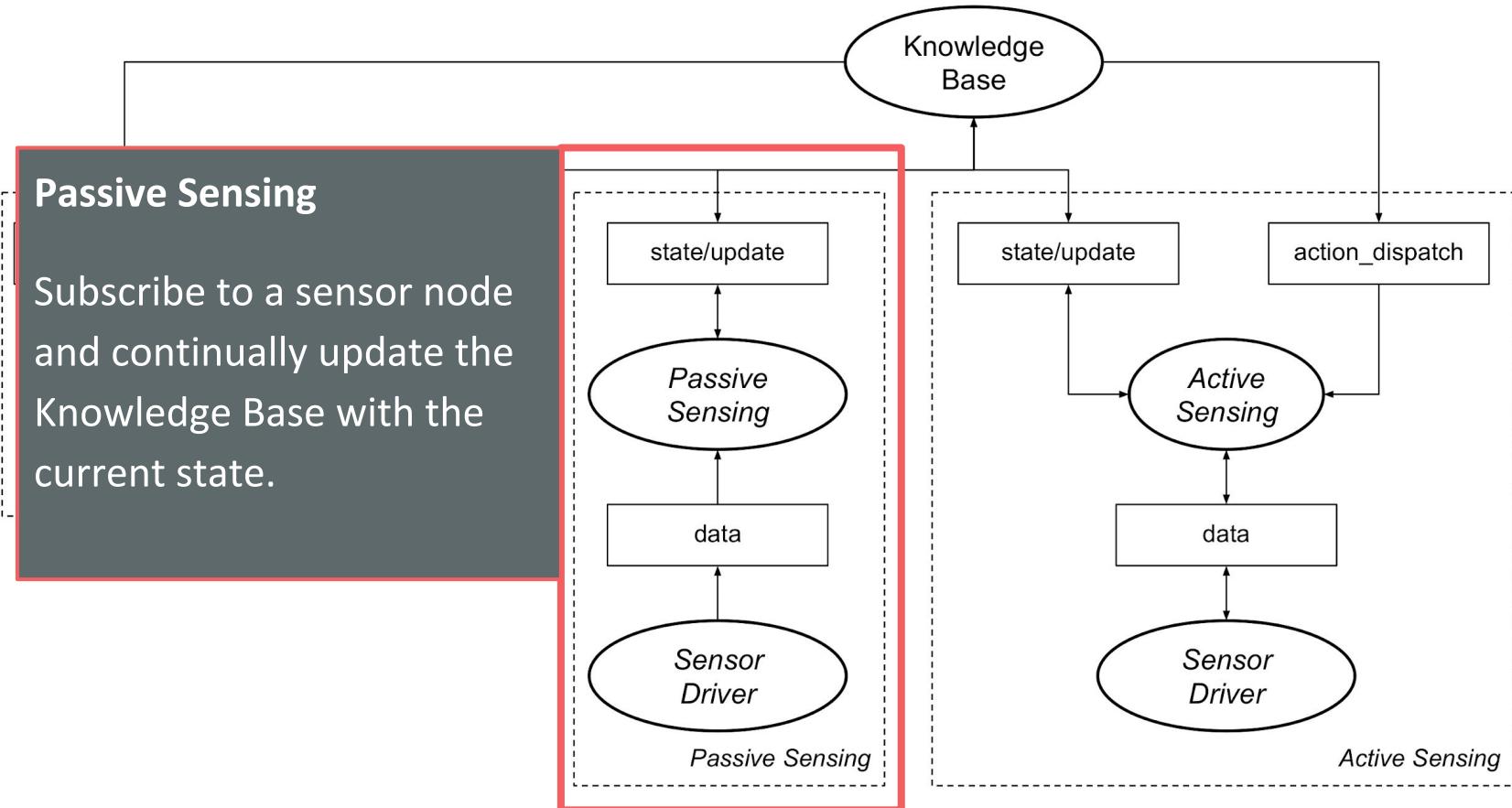
Updating the Knowledge Base



Updating the Knowledge Base



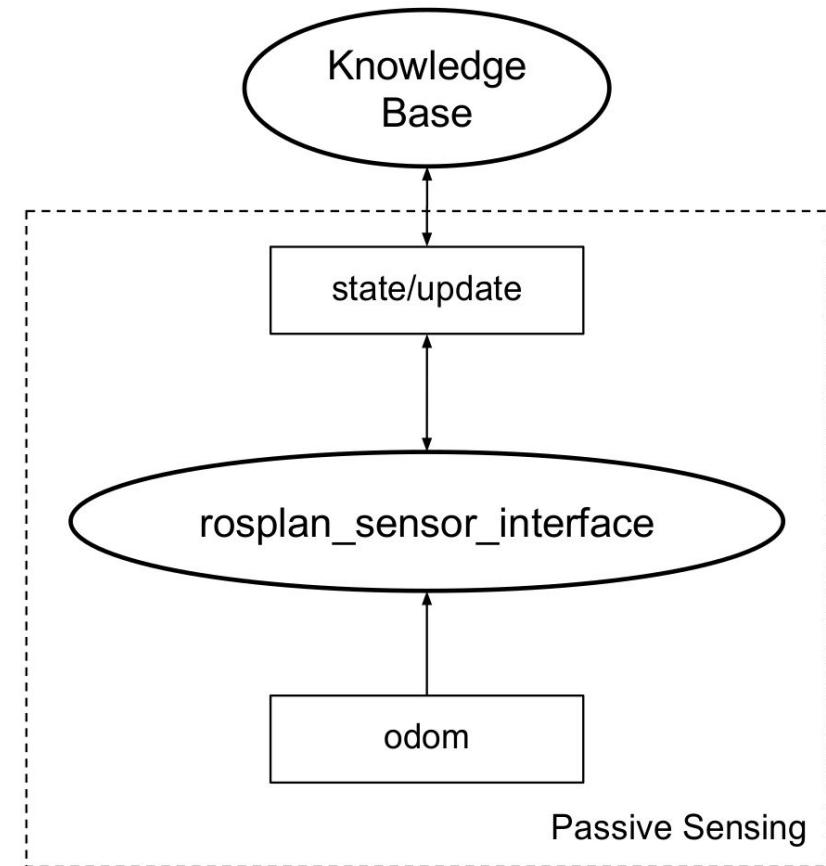
Updating the Knowledge Base



Updating the Knowledge Base

The sensor interface simplifies *passive sensing*.

- A single node.
- Connects topics and services to PDDL predicates.



```
<?xml version="1.0"?>
<launch>

<!-- arguments -->
<arg name="domain_path"      default="$(find rosplan_demos)/common/domain_turtlebot.pddl" />
<arg name="problem_path"     default="$(find rosplan_demos)/common/problem_turtlebot.pddl" />

<!-- knowledge base -->
<node name="rosplan_knowledge_base" pkg="rosplan_knowledge_base" type="knowledgeBase" respawn="false" output="screen">
    <param name="domain_path" value="$(arg domain_path)" />
    <param name="problem_path" value="$(arg problem_path)" />
    <!-- conditional planning flags -->
    <param name="use_unknowns" value="false" />
</node>

<arg name="main_rate"  default="10"/>

<node name="rosplan_sensing_interface" pkg="rosplan_sensing_interface" type="sensing_interface.py" respawn="false" output="screen">
    <rosparam command="load" file="$(find rosplan_sensing_interface)/icaps2019_tutorial.yaml" />
    <param name="main_rate"  value="10" />
</node>

</launch>
```

```
functions:
  - $(find rosplan_sensing_interface)/icaps2019_tutorial.py

topics:

localised:
  params:
    - kenny
  topic: /localised_mock
  msg_type: std_msgs/Bool
  operation: msg.data

docked:
  params:
    - kenny
  topic: /mobile_base/sensors/core
  msg_type: kobuki_msgs/SensorState
  operation: msg.charger != msg.DISCHARGING

undocked:
  params:
    - kenny
  topic: /mobile_base/sensors/core
  msg_type: kobuki_msgs/SensorState
  operation: msg.charger == msg.DISCHARGING

robot_at:
  params:
    - kenny
    - '*'
  topic: /amcl_pose
  msg_type: geometry_msgs/PoseWithCovarianceStamped
```

```
functions:
```

```
- $(find rosplan_sensing_interface)/icaps2019_tutorial.py
```

```
topics:
```

```
localised:
  params:
    - kenny
topic: /localised_mock
msg_type: std_msgs/Bool
operation: msg.data
```

```
docked:
```

```
  params:
    - kenny
topic: /mobile_base/sensors/core
msg_type: kobuki_msgs/SensorState
operation: msg.charger != msg.DISCHARGING
```

```
undocked:
```

```
  params:
    - kenny
topic: /mobile_base/sensors/core
msg_type: kobuki_msgs/SensorState
operation: msg.charger == msg.DISCHARGING
```

```
robot_at:
```

```
  params:
    - kenny
    - '*'
topic: /amcl_pose
msg_type: geometry_msgs/PoseWithCovarianceStamped
```

```
functions:
```

```
- $(find rosplan_sensing_interface)/icaps2019_tutorial.py
```

```
topics:
```

```
localised:
```

```
  params:
```

```
    - kenny
```

```
  topic: /localised_mock
```

```
  msg_type: std_msgs/Bool
```

```
  operation: msg.data
```

```
docked:
```

```
  params:
```

```
    - kenny
```

```
  topic: /mobile_base/sensors/core
```

```
  msg_type: kobuki_msgs/SensorState
```

```
  operation: msg.charger != msg.DISCHARGING
```

```
undocked:
```

```
  params:
```

```
    - kenny
```

```
  topic: /mobile_base/sensors/core
```

```
  msg_type: kobuki_msgs/SensorState
```

```
  operation: msg.charger == msg.DISCHARGING
```

```
robot_at:
```

```
  params:
```

```
    - kenny
```

```
    - '*'
```

```
  topic: /amcl_pose
```

```
  msg_type: geometry_msgs/PoseWithCovarianceStamped
```

```
functions:
  - $(find rosplan_sensing_interface)/icaps2019_tutorial.py

topics:

localised:
  params:
    - kenny
  topic: /localised_mock
  msg_type: std_msgs/Bool
  operation: msg.data

docked:
  params:
    - kenny
  topic: /mobile_base/sensors/core
  msg_type: kobuki_msgs/SensorState
  operation: msg.charger != msg.DISCHARGING

undocked:
  params:
    - kenny
  topic: /mobile_base/sensors/core
  msg_type: kobuki_msgs/SensorState
  operation: msg.charger == msg.DISCHARGING

robot_at:
  params:
    - kenny
    - '*'
  topic: /amcl_pose
  msg_type: geometry_msgs/PoseWithCovarianceStamped
```

```
#!/usr/bin/env python
from geometry_msgs.msg import PoseStamped
from math import sqrt

def robot_at(msg, params):

    assert(msg.header.frame_id == "map")
    assert(len(params) == 2)
    ret_value = []
    attributes = get_kb_attribute("robot_at")
    curr_wp = ''

    # Find current robot_location in knowledge base
    for a in attributes:
        if not a.is_negative:
            curr_wp = a.values[1].value
            break

    # for each robot parameter
    for robot in params[0]:

        # find closest waypoint
        distance = float('inf')
        closest_wp = ''
        for wp in params[1]:
            pose = rospy.get_param("/rosplan_demo_waypoints/"+wp)
            assert(len(pose) > 0)
            x = pose[0] - msg.pose.pose.position.x
            y = pose[1] - msg.pose.pose.position.y
            d = sqrt(x**2 + y**2)
            if d < distance:
                closest_wp = wp
                distance = d

        # set state in knowledge base
        if curr_wp != closest_wp:
            ret_value.append((robot + ':' + curr_wp, False)) # Set current waypoint to false
            ret_value.append((robot + ':' + closest_wp, True)) # Set new wp to true

    return ret_value
```

```
#!/usr/bin/env python
from geometry_msgs.msg import PoseStamped
from math import sqrt

def robot_at(msg, params):

    assert(msg.header.frame_id == "map")
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    curr_wp = ''

    # Find current robot_location in knowledge base
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        if not a.is_negative:
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            break

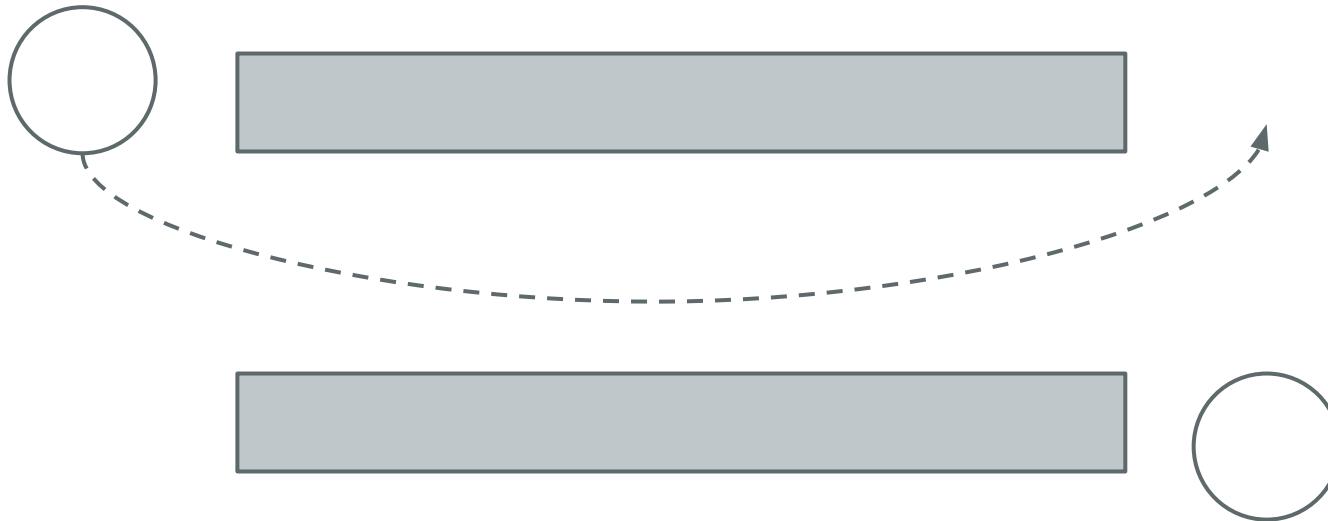
    # for each robot parameter
    for robot in params[0]:

        # find closest waypoint
        distance = float('inf')
        closest_wp = ''
        for wp in params[1]:
            pose = rospy.get_param("/rosplan_demo_waypoints/" + wp)
            assert(len(pose) > 0)
            x = pose[0] - msg.pose.pose.position.x
            y = pose[1] - msg.pose.pose.position.y
            d = sqrt(x**2 + y**2)
            if d < distance:
                closest_wp = wp
                distance = d

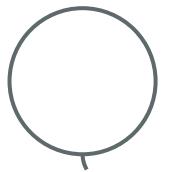
        # set state in knowledge base
        if curr_wp != closest_wp:
            ret_value.append((robot + ':' + curr_wp, False)) # Set current waypoint to false
            ret_value.append((robot + ':' + closest_wp, True)) # Set new wp to true

    return ret_value
```

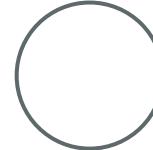
A Robot Plan



A Robot Plan

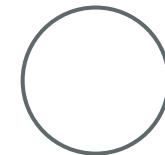
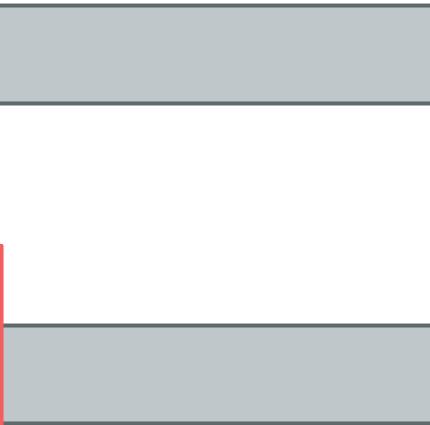


```
(:durative-action goto_waypoint
  :parameters (?r - robot ?from - waypoint)
  :duration (= ?duration (* (distance ?from ?to) 5))
  :condition (and
    (at start (at ?r ?from))
  )
  :effect (and
    (at start (not (at ?r ?from)))
    (at end (at ?r ?to))
  )
)
```



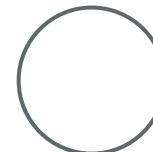
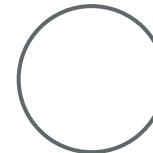
A Robot Plan

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  :parameters (?r - robot ?from - waypoint)
  :duration (= ?duration (* (distance ?from ?to) 5))
  :condition (and
    (at start (at ?r ?from))
  )
  :effect (and
    (at start (not (at ?r ?from)))
    (at end (at ?r ?to))
  )
)
```



A Robot Plan

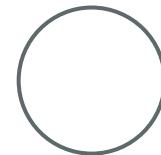
```
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    (at start (at ?r ?from))
  )
  :effect (and
    (at start (not (at ?r ?from)))
    (at end (at ?r ?to)))
  )
)
```



A Robot Plan

- Where was the robot during the action?
- When can the other robot move between the shelves?
- What is the state if the plan fails (for replanning)?

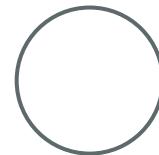
```
(:durative-action goto_waypoint
  :parameters (?r - robot ?from - waypoint)
  :duration (= ?duration (* (distance ?from ?to) 5))
  :condition (and
    (at start (at ?r ?from)))
  )
  :effect (and
    (at start (not (at ?r ?from)))
    (at end (at ?r ?to)))
  )
)
```



A Robot Plan

- Where was the robot during the action?
- When can the other robot move between the shelves?
- What is the state if the plan fails (for replanning)?

```
(:durative-action goto_waypoint
  :parameters (?r - robot ?from - waypoint)
  :duration (= ?duration (* (distance ?from ?to) 5))
  :condition (and
    (at start (at ?r ?from))
  )
  :effect (and
    (at start (not (at ?r ?from)))
    (at end (at ?r ?to))
  )
)
```



Example in Simulation

Part 3: Strategic-Tactical (The Problem)

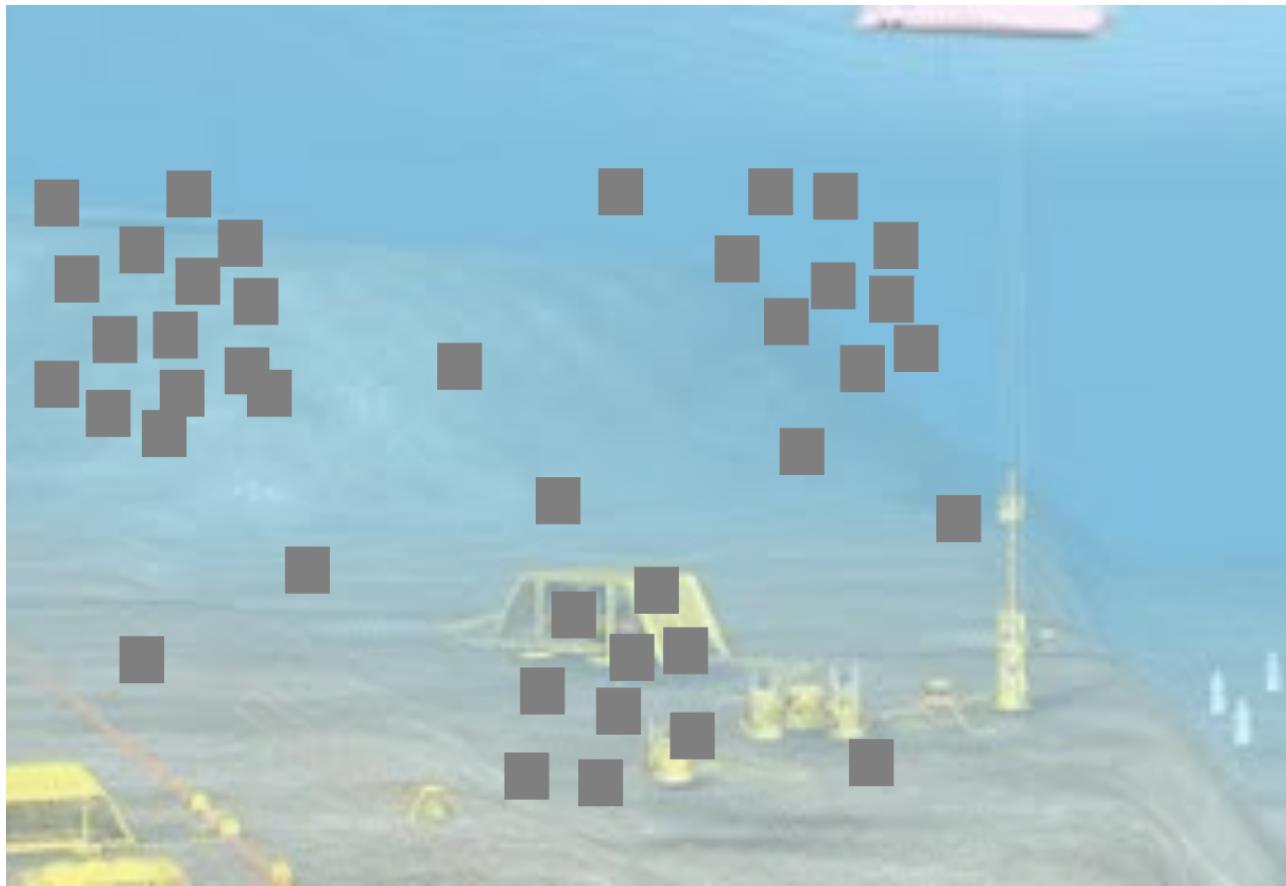
Strategic-Tactical Decomposition

Our approach is based on hierarchical abstraction.

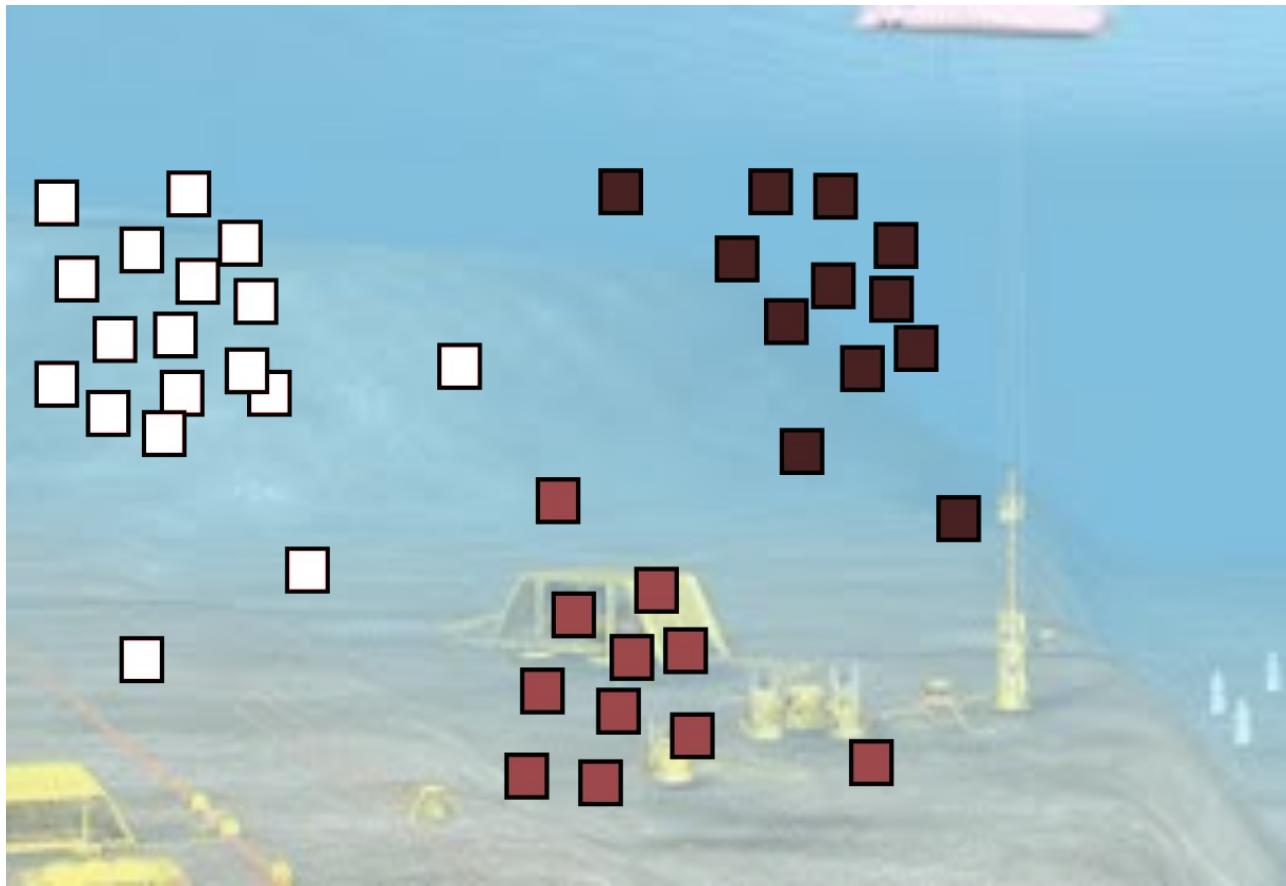
A plan is generated using the following steps:

1. **Automatically decompose a large problem into a set of smaller problems (subgoals).**
2. Generate a tactical plan for each subgoal.
3. Construct a strategic problem, containing strategic actions.
4. Generate a strategic plan for the whole mission.

Strategic-Tactical Decomposition



Strategic-Tactical Decomposition



Strategic-Tactical Decomposition

Our approach is based on hierarchical abstraction.

A plan is generated using the following steps:

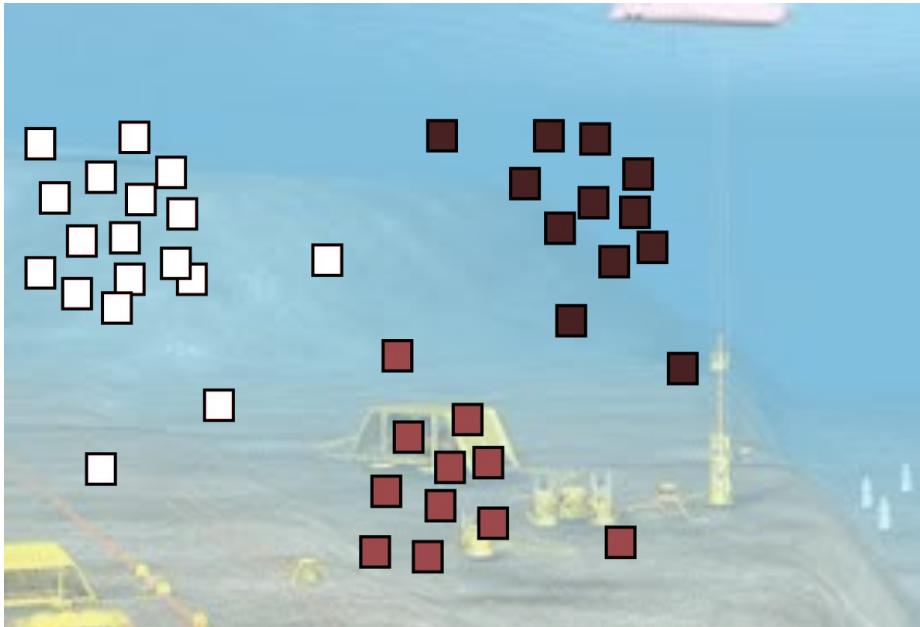
1. Automatically decompose a large problem into a set of smaller problems (subgoals).
2. **Generate a tactical plan for each subgoal.**
3. Construct a strategic problem, containing strategic actions.
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Tactical Planning

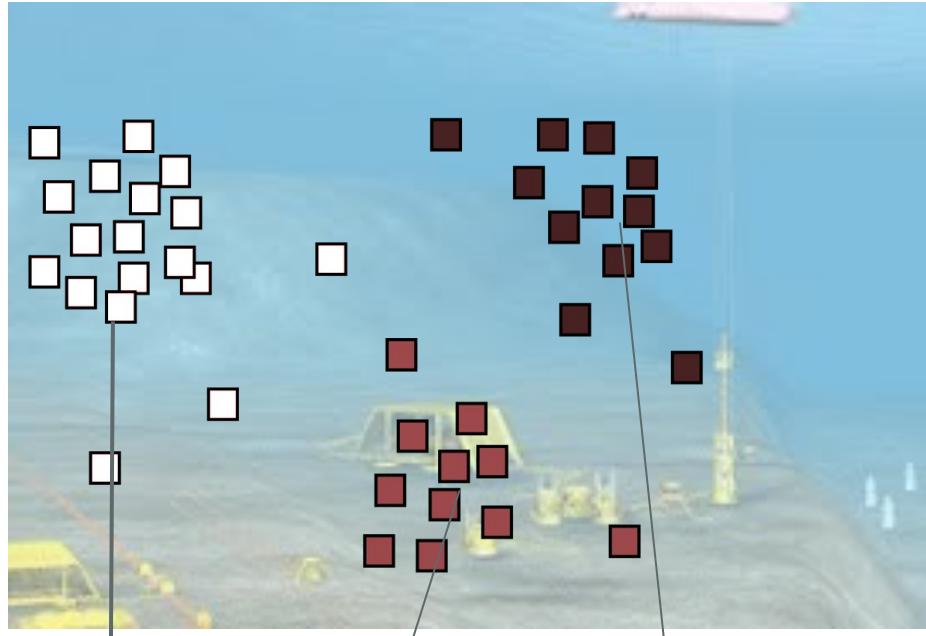
A tactical plan is generated for each subgoal.

- The temporal constraints are ignored.
- The planner is given a maximum of 10 seconds to plan.
- The plans are not executed.
- The duration and energy cost of the tactical plan is saved.

Tactical Planning



Tactical Planning

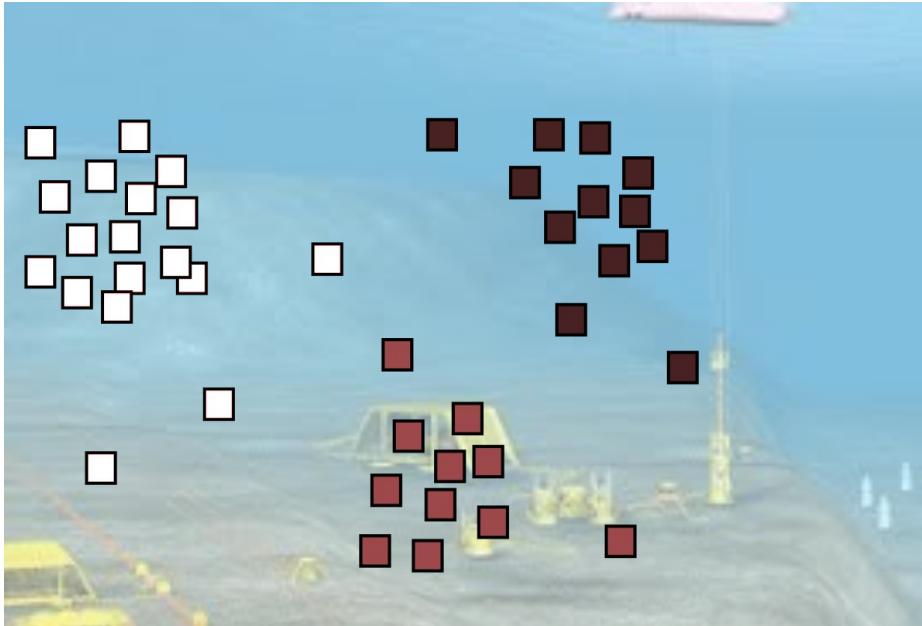


Tactical Plan

Tactical Plan

Tactical Plan

Tactical Planning



Tactical Plan

0

949.001

Tactical Plan

33.371: (do_hover_controlled auv wp1 wp2) [14.340] ; (41)
47.712: (do_hover_controlled auv wp2 wp23) [3.342] ; (58)
51.055: (observe_inspection_point auv wp23 ip1) [10.000] ; (296)
61.056: (correct_position auv wp23) [3.000] ; (271)
64.057: (observe_inspection_point auv wp23 ip4) [10.000] ; (315)
74.058: (correct_position auv wp23) [3.000] ; (271)
77.059: (observe_inspection_point auv wp23 ip5) [10.000] ; (322)
87.060: (correct_position auv wp23) [3.000] ; (271)
90.061: (do_hover_controlled auv wp23 wp17) [4.282] ; (33)
94.344: (observe_inspection_point auv wp17 ip3) [10.000] ; (308)
104.345: (correct_position auv wp17) [3.000] ; (264)
107.346: (do_hover_controlled auv wp17 wp27) [4.720] ; (67)
112.067: (observe_inspection_point auv wp27 ip2) [10.000] ; (305)
122.068: (correct_position auv wp27) [3.000] ; (275)
125.069: (observe_inspection_point auv wp27 ip6) [10.000] ; (329)
135.070: (correct_position auv wp27) [3.000] ; (275)
138.071: (observe_inspection_point auv wp27 ip8) [10.000] ; (341)
148.072: (correct_position auv wp27) [3.000] ; (275)
151.073: (do_hover_controlled auv wp27 wp17) [4.720] ; (34)
155.794: (do_hover_controlled auv wp17 wp6) [1.276] ; (115)
157.071: (observe_inspection_point auv wp6 ip7) [10.000] ; (336)
167.072: (correct_position auv wp6) [3.000] ; (291)
170.073: (do_hover_controlled auv wp6 wp2) [6.040] ; (44)
176.114: (do_hover_controlled auv wp2 wp36) [4.290] ; (95)
180.405: (observe_inspection_point auv wp36 ip9) [10.000] ; (348)
190.406: (correct_position auv wp36) [3.000] ; (285)
193.407: (do_hover_controlled auv wp36 wp2) [4.290] ; (43)
197.698: (do_hover_controlled auv wp2 wp1) [14.340] ; (2)
212.039: (observe_inspection_point auv wp1 ip3) [10.000] ; (307)
222.040: (correct_position auv wp1) [3.000] ; (256)
225.041: (do_hover_controlled auv wp1 wp16) [3.854] ; (27)
228.896: (observe_inspection_point auv wp16 ip2) [10.000] ; (302)
238.897: (correct_position auv wp16) [3.000] ; (263)
241.898: (do_hover_controlled auv wp16 wp21) [1.540] ; (47)
243.439: (observe_inspection_point auv wp21 ip2) [10.000] ; (304)
253.440: (correct_position auv wp21) [3.000] ; (269)
256.441: (observe_inspection_point auv wp21 ip3) [10.000] ; (310)
266.442: (correct_position auv wp21) [3.000] ; (269)
269.443: (do_hover_controlled auv wp21 wp27) [4.252] ; (68)
273.696: (do_hover_controlled auv wp27 wp12) [4.506] ; (14)
278.203: (observe_inspection_point auv wp12 ip2) [10.000] ; (301)
288.204: (correct_position auv wp12) [3.000] ; (259)
291.205: (do_hover_controlled auv wp12 wp27) [4.506] ; (66)
599.001: (turn_valve auv wp27 p1 v1) [120.000] ; (350)

Strategic-Tactical Decomposition

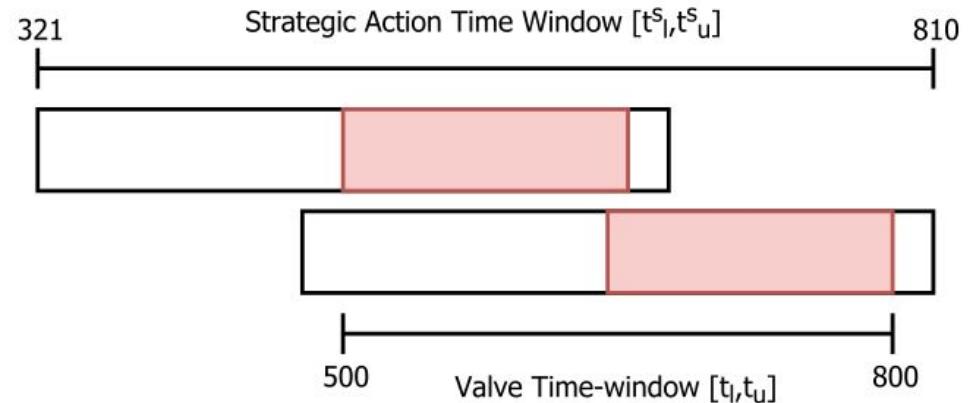
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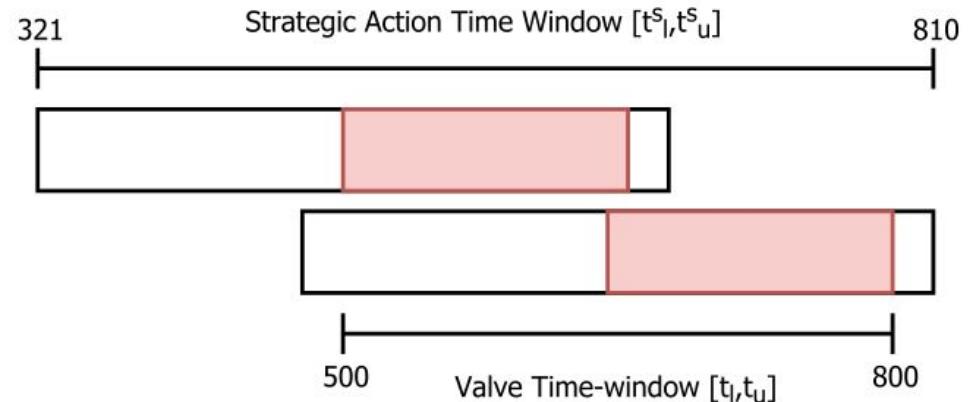
Strategic Problem Compilation

Upper and lower bounds are extracted from tactical plans to impose temporal constraints in the strategic problem.

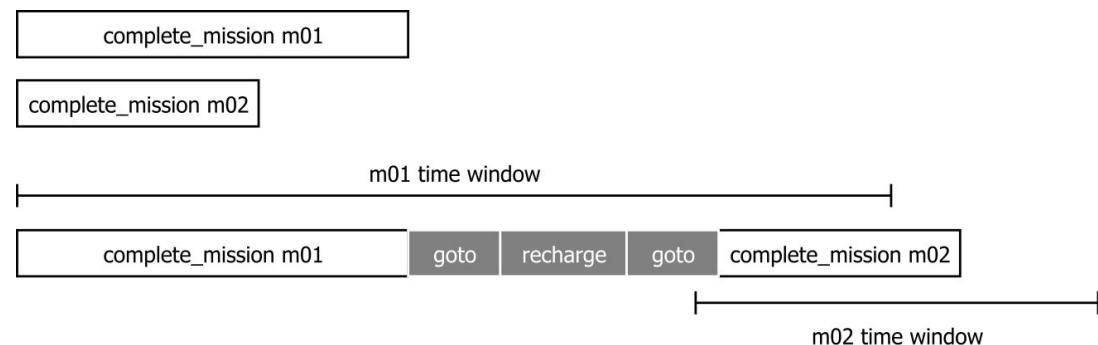


Strategic Problem Compilation

Upper and lower bounds are extracted from tactical plans to impose temporal constraints in the strategic problem.



The strategic plan schedules the subgoals within new constraints.



Strategic Problem Compilation

| | |
|--|---|
| (active mission0) | (= (mission_duration mission0) 261.867) |
| (active mission1) | (= (mission_duration mission1) 242.066) |
| (active mission2) | (= (mission_duration mission2) 336.17) |
| (active mission3) | (= (mission_duration mission3) 365.49) |
| (active mission4) | (= (mission_duration mission4) 340.969) |
| (active mission5) | (= (mission_duration mission5) 337.334) |
| (active mission6) | (= (mission_duration mission6) 608.425) |
| (active mission7) | (= (mission_duration mission7) 800.794) |
| (active mission8) | (= (mission_duration mission8) 692.803) |
| (active mission9) | (= (mission_duration mission9) 629.094) |
| | |
| (in mission0 mission_site_start_point_1) | (at 4100 (not (active mission0))) |
| (in mission1 mission_site_start_point_1) | (at 7100 (not (active mission1))) |
| (in mission2 mission_site_start_point_1) | (at 99999 (not (active mission10))) |
| (in mission3 mission_site_start_point_1) | |
| (in mission4 mission_site_start_point_1) | |
| (in mission5 mission_site_start_point_1) | |
| (in mission6 mission_site_start_point_1) | |
| (in mission7 mission_site_start_point_1) | |
| (in mission8 mission_site_start_point_1) | |
| (in mission9 mission_site_start_point_1) | |

Strategic-Tactical Decomposition

Our approach is based on hierarchical abstraction.

A plan is generated using the following steps:

1. Automatically decompose a large problem into a set of smaller problems (subgoals).
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4. **Generate a strategic plan for the whole mission.**

Strategic Plan Execution

0.000: (do_hover auv wp_auv0 mission_site_start_point_1) [112.805]
112.806: (complete_mission auv mission2 mission_site_start_point_1) [336.170]
448.977: (complete_mission auv mission1 mission_site_start_point_1) [242.065]
691.043: (do_hover auv mission_site_start_point_1 mission_site_start_point_0) [269.444]
960.488: (dock_auv auv mission_site_start_point_0) [20.000]
980.488: (recharge auv mission_site_start_point_0) [1800.000]
2780.489: (undock_auv auv mission_site_start_point_0) [10.000]
2790.489: (do_hover auv mission_site_start_point_0 mission_site_start_point_1) [269.444]
3059.934: (complete_mission auv mission5 mission_site_start_point_1) [337.334]
3397.269: (complete_mission auv mission0 mission_site_start_point_1) [261.867]
3659.137: (complete_mission auv mission7 mission_site_start_point_1) [337.334]

Strategic Plan Execution

0.000: (do_hover auv wp_auv0 mission_site_start_point_1) [112.805]

112.806: (complete_mission auv mission2 mission_site_start_point_1) [336.170]

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691.043: (do_hover auv mission_site_start_point_1 mission_site_start_point_0) [269.444]

960.488: (dock_auv auv mission_site_start_point_0) [20.000]

980.488: (recharge auv mission_site_start_point_0) [1800.000]

2780.489: (undock_auv auv mission_site_start_point_0) [10.000]

2790.489: (do_hover auv mission_site_start_point_0 mission_site_start_point_1) [269.444]

3059.934: (complete_mission auv mission5 mission_site_start_point_1) [337.334]

3397.269: (complete_mission auv mission0 mission_site_start_point_1) [261.867]

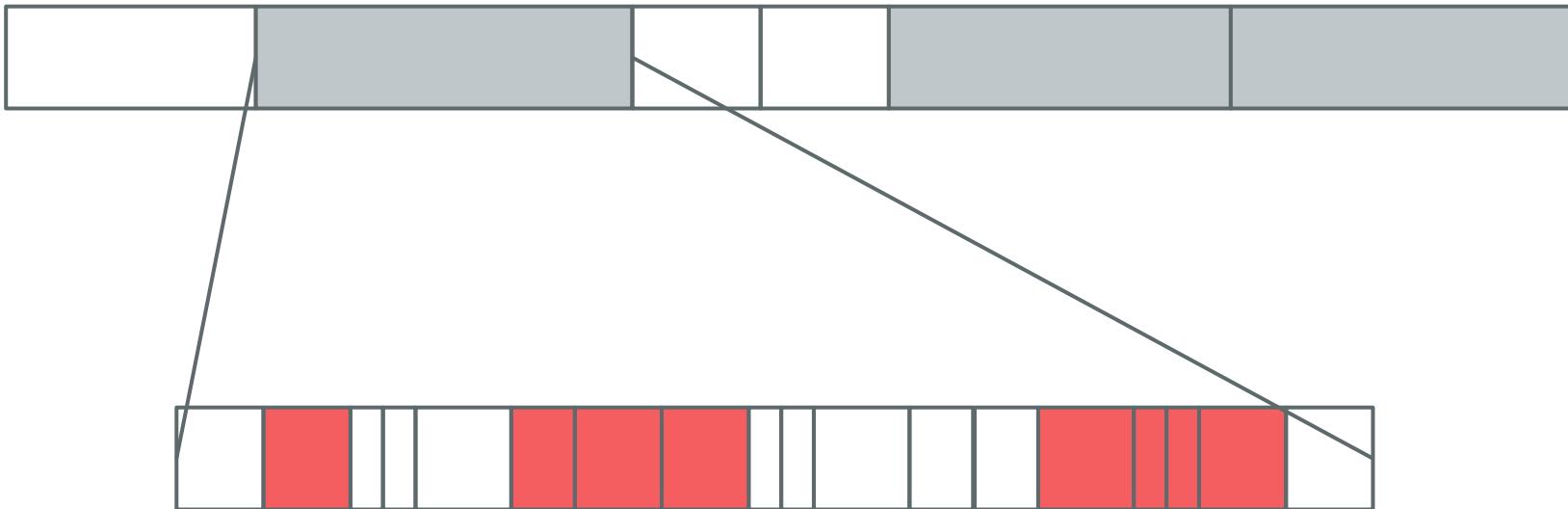
3659.137: (complete_mission auv mission7 mission_site_start_point_1) [337.334]

When the *complete_mission* action is dispatched, the tactical plan is executed.

Strategic Plan Execution



Strategic Plan Execution



Strategic Plan Execution

When the *complete_mission* action is dispatched, the tactical plan is executed.

The plans are executed:

1. The tactical problem is regenerated, including the temporal constraints.

Strategic Plan Execution

When the *complete_mission* action is dispatched, the tactical plan is executed.

The plans are executed:

1. The tactical problem is regenerated, including the temporal constraints.
2. A new tactical plan is generated.

Strategic Plan Execution

When the *complete_mission* action is dispatched, the tactical plan is executed.

The plans are executed:

1. The tactical problem is regenerated, including the temporal constraints.
2. A new tactical plan is generated.
3. If the tactical plan fails, then it is replanned.

Strategic Plan Execution

When the *complete_mission* action is dispatched, the tactical plan is executed.

The plans are executed:

1. The tactical problem is regenerated, including the temporal constraints.
2. A new tactical plan is generated.
3. If the tactical plan fails, then it is replanned.
4. The strategic plan execution monitors the execution of a tactical plan as any other action. The tactical plan can fail (action failure) or be cancelled (timeout).

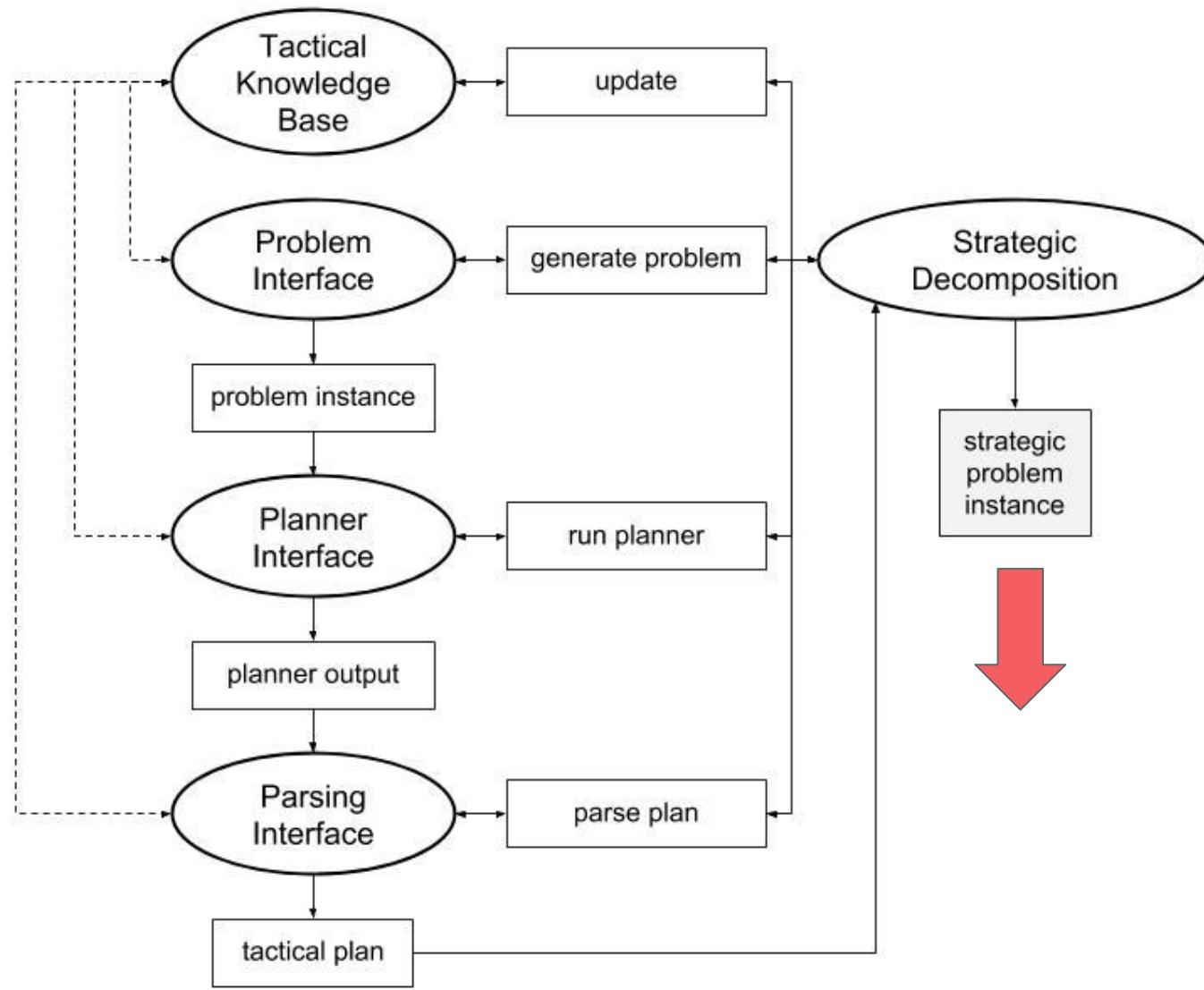
Strategic Plan Execution

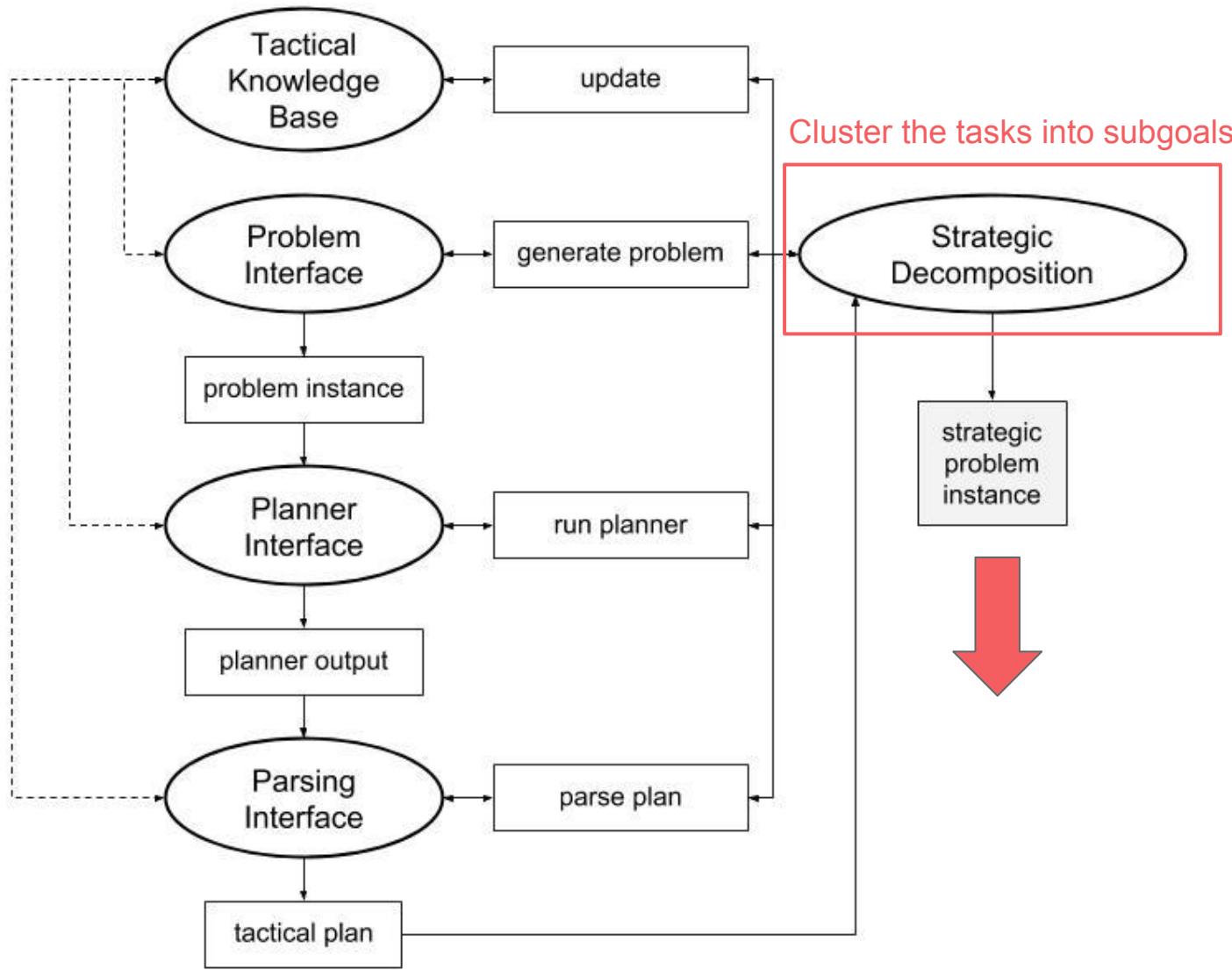
When the *complete_mission* action is dispatched, the tactical plan is executed.

The plans are executed:

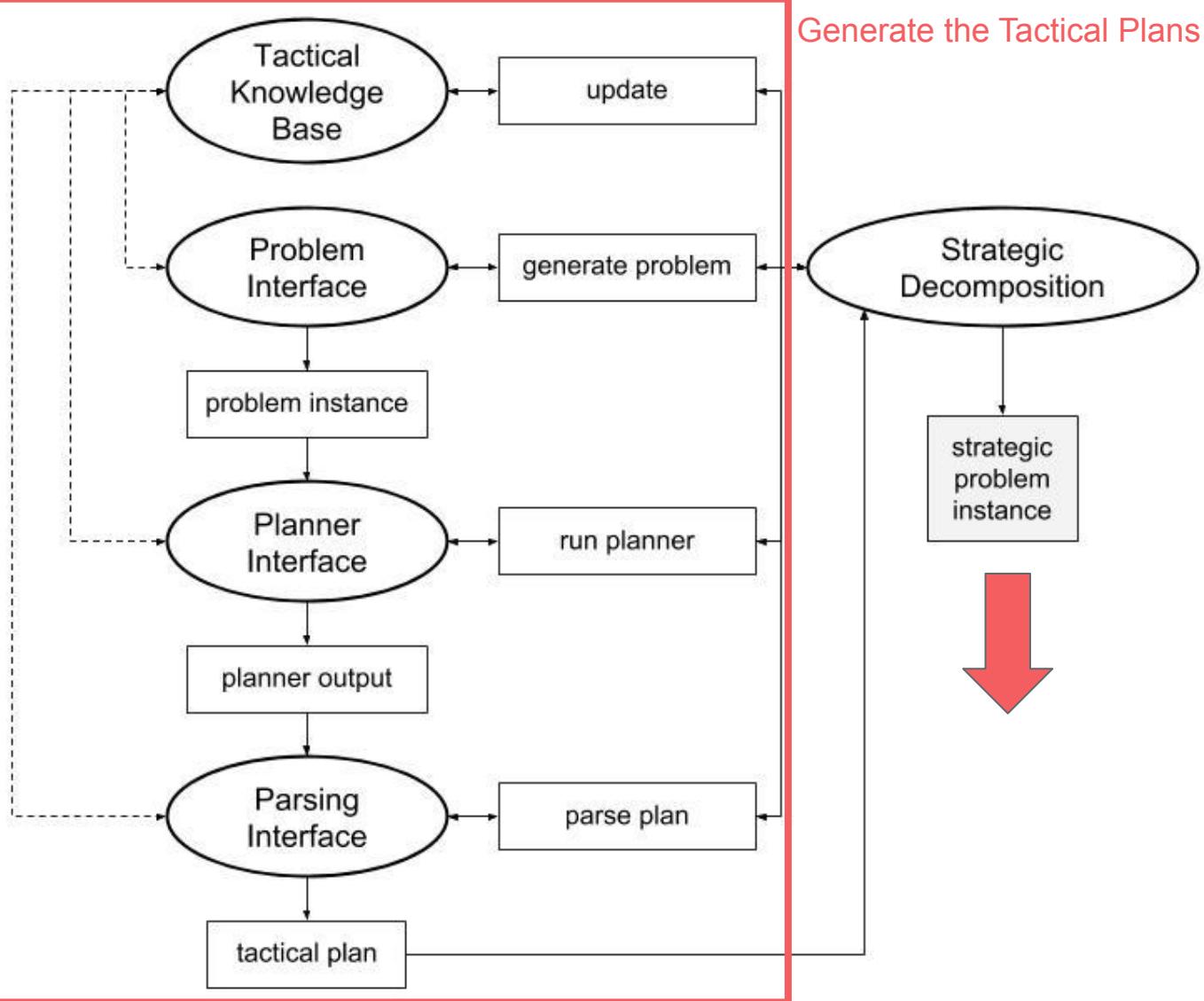
1. The tactical problem is regenerated, including the temporal constraints.
2. A new tactical plan is generated.
3. If the tactical plan fails, then it is replanned.
4. The strategic plan execution monitors the execution of a tactical plan as any other action. The tactical plan can fail (action failure) or be cancelled (timeout).
5. If the strategic plan fails, then replanning takes place at the strategic layer (without replanning the tactical problems).

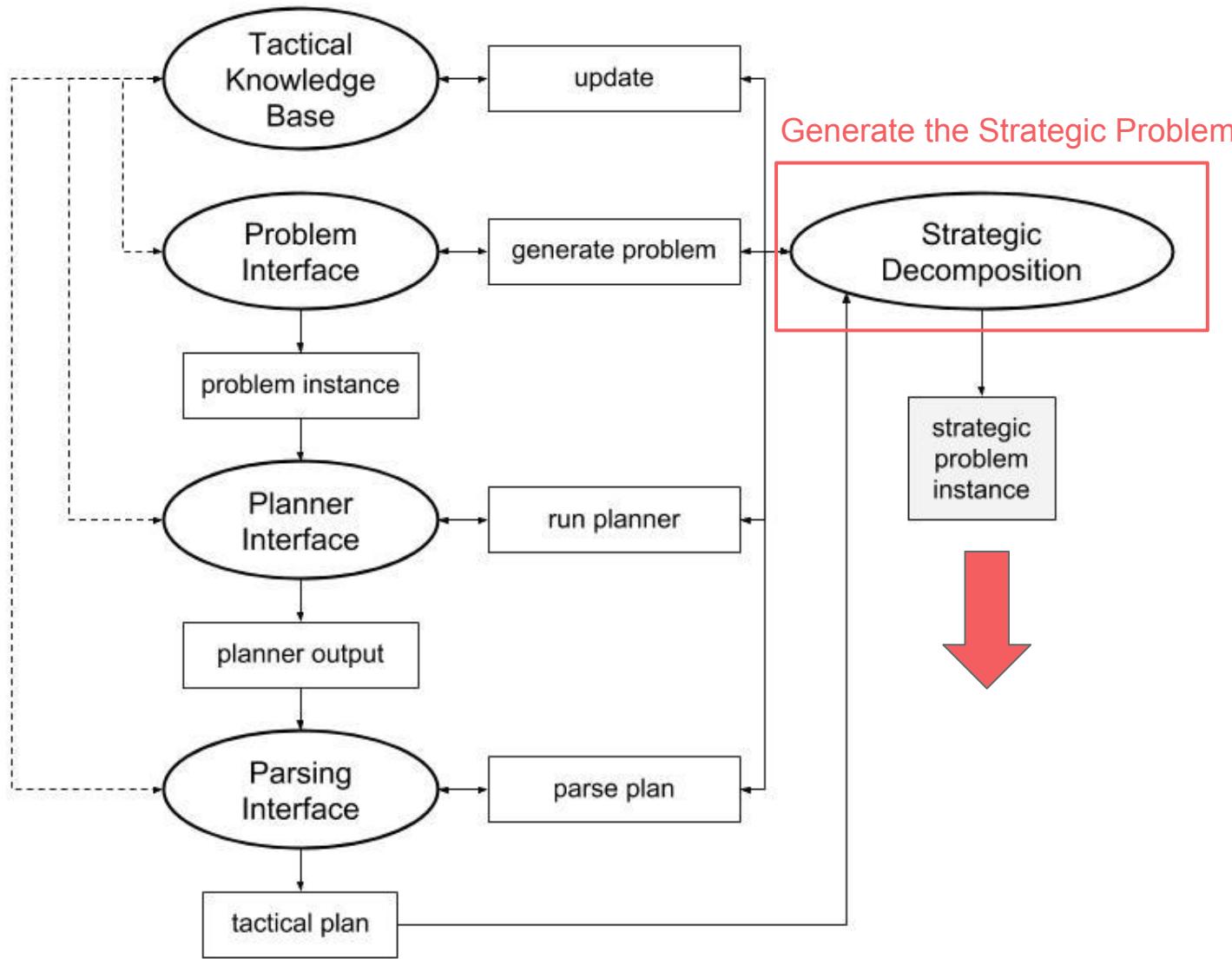
Part 4: Strategic-Tactical (ROSPlan setup)



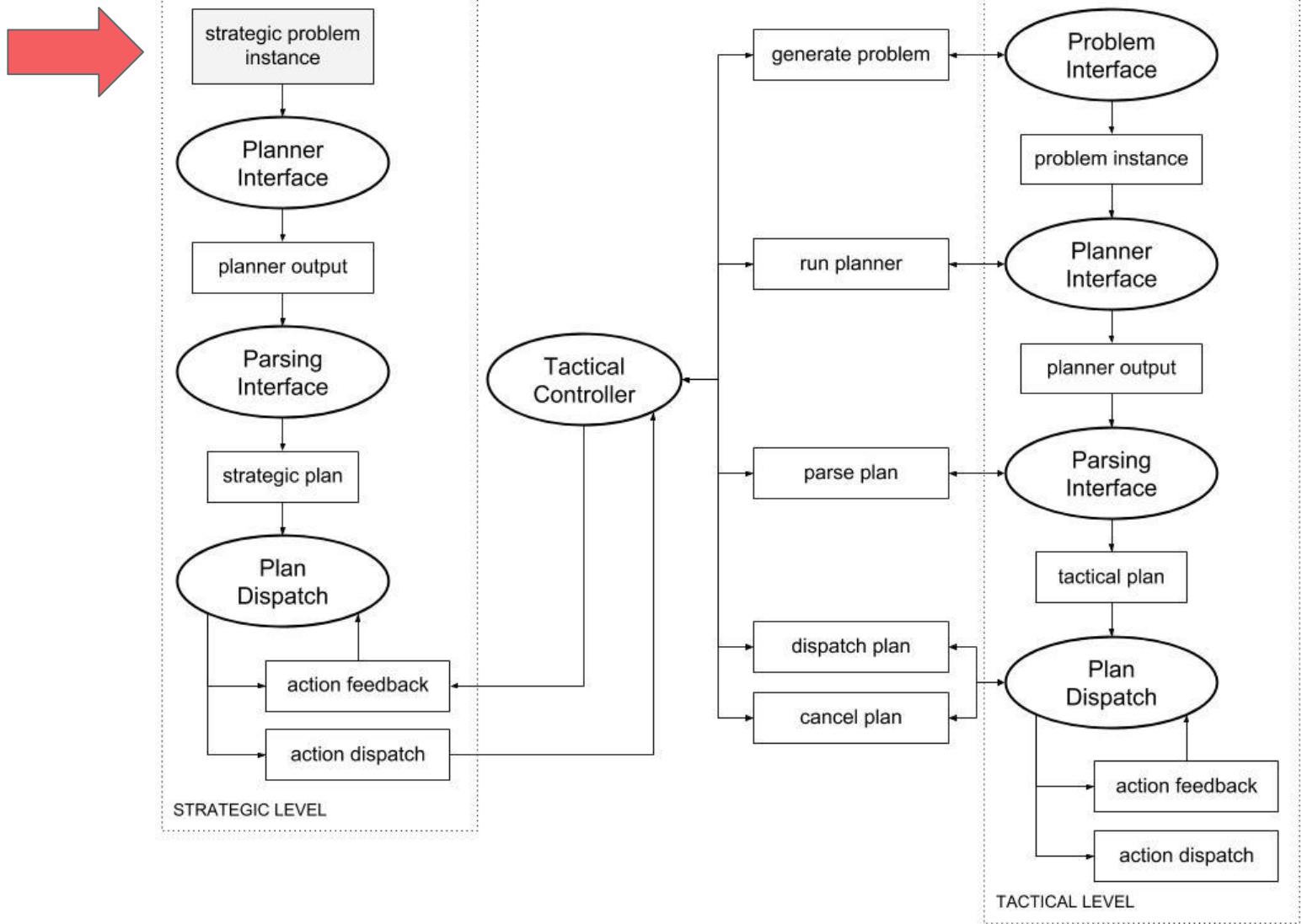


Cluster the tasks into subgoals

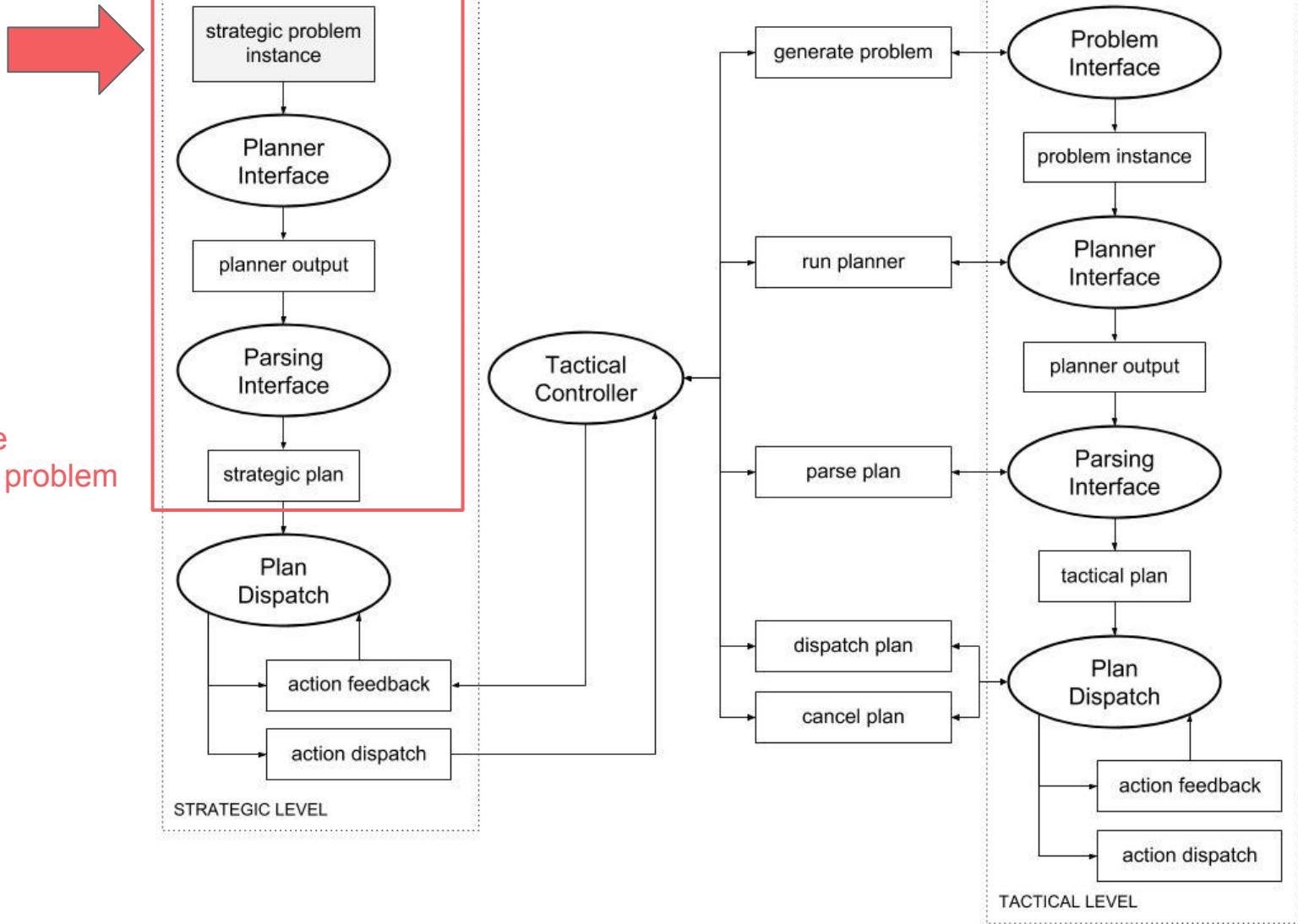




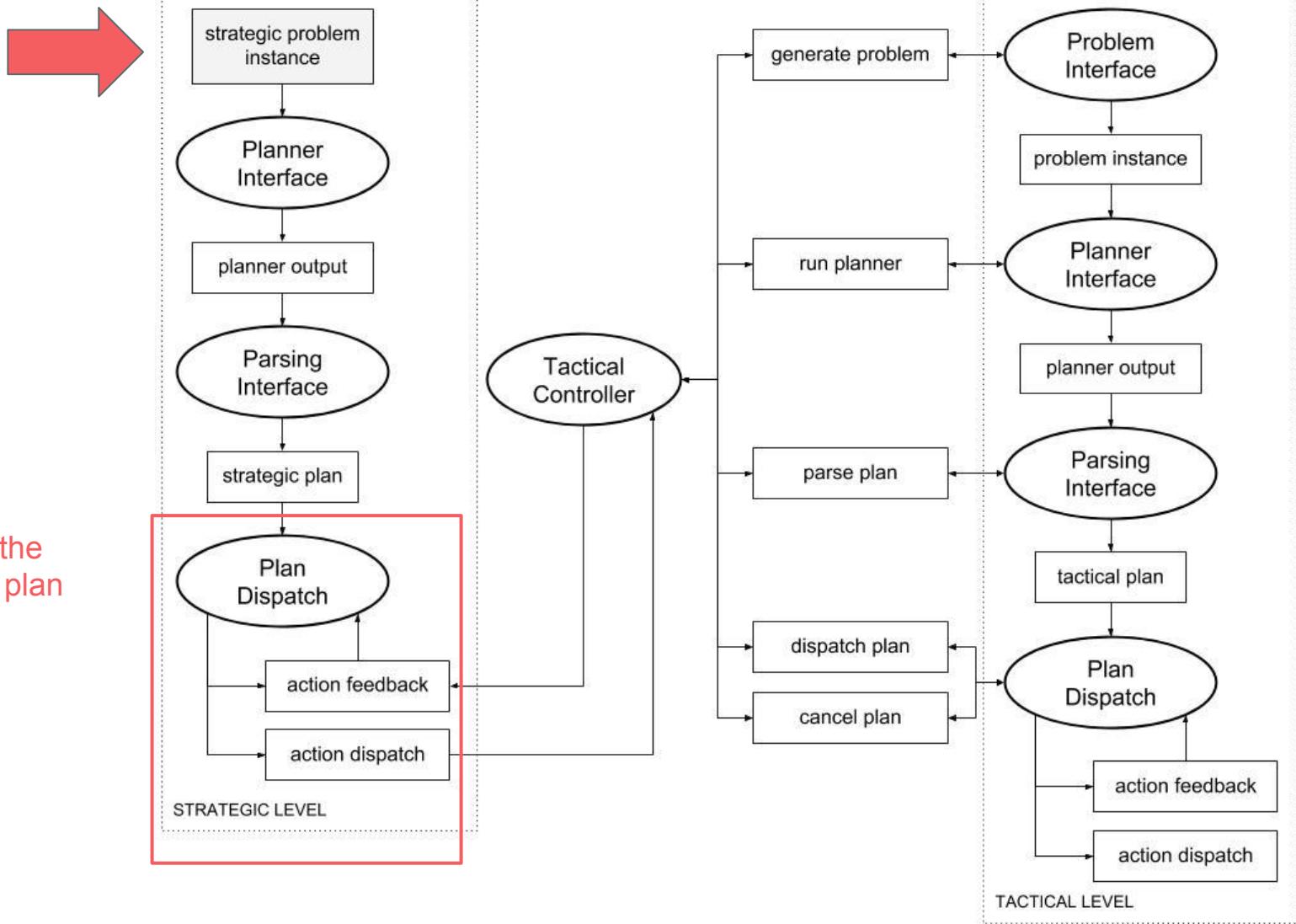
Generate the Strategic Problem

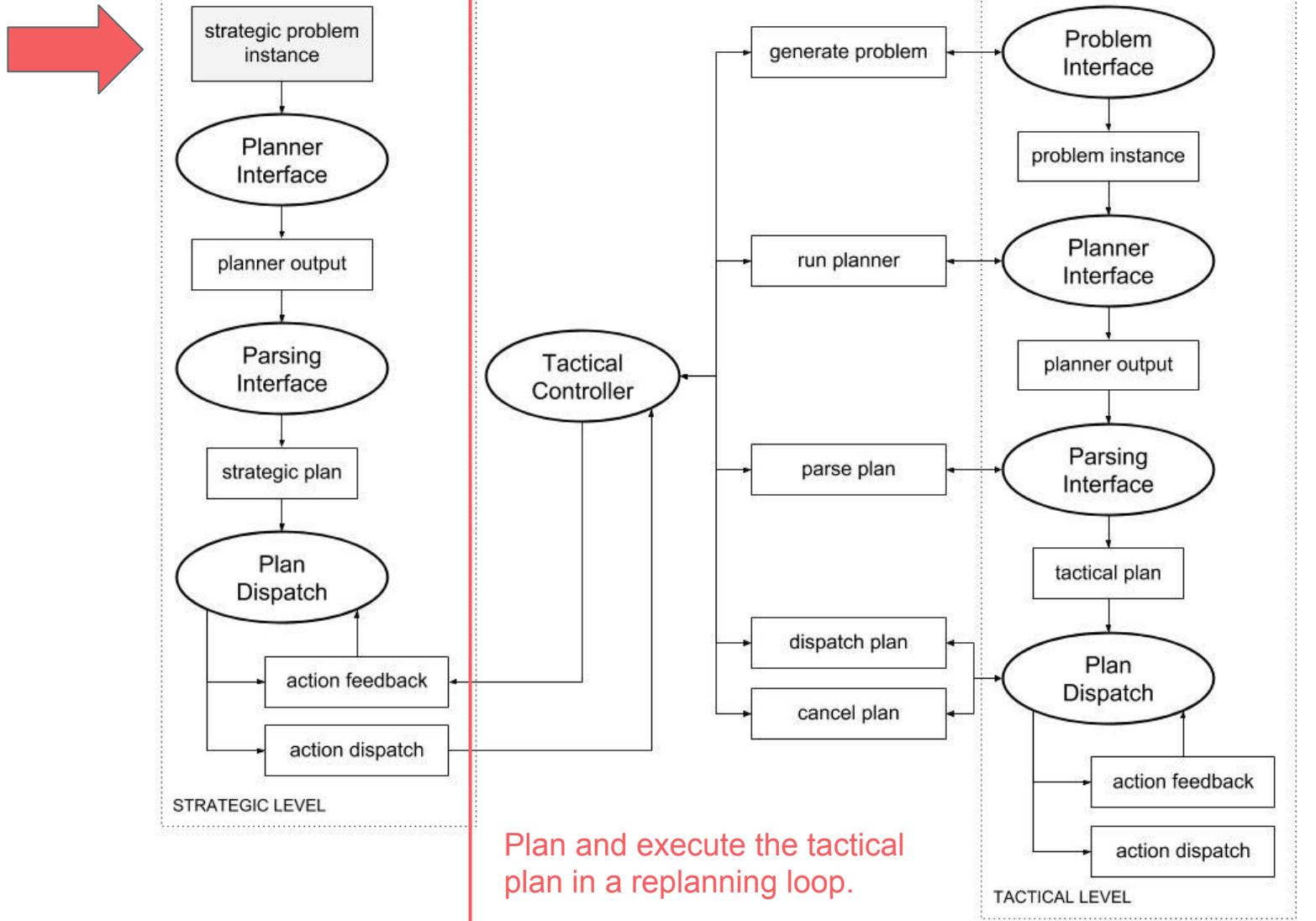


Solve the strategic problem



Execute the strategic plan





Part 5: Probabilistic Planning

Probabilistic Planning

The robot is given the task to navigate through a busy office to deliver papers from the printer.

- The printer is often busy.
- The robot relies on nearby humans to load the printed papers.



What is RDDL?

Relational Dynamic Influence Diagram Language

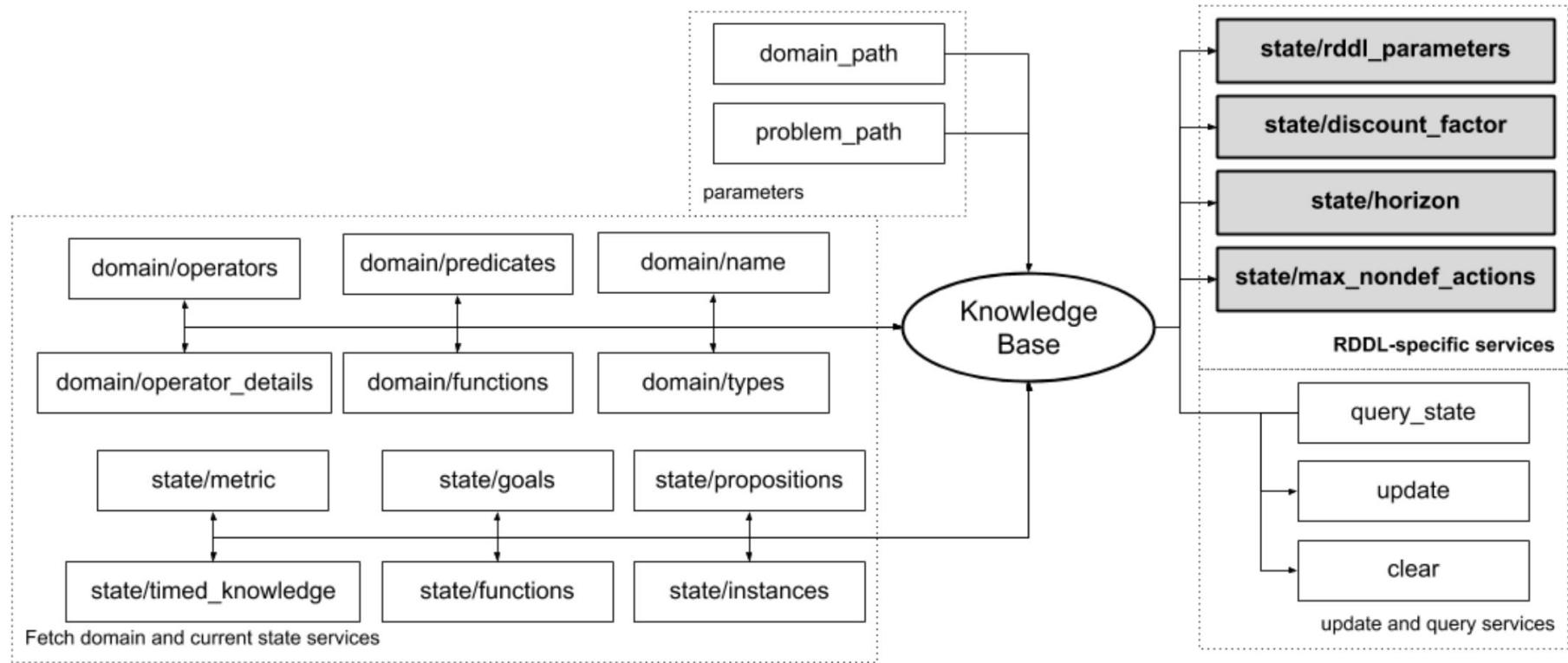
A language for probabilistic planning based on a Dynamic Bayes Net.

Allows domains with:

- Nondeterministic action outcome.
- Domains with partial observation.
- Unrestricted concurrency.

[Sanner 2010]

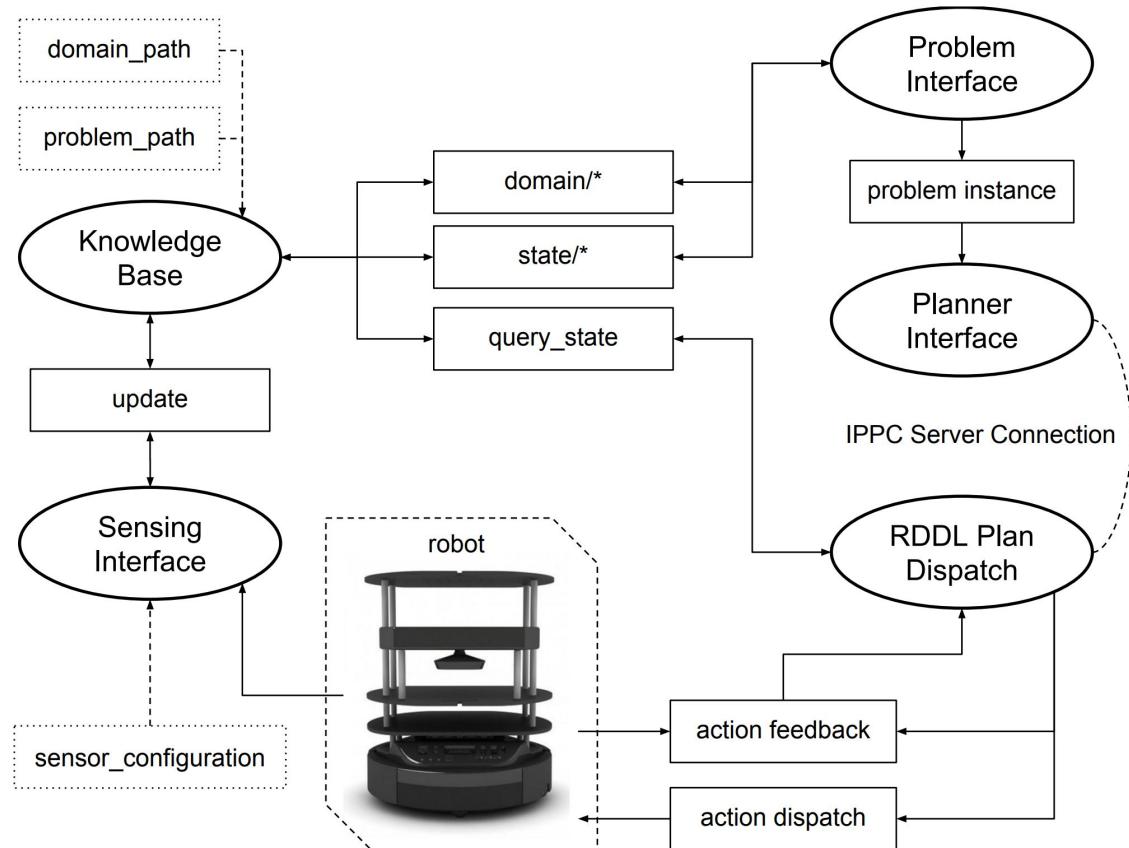
RDDL



System Architecture

The default *planner interface*, *plan parser*, and *plan dispatcher* are replaced by a single custom component.

The new node performs *online planning* using the IPPC server connection.



System Architecture

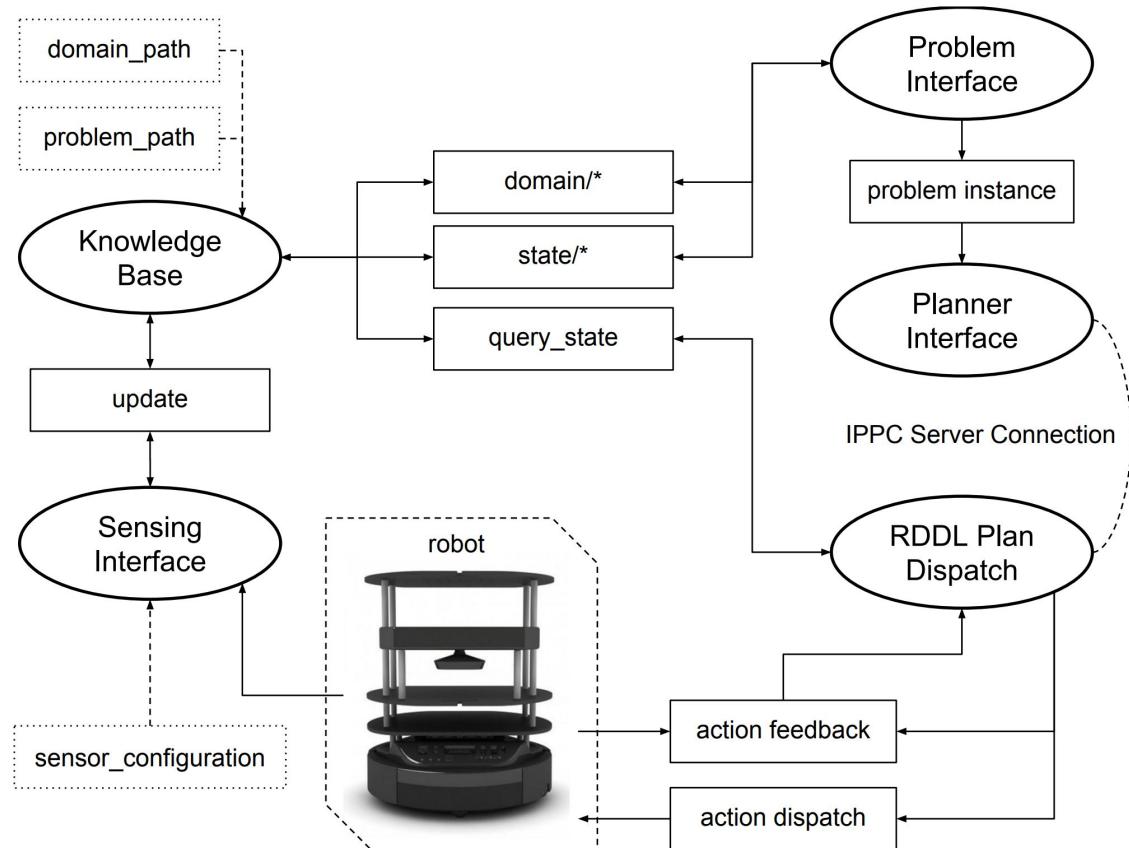
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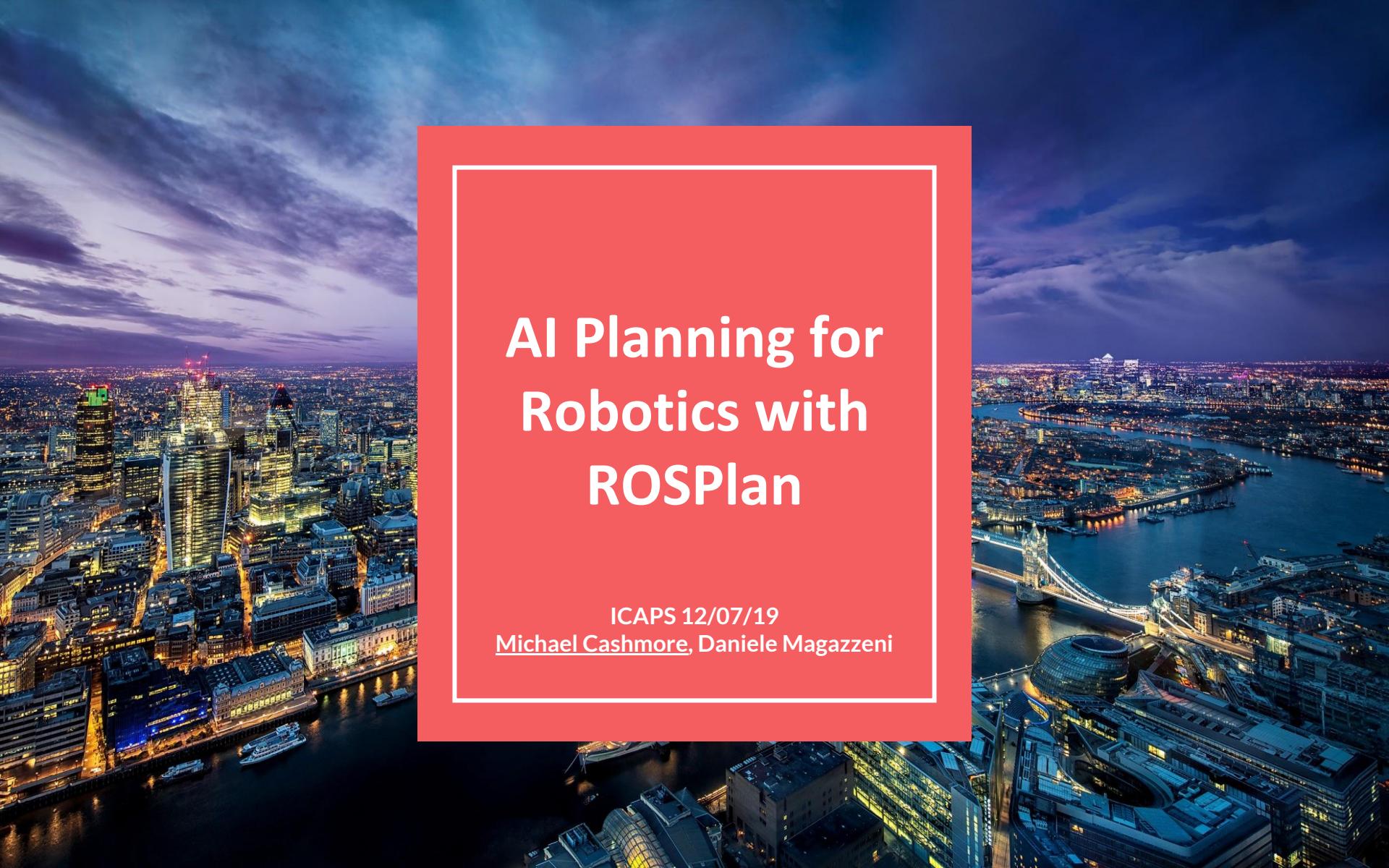
The new node performs *online planning* using the IPPC server connection.

The planners PROST and GLUTTON perform planning interleaved with execution.

[Keller and Eyerich 2012]

[Kolobov et al. 2012]





AI Planning for Robotics with ROSPlan

ICAPS 12/07/19
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