NewPlan例子计算过程

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**demo\_p.pddl，包含初始Knowledge Base(下面简称KB)，和goal（即推理目标，下面称goal）**：

(define (problem demo)

(:domain demo)

(:init (and

(K (and (imply (doorOpen) (inRoom))

(imply (not (lightOn)) (not(inRoom)))

)

)

(DK (inRoom))

(DK (not (inRoom)))

(DK (lightOn))

(DK (not (lightOn)))

)

)

(:goal (or

(K (inRoom))

(K (not (inRoom)))

)

)

)

**demo\_domain.pddl，**定义感知(sense)动作和物理(knock)动作：

(define (domain demo)

(:action senseL

:parameters ()

:precondition (and (DK (lightOn)) (DK (not (lightOn))))

:observe (lightOn)

)

(:action senseD

:parameters ()

:precondition (K (hasKnocked))

:observe (doorOpen)

)

(:action knock

:parameters ()

:precondition (K (lightOn))

:effect (((inRoom), (doorOpen, hasKnocked), ),

((not (inRoom)), (hasKnocked), (doorOpen))

)

)

)