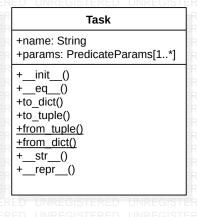


+__eq__() +__ne__() +to__dict() +to__tuple() +from__dict() +__str__() +__repr__()

Predicate +name: String +params: PredicateParams[1..*] +__init__() +__eq__() +to_dict() +to_tuple() +from_tuple() +from_dict() +__str__() +__repr__()

+name: String +params: PredicateParams[1..*] +value = None +__init__() +__eq__() +to_dict() +to_tuple() +from_tuple() +from_dict() +__str__() +__repr__()

Fluent



KnowledgeBaseInterface

_kb_collection_name: String = knowledge_base

kb database name: String = robot store

goal_collection_name: String = goal

+logger: logger

_init__()

+update kb()

+insert_facts() +remove_facts() +update_predicate()

+insert_fluents()
+remove_fluents()
+update_fluent()
+insert_goals()
+remove_goals()
-__get_kb_collection()
-_ item_exits()

+get_predicate_names()

+get fluent assertions()

+get_fluent_assertions()

_insert_predicates() _remove_predicates()

insert fluents()

remove fluents()

+get_predicates_assertions()

+get_fluent_names()

+get action model() +ACTIONs()

HDDLKnowledgeUtils

+get_ordered_param_list()

+get assertion param list() +predicates()

HDDLFluentLibrary

+get assertion param list()

+fluents()

+numericfluents()

HDDLPredicateLibrary

ActionDispatcher +action_dispatch_pub: rospy.Publisher +action_name: String +executing: Boolean = False +succeeded: Boolean = False +__init__() -_get_action_feedback()

+dispatch action()

+get assertion param list()