**USEFUL TIPS:**

The [LTLstack Wiki](#) is an extremely useful tool for implementing new LTLstack packages, as well as for finding general information and installation/implementation instructions.

The most important files to consider in a LTLstack package are the slugs specifications and the proposition YAML file.

**Installation**

1. Follow step 3 in the LTLstack documentation (given as a PDF in this folder), installing slugs in the same directory as the catkin workspace.
2. Follow step 4 in the LTLstack documentation (step 4(d) is not necessary, unless you wish to run an example and have access to the GUI that runs it).

**Implementing a new program**

To create a new LTLstack package, follow steps 6 and 7 in the LTLstack documentation (assuming you already have the proposition nodes). To run it, follow step 8.

The LTLstack wiki also has these instructions.

**Troubleshooting**

- If something isn't working, use the guide at the end of the LTLstack documentation
- Make sure you have completed the [ROS tutorials](#) (or have the [msg installation](#) correct)
- Check to make sure your specification is correct
- Check to make sure your nodes run properly and that your files are executable

**Notes**
- It is a similar process for every robot/workspace you would like to use LTLstack with
- Check out the tutorial and example files provided for reference and implementation help

A. Kubota, E. I. C. Peterson, V. Rajendren, H. Kress-Gazit, and L. D. Riek. JESSIE: Synthesizing Social Robot Behaviors for Personalized Neurorehabilitation and Beyond. In *Proceedings of the 2020 ACM/IEEE International Conference on Human-Robot Interaction (HRI)*. IEEE, 2020.