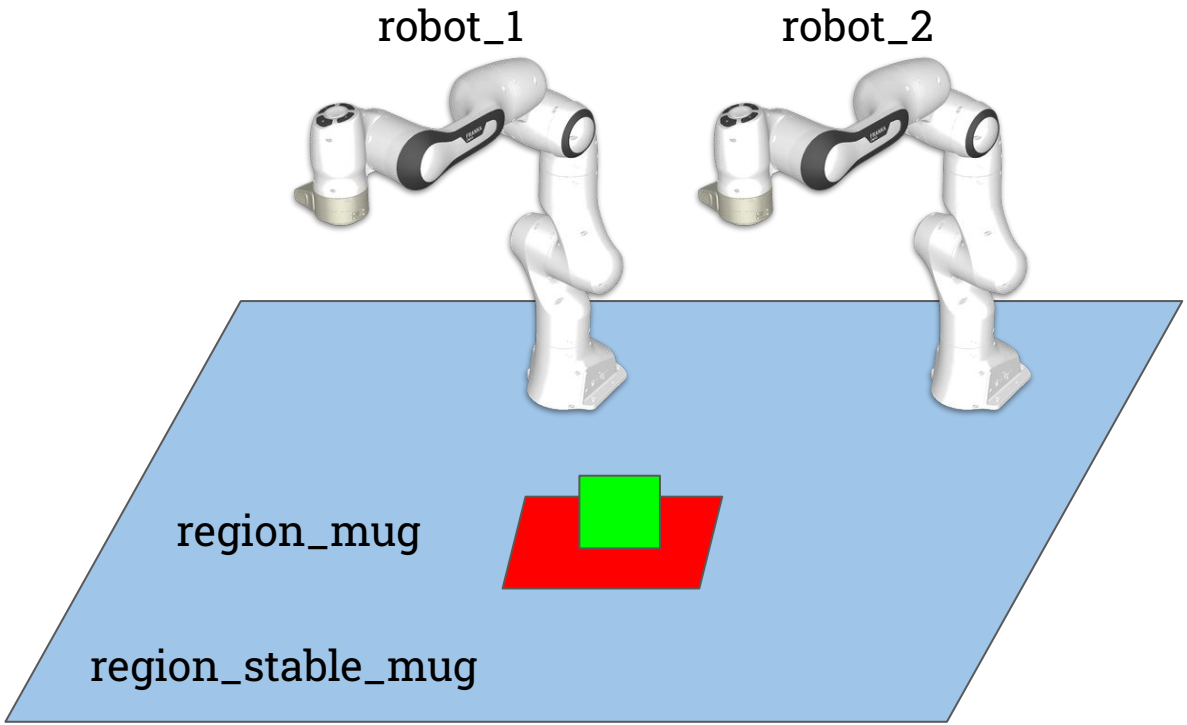
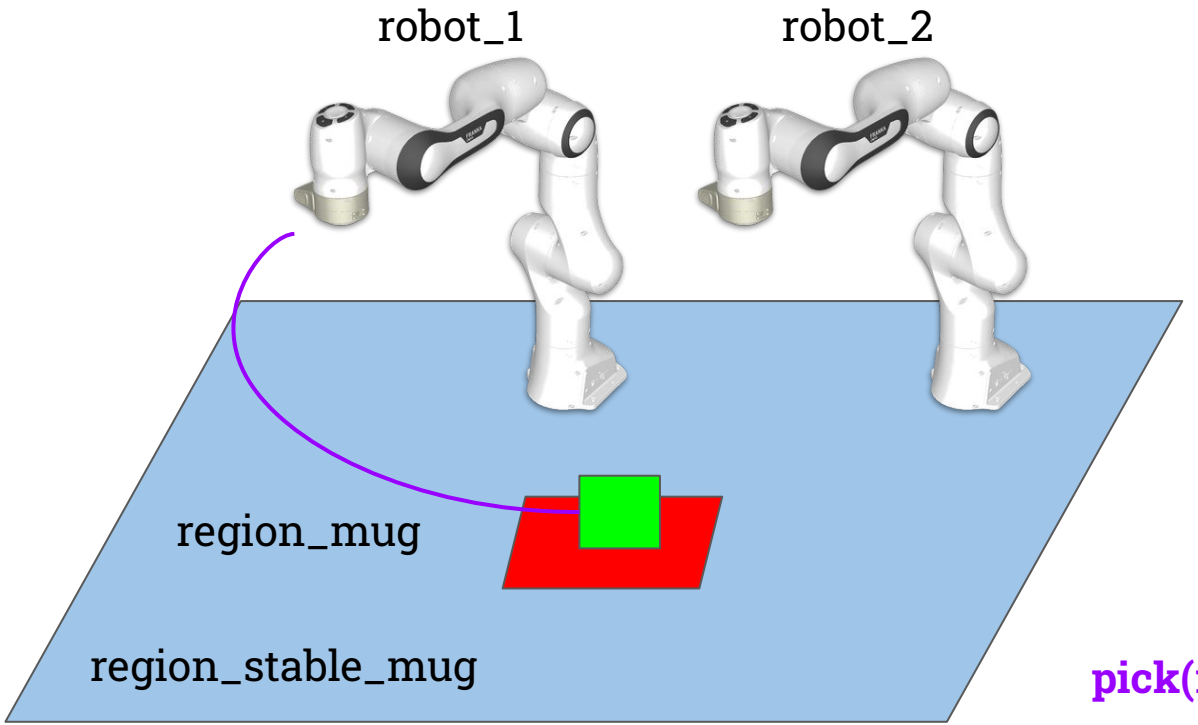
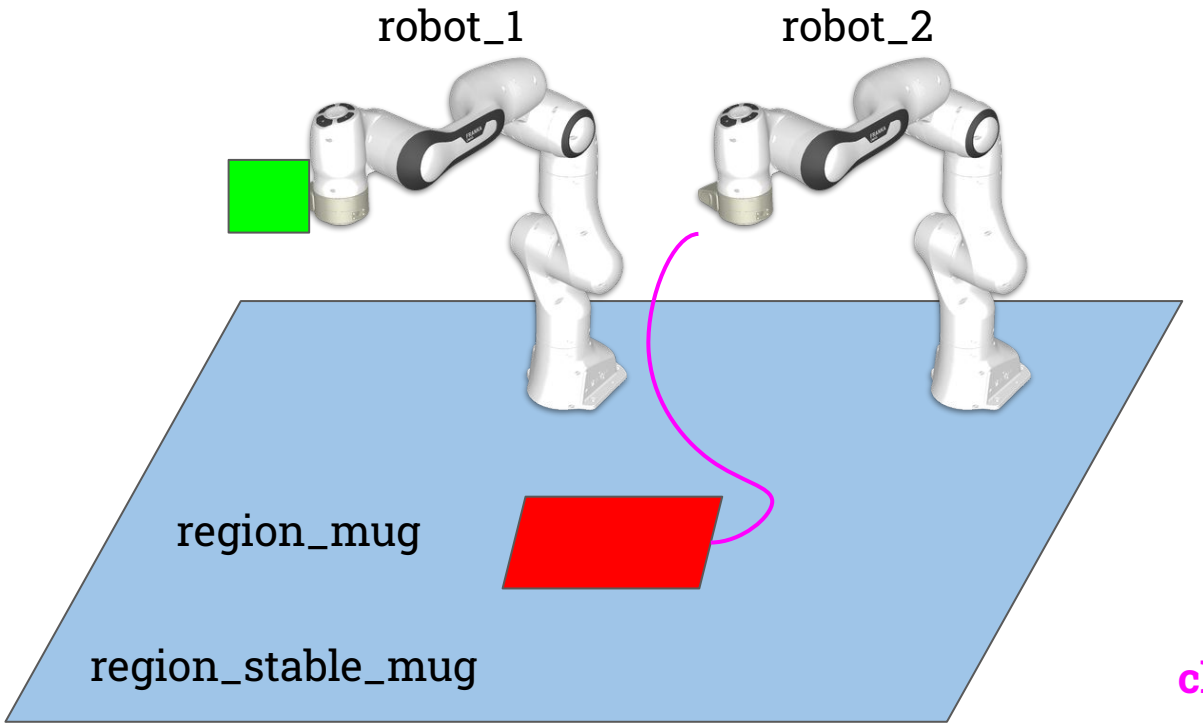


in_obj(mug, region_mug)
clean(region_stable_mug)



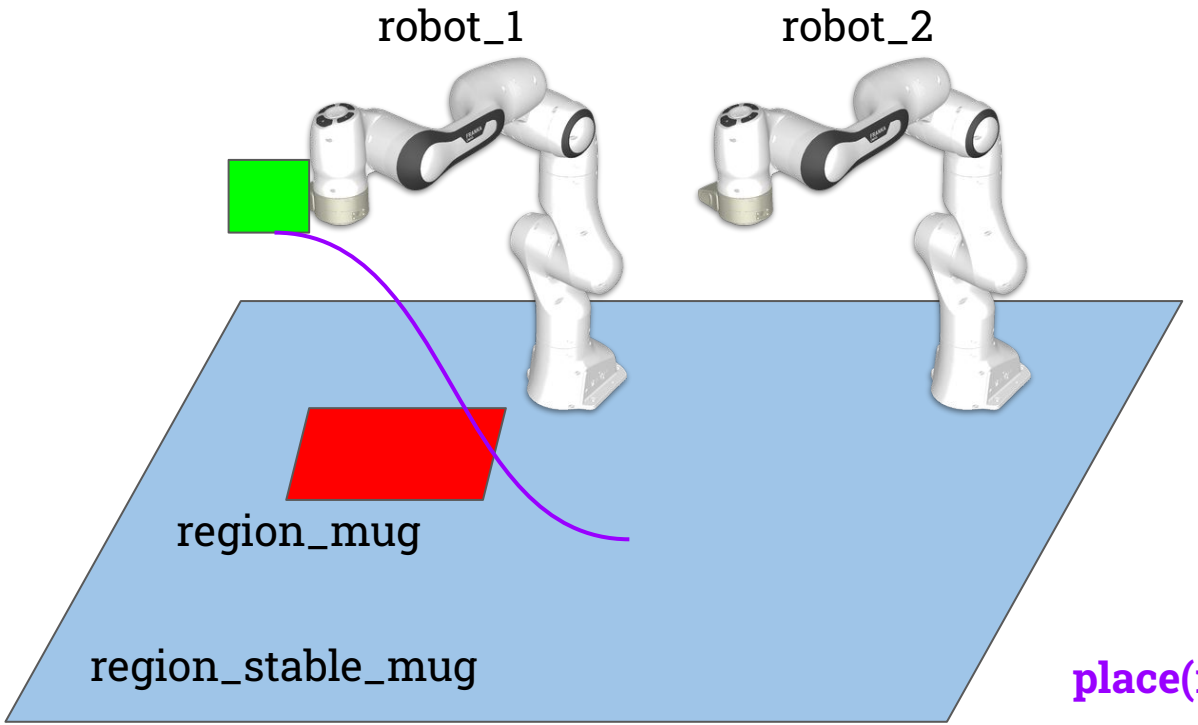
pick(robot_1, mug, region_mug)

holding(robot_1, mug)
clean(region_stable_mug)



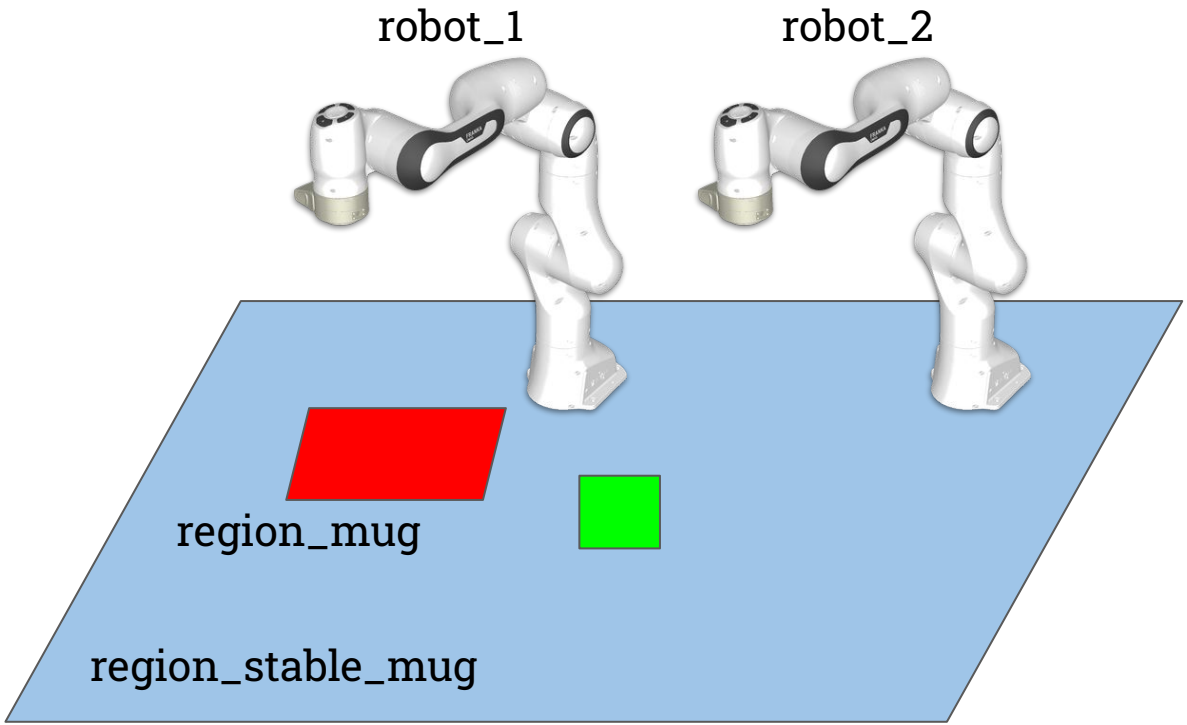
clean(robot_2, region_mug)

holding(robot_1, mug)
clean(region_stable_mug)
clean(region_mug)



place(robot_1, mug, region_mug)

in_obj(mug, region_mug)
clean(region_stable_mug)
clean(region_mug)



Goal achieved

in_obj(mug, region_mug)
clean(region_stable_mug)
clean(region_mug)