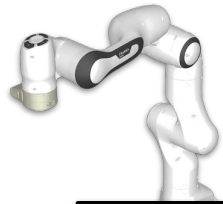
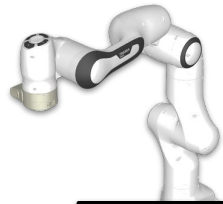


region_door

region_mug



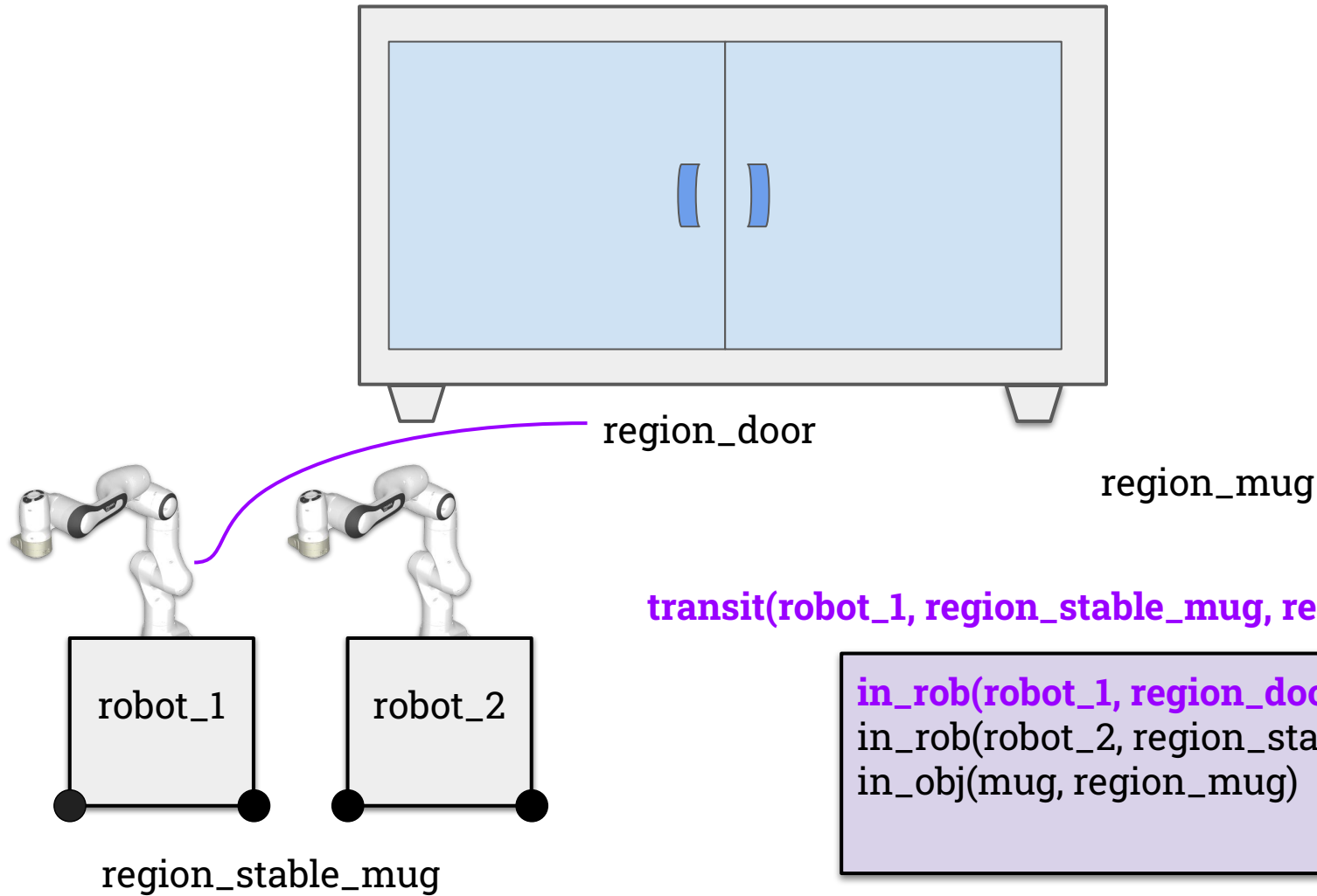
robot_1



robot_2

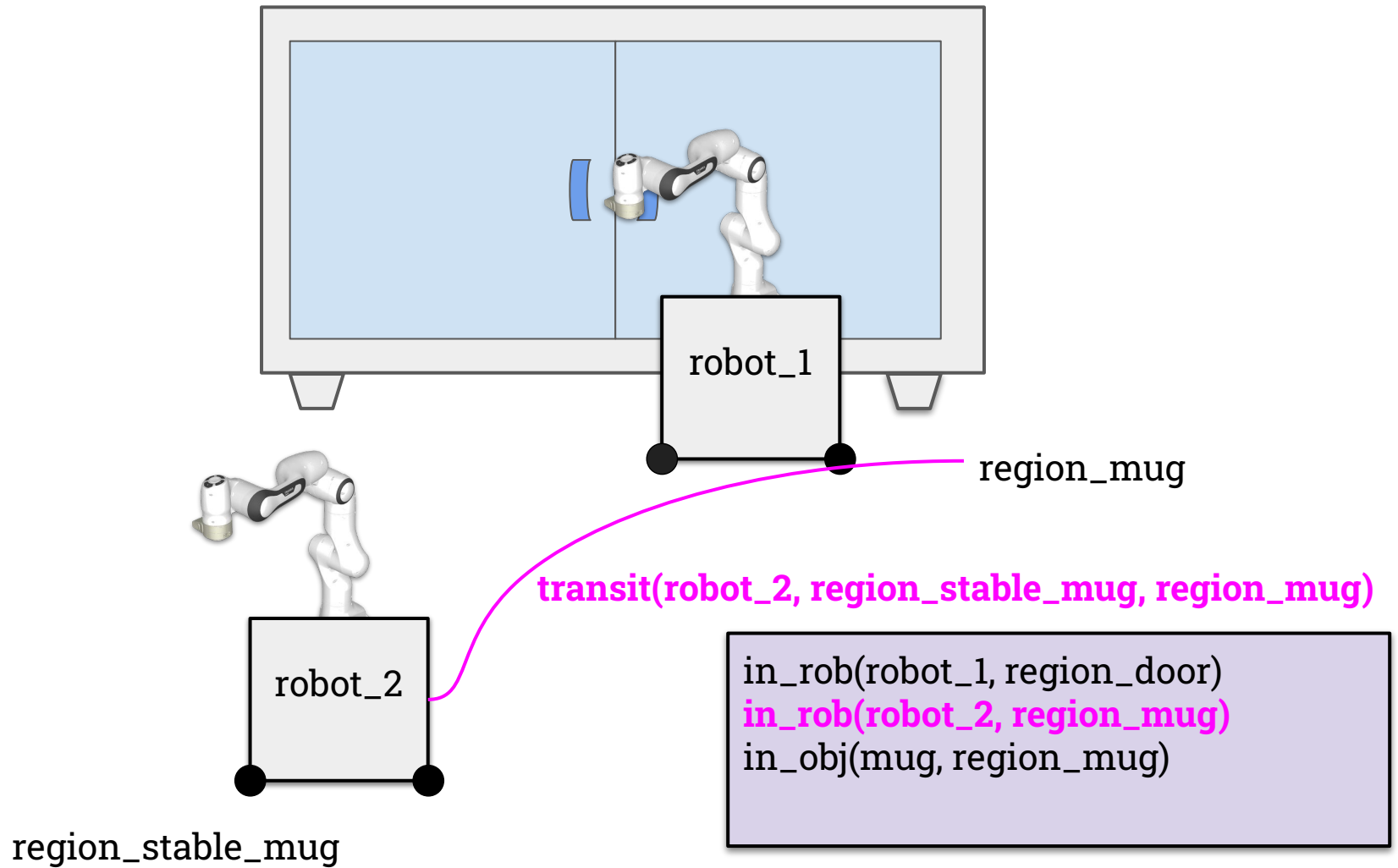
region_stable_mug

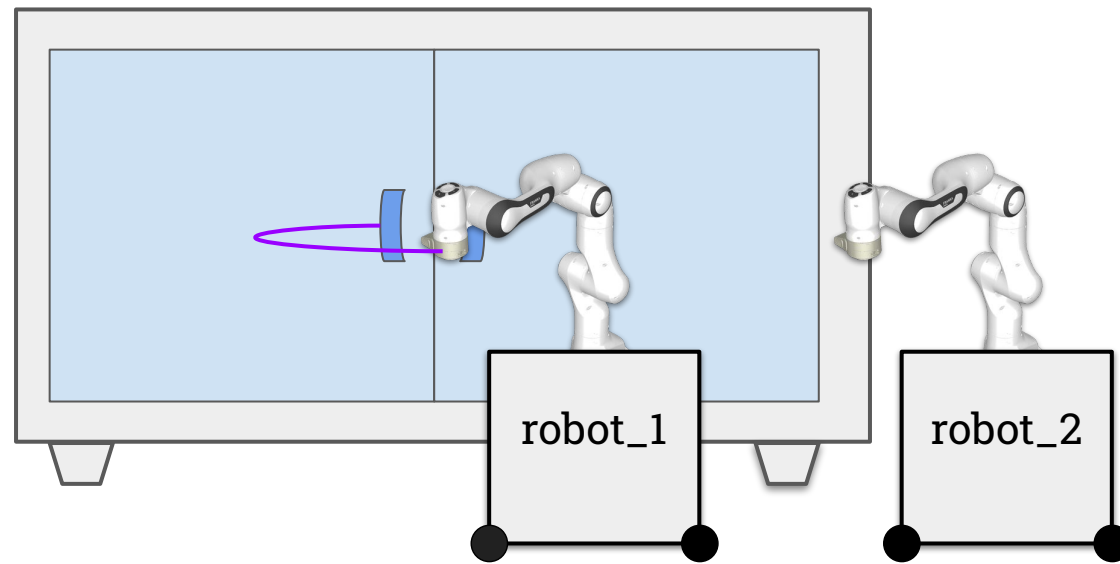
```
in_rob(robot_1, region_stable_mug)
in_rob(robot_2, region_stable_mug)
in_obj(mug, region_mug)
```



transit(robot_1, region_stable_mug, region_door)

in_rob(robot_1, region_door)
in_rob(robot_2, region_stable_mug)
in_obj(mug, region_mug)

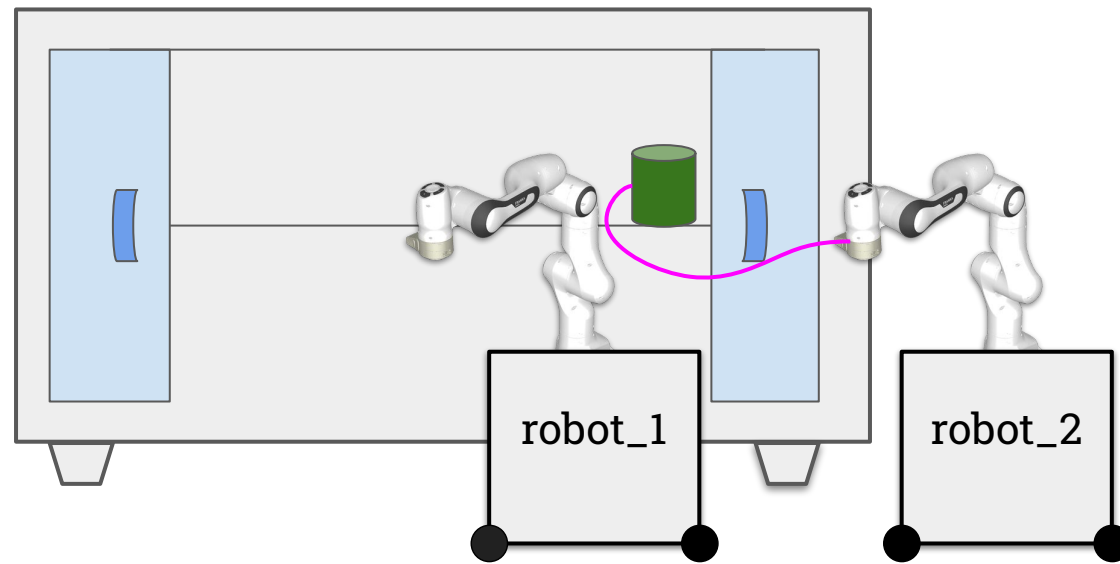




open(robot_1)

```
in_rob(robot_1, region_door)
in_rob(robot_2, region_mug)
in_obj(mug, region_mug)
open(door)
```

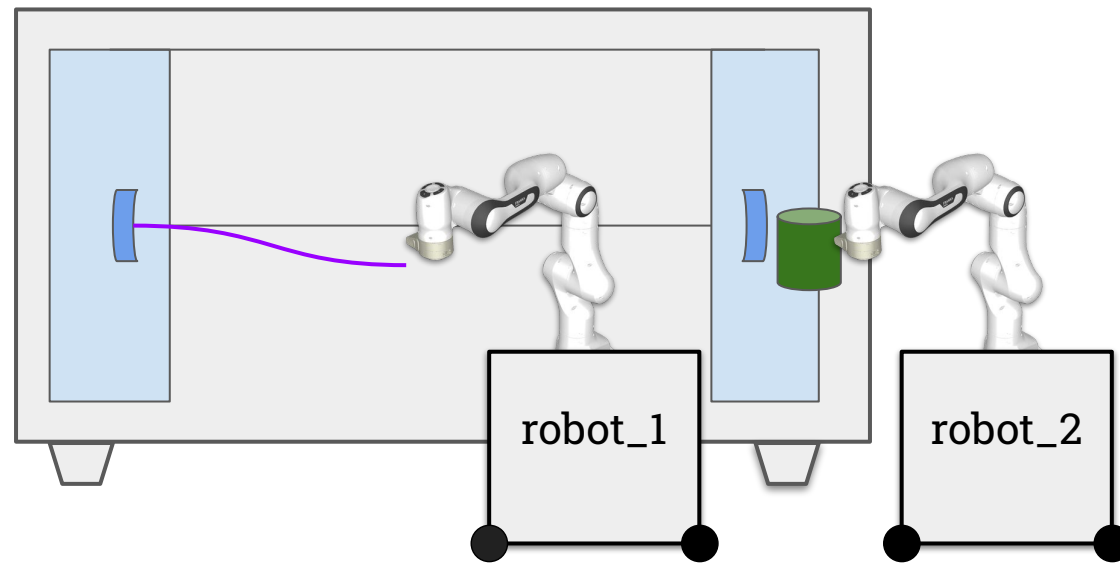
region_stable_mug



pick(robot_2, mug, region_mug)

```
in_rob(robot_1, region_door)
in_rob(robot_2, region_mug)
holding(robot_2, mug)
open(door)
```

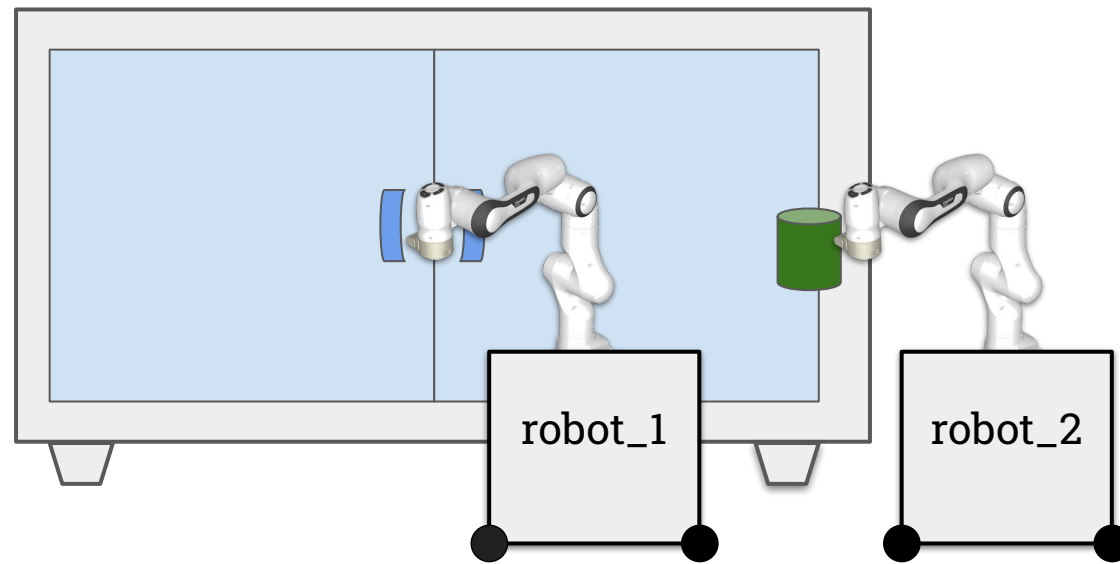
region_stable_mug



close(robot_1)

```
in_rob(robot_1, region_door)
in_rob(robot_2, region_mug)
holding(robot_2, mug)
not(open(door))
```

region_stable_mug



Goal achieved

```
in_rob(robot_1, region_door)
in_rob(robot_2, region_mug)
holding(robot_2, mug)
not(open(door))
```

region_stable_mug