Planning and Aproximate Reasoning: Robot Chef Task

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Abstract

Escribir un resumen aqui

1 Introduction

2 Analysis of the problem

2.1 Basic problem

Predicates used:

- (robot-at ?*r* - robot ?*loc* - location): Representes the localitation of a specific robot 'r', in an area of the kitchen 'loc'.
- (ingredient-at ?ingredient - ingredient ?loc - location): This predicate signifies the presence of an 'ingridient' in an area 'loc'.
- (tool-at ?tool - tool ?loc - location): This predicate indicates that the instrument 'tool' is in the area of the kitchen 'loc'.
- (ingredient-prepared ?ingredient - ingredient): This predicate indicates that the finished item of food 'dish' has been successfully assembled.
- (dish-assembled ?dish - dish): ??
- (dish-plated ?dish - dish ?loc - location): It denotes that the instrument 'tool' is clean.
- (tool-clean ?tool - tool): This predicaate denotes that the robot 'r' is holding the ingridient 'ingridient'.
- (holding ?r - robot ?item - item): This predicate represents that the robot 'r' is holding 'item', it can be a tool or an ingredient.
- (adjacent ?loc1 - location ?loc2 - location): Comprobation if the areas of the kitchen 'loc1' and 'loc2' are adjacent.
- (used-in ?ingredient - ingredient ?dish - dish): This predicates represents if the item 'ingrdient' has been used to prepare the recipe 'dish'.

3 Results

4 Discusion

5 Conclusion

Hola [1]

References

[1] Fu Chang, Chin-Chin Lin, and Chi-Jen Lu. Adaptive prototype learning algorithms: Theoretical and experimental studies. Journal of Machine Learning Research, 7:2125–2148, 2006.