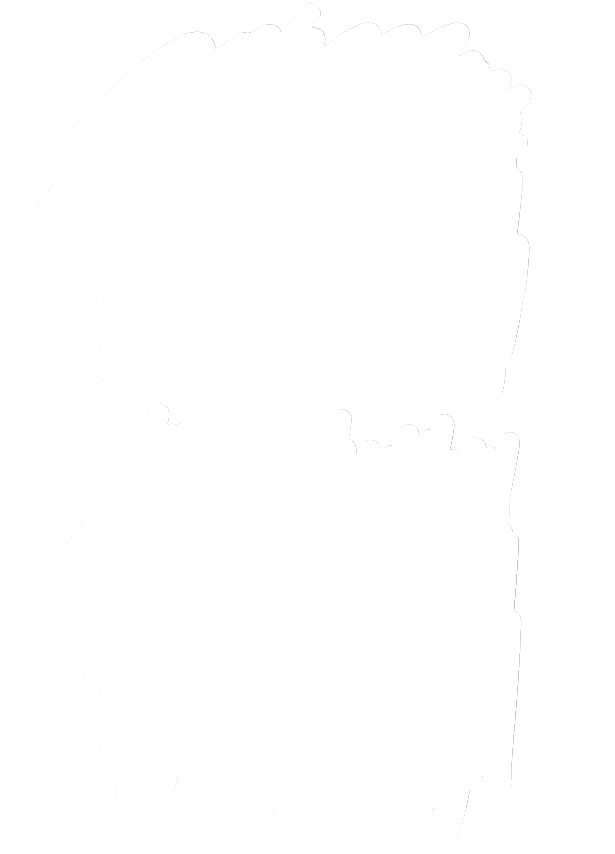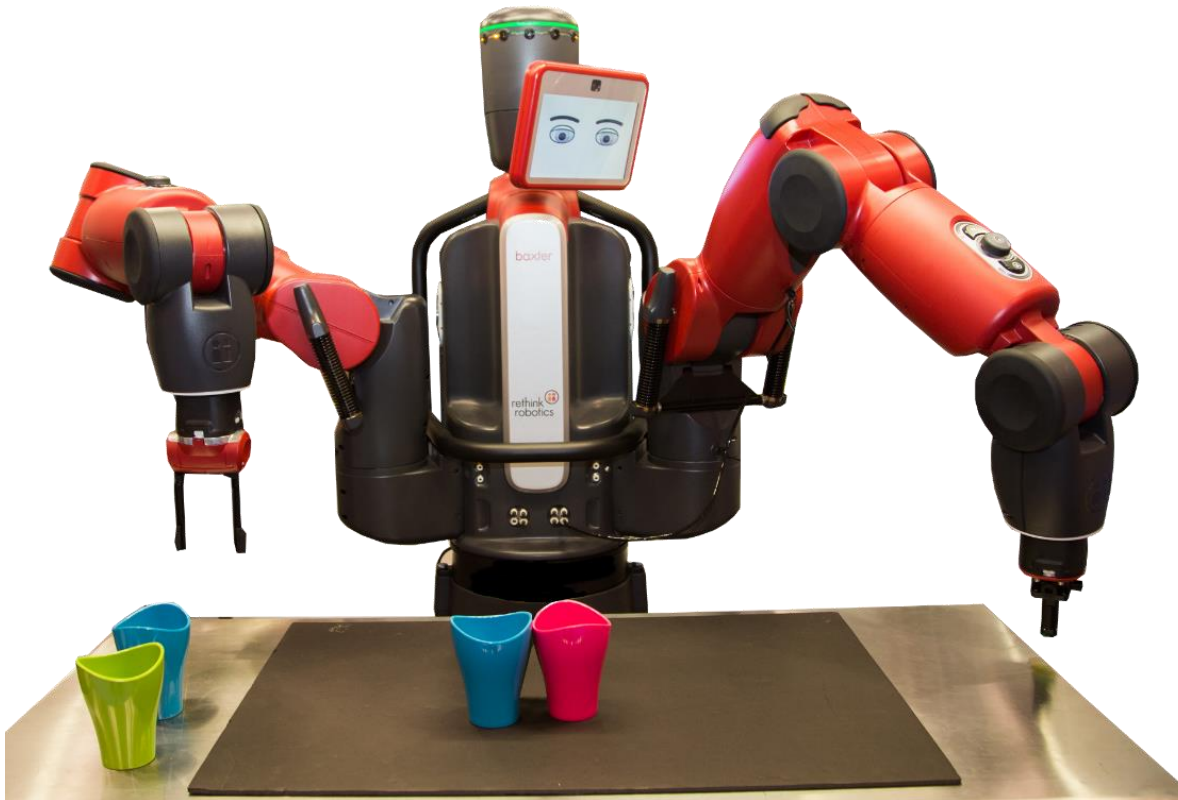# One arm robot problem

Plan found:

init

move b1 p5 p4

move b1 p4 p1

move r1 p3 p4

move g1 p6 p3

goal