

NON LINEAR PLANNING EXAMPLE

Given the following initial state **ontable(a,p1), ontable(d,p3), on(c,d), ontable(b,p2), clear(a), clear(c), clear(b), handempty**
and the goal **ontable(a,p2)**

Actions are described as follows

pickup(X,Pos)

PRECOND: ontable(X,Pos), clear(X), handempty

DELETE: ontable(X,Pos), clear(X), handempty

ADD: holding(X), empty(Pos)

putdown(X,Pos)

PRECOND: holding(X), empty(Pos)

DELETE: holding(X), empty(Pos)

ADD: ontable(X,Pos), clear(X), handempty

stack(X,Y)

PRECOND: holding(X), clear(Y)

DELETE: holding(X), clear(Y)

ADD: handempty, on(X,Y), clear(X)

unstack(X,Y)

PRECOND: handempty, on(X,Y), clear(X)

DELETE: handempty, on(X,Y), clear(X)

ADD: holding(X), clear(Y)

start

ontable(a,p1), ontable(d,p3), on(c,d), ontable (b,p2), clear(a), clear(c), clear(b), handempty

on(a,p2)

stop

start

ontable(a,p1), ontable(d,p3), on(c,d), ontable (b,p2), clear(a), clear(c), clear(b), handempty

holding(a) empty(p2)

putdown(a,p2)



on(a,p2)

stop

start

ontable(a,p1), ontable(d,p3), on(c,d), ontable (b,p2), clear(a), clear(c), clear(b), handempty

clear(a) ontable(a,PX) handempty

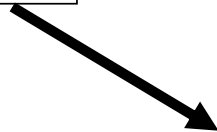
pickup(a,PX)

holding(a) empty(p2)

putdown(a,p2)

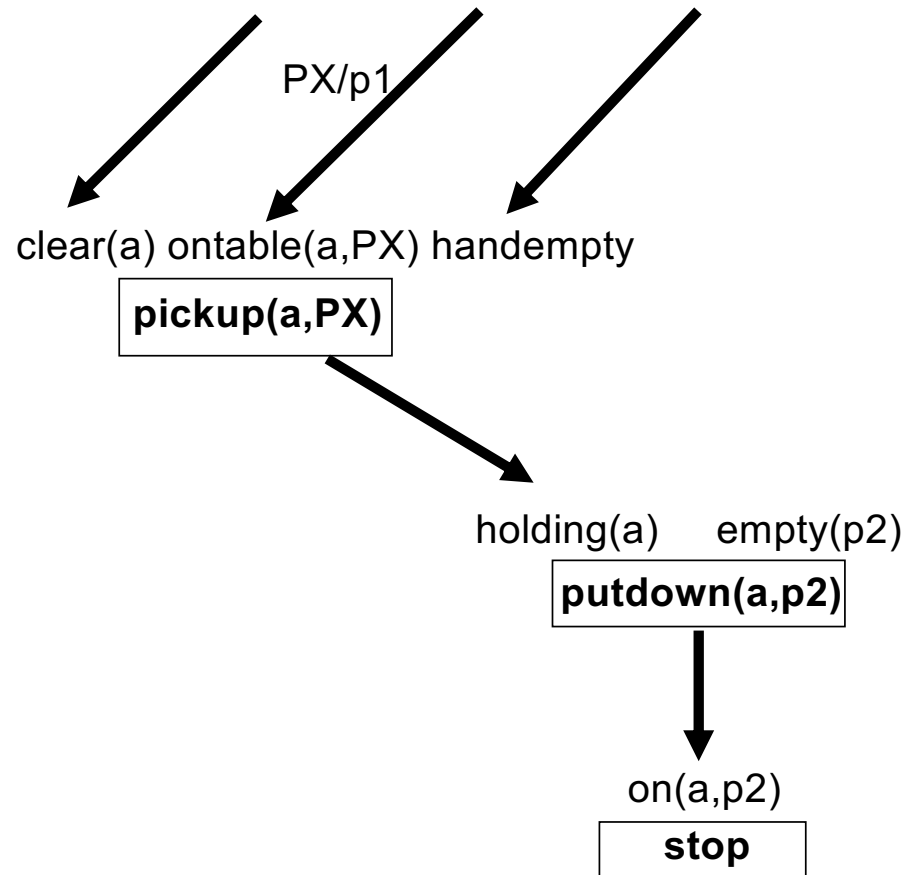
on(a,p2)

stop



start

ontable(a,p1), ontable(d,p3), on(c,d), ontable (b,p2), clear(a), clear(c), clear(b), handempty



start

ontable(a,p1), ontable(d,p3), on(c,d), ontable (b,p2), clear(a), clear(c), clear(b), handempty

