

	ACL		GoalNet	
	IED	SJI	IED	SJI
put chocolate and vanilla syrup on top	1.43E-07	0.1249	0.714	0.714
Pred delta_pos	(grasping robot syrup_1)(state syrup_1 ramen)(in ramen_1 syrup_1)		(state mug_1 chocolate)', '(on spoon_1 fridge)', '(near robot beer_1)', '(grasping robot mug_1)', '(grasping robot syrup_2)'	
Pred delta_neg	(on syrup_1 stovefire_2)		(grasping robot spoon_1)', '(on syrup_2 stovefire_2)'	
Pred Action	moveto(ramen_1), grasp(ramen_1), moveto(syrup_1), grasp(syrup_1), add(ramen_1 syrup_1),		moveto mug_1', 'grasp mug_1', 'moveto syrup_2', 'moveto beer_1', 'on_keep spoon_1 fridge', 'grasp syrup_2', 'squeeze syrup_2 mug_1'	
bring us coke and the beer	0.333	0.166	1	0.999
Pred delta_pos	(near robot beer_1)(on coke_1 beer_1)		(on coke_1 coffeetable_1)', '(on beer_1 coffeetable_1)'	
Pred delta_neg	(on coke_1 armchair_2)		(on coke_1 armchair_2)', '(on beer_1 snacktable_1)'	
Pred Action	moveto(coke_1), grasp(coke_1), moveto(beer_1), keep(coke_1 on beer_1),		['moveto beer_1', 'grasp beer_1', 'moveto coke_1', 'grasp coke_1', 'on_keep beer_1 coffeetable_1', 'on_keep coke_1 coffeetable_1']	
put some water into the kettle	0.4	0	1	0.99
Pred delta_pos	(near robot stovefire_4)(on kettle stovefire_4)		sink)', '(state kettle water)', '(state sinkknob tapison)', '(near robot stovefire_4)'	
Pred delta_neg	Empty		Empty	
Pred Action	o(kettle), grasp(kettle), moveto(stovefire_4), keep(kettle on stovefire_4),		'grasp kettle', 'moveto sink', 'keep_on_sink kettle', 'turn_s'	
place both books on the center table	1	0.99	0.41	0.49
Pred delta_pos	(near robot coffeetable_1)(on book_1 coffeetable_1)		(near robot coffeetable_1)', '(grasping robot book_2)', '(near robot cd_1)', '(on book_1 coffeetable_1)'	
Pred delta_neg	(on book_1 armchair_3)		(on book_1 armchair_3)', '(on book_2 loveseat_1)'	
Pred Action	moveto(book_1), grasp(book_1), moveto(coffeetable_1), keep(book_1 on coffeetable_1),		moveto book_1', 'grasp book_1', 'moveto coffeetable_1', 'near_keep book_1 coffeetable_1', 'moveto cd_1', 'moveto book_2', 'grasp book_2', 'moveto book_1', 'grasp book_1', 'on_keep book_1 coffeetable_1'	
Set up the TV and the Xbox	0	0	0.1666	0.545
Pred delta_pos	Empty		(near robot loveseat_1)', '(on xbox_1 loveseat_1)', '(near robot tv_1)', '(state xbox_1 cd)', '(in cd_1 xbox_1)'	
Pred delta_neg	Empty		(on xbox_1 snacktable_1)', '(on cd_1 studytable_1)'	
Pred Action	Empty		moveto xbox_1', 'grasp xbox_1', 'moveto tv_1', 'moveto cd_1', 'grasp cd_1', 'insert cd_1 xbox_1', 'moveto loveseat_1', 'on_keep xbox_1 loveseat_1'	
put pillows onto the coaches	0	0.076	0.33	0.363
Pred delta_pos	(grasping robot pillow_1)(state pillow_1 cd)(in cd_1 pillow_1)		(near robot loveseat_1)', '(on pillow_3 loveseat_1)', '(grasping robot pillow_1)', '(near robot pillow_1)'	
Pred delta_neg	(on pillow_1 shelf_1)(on cd_1 snacktable_1)		(on pillow_3 shelf_1)', '(on pillow_1 shelf_1)'	
Pred Action	moveto(cd_1), grasp(cd_1), moveto(pillow_1), grasp(pillow_1), insert(cd_1 pillow_1),		moveto pillow_3', 'moveto pillow_1', 'grasp pillow_1', 'moveto pillow_1', 'grasp pillow_3', 'moveto loveseat_1', 'on_keep pillow_3 loveseat_1'	