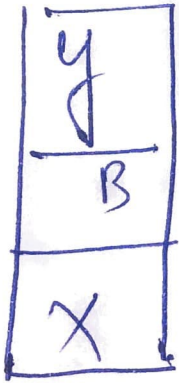
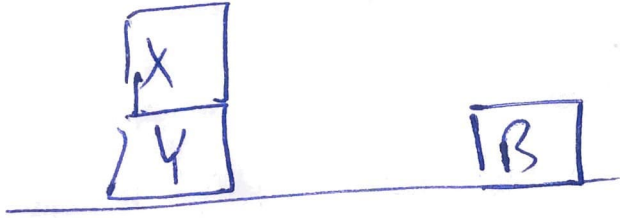


Goal Stack Planning





POORNIMA

COLLEGE OF ENGINEERING

DETAILED LECTURE NOTES

PAGE NO.

Pre condition

Action

1) Pickup (x)

- arm empty
- on (x, table)
- clear (x)

◦ holding (x)

2) Putdown (x)

- holding (x)

- arm empty
- on (x, table)
- clear (x)

3) Stack (x, y)^b

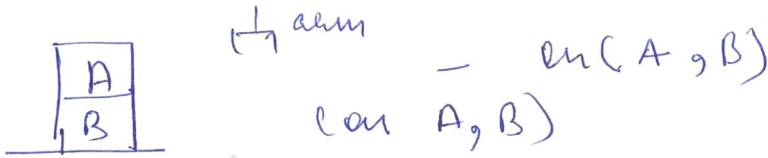
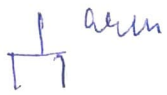
- holding (x)

- on (x, y)
- clear (x)
- arm empty

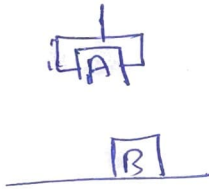
4) unstack (x, y)

- on (x, y)
- clear (x)
- arm empty

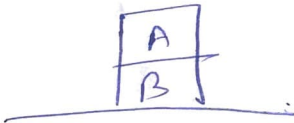
- holding (x)
- clear (y)



① Pickup (A)



② Stack (A, B)



goal state achieved

$on(A, B)$ (pop)

stack (A, B) — ②

~~holding (A)~~
— $clear(B)$ (pop)

A —
pickup (A) — ①

→ arm empty
→ $on(A, table)$
→ $clear(A)$ (pop)

• if pre conditions
are specified
then you can
perform these
actions.