AdaptBot: Supplementary Material

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1 Question asked during Knowledge Expansion

1.1 Question asked for unknown action

Revising action name.

• **Robot:** I do not know how to execute action 'place', am I mistaking it for another action? Please answer in 'Yes' or 'No'.

• Human: Yes

• **Robot:** Please revise the action name

• Human: put_down_obj

pick_up_obj("apple", "initial_state.ttl")
put_down_obj("apple", "sink")
clean("apple", "updated_state.ttl")
pick_up_obj("apple", "updated_state.ttl")
slice("apple", "knife", "updated_state.ttl")
place("apple", "plate")



pick_up_obj("apple", "initial_state.ttl")
put_down_obj("apple", "sink")
clean("apple", "updated_state.ttl")
pick_up_obj("apple", "updated_state.ttl")
slice("apple", "knife", "updated_state.ttl")
put_down_obj ("apple", "plate")

Removing unexecutable action.

• **Robot:** I do not know how to execute action 'squueze', am I mistaking it for another action? Please answer in 'Yes' or 'No'.

• Human: No

pick_up_rec ("glass", "initial_state.ttl")
put_down_rec ("glass", "countertop")
pick_up_object ("water", "updated_state.ttl")
put_down_object ("water", "glass")
pick_up_object ("lemon", "updated_state.ttl")
squeeze ("lemon", "glass")



pick_up_rec ("glass", "initial_state.ttl")
put_down_rec ("glass", "countertop")
pick_up_object ("water", "updated_state.ttl")
put_down_object ("water", "glass")
pick_up_object ("lemon", "updated_state.ttl")

1.2 Question asked for unknown item

Adding an item to G_s and G_k .

Example 1

• **Robot:** Item 'mango' is not present in my knowledge base. Is it present in the environment? Please answer in 'Yes' or 'No'. If I am mistaking it for another item, please enter 'correct_item'.

• Human: Yes.

• Robot: What kind of item is 'mango'? Choose from: 'edible_object', 'receptacle', 'tool'.

• Human: edible_object

• **Robot:** What is the location of the object?

• Human: Fridge

• Robot: Is it sliceable? Please answer in 'True' or 'False.

• Human: True

• Robot: Is it boilable? Please answer in 'True' or 'False'.

• Human: False

• Robot: Is it fryable? Please answer in 'True' or 'False'.

• Human: False

• Robot: Does this object needs cleaning? Please answer in 'True' or 'False'.

• Human: True

Example 2

• **Robot:** Item 'bowl' is not present in my knowledge base. Is it present in the environment? Please answer in 'Yes' or 'No'. If I am mistaking it for another item, please enter 'correct_item'.

• Human: Yes.

• Robot: What kind of item is 'bowl'? Choose from: 'edible_object', 'receptacle', 'tool'.

• Human: receptacle

• **Robot:** What is the location of the object?

• Human: Cabinet

• Robot: Is receptacle sensitive? Please answer in 'True' or 'False.

• Human: True

• Robot: Can this receptacle be used for slicing on? Please answer in 'True' or 'False'.

• Human: False

• Robot: Does this receptacle needs cleaning? Please answer in 'True' or 'False'.

• Human: True

Example 3

• **Robot:** Item 'fork' is not present in my knowledge base. Is it present in the environment? Please answer in 'Yes' or 'No'. If I am mistaking it for another item, please enter 'correct_item'.

• Human: Yes.

• Robot: What kind of item is 'fork'? Choose from: 'edible_object', 'receptacle', 'tool'.

• Human: tool

• **Robot:** What is the location of the object?

• Human: rack

• Robot: Is it a slicing tool? Please answer in 'True' or 'False.

• Human: False

• Robot: Does this tool needs cleaning? Please answer in 'True' or 'False'.

• Human: True

Revising the item name.

• **Robot:** Item 'sauce' is not present in my knowledge base. Is it present in the environment? Please answer in 'Yes' or 'No'. If I am mistaking it for another item, please enter 'correct_item'.

• Human: correct_item.

• **Robot:** Please revise the object name.

• Human: ketchup

Item isn't present in the environment.

• **Robot:** Item 'grapes' is not present in my knowledge base. Is it present in the environment? Please answer in 'Yes' or 'No'. If I am mistaking it for another item, please enter 'correct_item'.

• Human: No.

pick_up_rec ("plate", "initial_state.ttl")
put_down_rec ("plate", "countertop")
pick_up_object ("apple", "updated_state.ttl")
put_down_object ("apple", "plate")
pick_up_object ("banana", "updated_state.ttl")
put_down_object ("grapes", "updated_state.ttl")
pick_up_object ("grapes", "updated_state.ttl")
put_down_object ("grapes", "plate")



pick_up_rec ("plate", "initial_state.ttl")
put_down_rec ("plate", "countertop")
pick_up_object ("apple", "updated_state.ttl")
put_down_object ("apple", "plate")
pick_up_object ("banana", "updated_state.ttl")
put_down_object ("banana", "plate")

2 Results for other LLMs

will update very soon..