

References

- [KLP11] Leslie Pack Kaelbling and Tomás Lozano-Pérez. Hierarchical task and motion planning in the now. In *2011 IEEE International Conference on Robotics and Automation*, pages 1470–1477, 2011.

Decomposes TAMP problem and solves in real time based on world's state through execution. Represents actions in world as operation and modifications to world state as fluents. Decomposes operations into weakest precondition subgoals and solves those recursively. This makes order of execution critical! Will only find a plan if the goal state is reachable through some set of operations. Defines goals as conjunctions of fluents (i.e. like $\text{Clean}(a)$).