A Algorithms

Algorithm 1: Caching a skill in an abstract domain.

```
1 Algorithm cachSkill
       Inputs:
           A state trace from the skill execution \mathfrak{S}\left(\boldsymbol{E}\right)
           A public abstraction key PubKey = (project_p, reconst_p, \mathcal{P}_s)
       | Caching success flag
       validPrivateKeys \leftarrow \bigcap_{S \in \mathfrak{S}(E)} \mathcal{P}_S
\mathbf{2}
       if validPrivateKeys \neq \emptyset then
3
           Select a key p from validPrivateKeys
4
5
           abstractTrace \leftarrow \mathtt{project}_p\left(\mathfrak{S}\left(\pmb{E}\right)\right)
           DataBase.add(abstractTrace, PubKey)
6
                                                                // caching succeeded
           return True
8
       \mathbf{end}
       return False
                                // caching failed, try another public key
```

Algorithm 2: Get a private key for reconstruction (applicability test).

```
1 Algorithm getPrivateKey
             Inputs:
                     An abstract skill's state trace (\xi_0, \ldots, \xi_n)
                     A start state \boldsymbol{S}_{\mathrm{start}}
A task goal state \boldsymbol{S}_{\mathrm{goal}}
                     A public key PubKey = (project_p, reconst_p, \mathcal{P}_s)
              Output:
                     If the abstract skill is applicable, returns a private key for
                       reconstruction; otherwise, returns False
             if \left|\mathcal{P}_{S_{start}}^{oldsymbol{\xi}_0}\right|=1 then
  \mathbf{2}
                    p \leftarrow \mathcal{P}_{oldsymbol{S}_{	ext{start}}}^{oldsymbol{\xi}_{0}} \ 	ext{if project}_{p}\left(oldsymbol{S}_{goal}
ight) = oldsymbol{\xi}_{n} \ or \ 	ext{reconst}_{p}\left(oldsymbol{\xi}_{n}
ight) = oldsymbol{S}_{goal} \ 	ext{then}
  3
  4
                                                                                                                               // applicable
  5
                     end
  6
  7
             \quad \text{end} \quad
             \begin{array}{l} \text{else if } \left| \mathcal{P}_{S_{start}}^{\boldsymbol{\xi}_0} \right| > 1 \text{ then} \\ \left| \begin{array}{l} intersection \, \leftarrow \, \mathcal{P}_{S_{\text{goal}}}^{\boldsymbol{\xi}_n} \cap \mathcal{P}_{S_{\text{start}}}^{\boldsymbol{\xi}_0} \end{array} \right| \end{array}
  8
  9
                     if intersection \neq \emptyset then
10
                            Select a key p from intersection
11
                            \mathbf{return}\ p
                                                                                                                               // applicable
12
13
                     end
              \mathbf{end}
14
              return False
                                                                                                          // skill inapplicable
15
```

Algorithm 3: Reconstruction of a cached abstract skill.

```
1 Algorithm reconstructSkill
        Inputs:
             An abstract skill's state trace (\boldsymbol{\xi}_0, \dots, \boldsymbol{\xi}_n)
            A public key PubKey = \left( \texttt{project}_p, \texttt{reconst}_p, \mathcal{P}_s \right)
            A "classical" task planning problem P \doteq (D, S_{\text{start}}, S_{\text{goal}})
        Output:
             A plan that solves the given problem, if reconstruction
              succeeded; otherwise, returns False
        p \leftarrow \text{getPrivateKey}(\boldsymbol{\xi}_0, \boldsymbol{\xi}_n, \boldsymbol{S}_{start}, \boldsymbol{S}_{goal}, PubKey)
 \mathbf{2}
        if p \neq False then
                                                              // skill is applicable
 3
            states \leftarrow \mathtt{reconst}_p\left(\boldsymbol{\xi}_0,\ldots,\boldsymbol{\xi}_n\right) // reconstruct state trace
            actions \leftarrow \texttt{recoverActions}(states, D)
                                                                    // recover actions
 5
            if actions \neq False then
 6
                 {f return}\ actions
 7
            end
 8
        end
        return False
10
 1 Procedure recoverActions
        Inputs:
            A state trace (S_0, \ldots, S_n)
            A planning domain D
        Output:
            If feasible, returns a sequence of actions that follows the states in
              the trace; otherwise, returns False
        for i \in \{1, ..., n\} do
 2
            if \exists an action a \in A between S_{i-1} and S_i then
 3
             a_i \leftarrow a
 4
            end
 6
            else
              return False
                                                                            // unfeasible
 7
            end
 8
        end
 9
                                                                               // feasible
        return (a_1,\ldots,a_n)
10
```