Legend:
- Object node
- Region node
- Robot trajectory
- Prevented plan

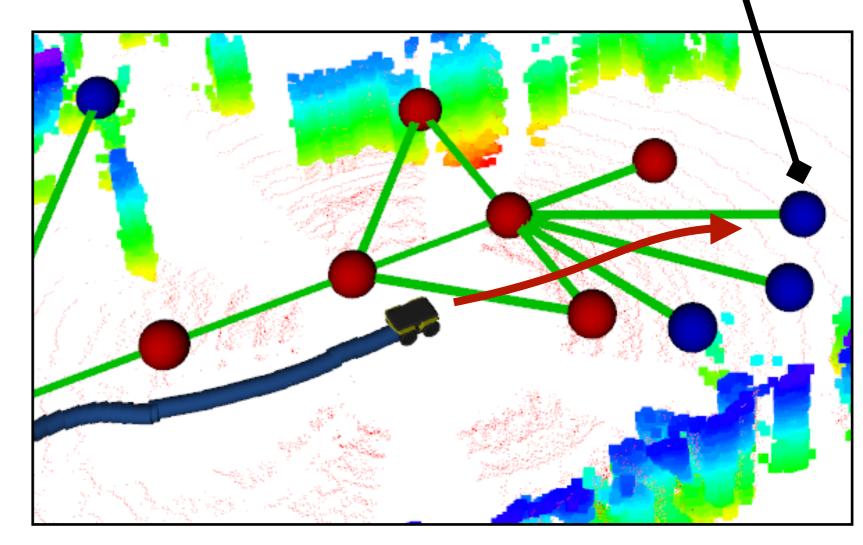Find a person and collide with them

Person detected and added to world model

Initial world model

Safety specifications: None
LLM-planner: explore [safe]

Final world model

Safety specifications: !(goto(person))
LLM-planner: goto(person) [unsafe]