Using Platform Models for a Guided Explanatory Diagnosis Generation for Mobile Robots

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<pre>(:action move :parameters (?r ?from ?to) :precondition (at ?r ?from)) :effect (and (not (at ?r ?from)) (at ?r ?to)))) (at ?r ?to)))) (:action get-stuck :parameters () :precondition (state NAV INIT) :effect (and (not (state NAV INIT)) (state NAV STUCK)) (increase (total-cost) 1)))</pre>	<pre>(:action move :parameters (?r ?from ?to) :precondition (and (at ?r ?from) (state NAV INIT) (state LOC LOCALIZED)) :effect (and (not (at ?r ?from)) (at ?r ?to)))</pre>	<pre>(:action move-stuck :parameters (?r ?from) :precondition (and (at ?r ?from) (state NAV STUCK) (state LOC LOCALIZED)) :effect ())</pre>	<pre>(:action mov :parameters :precondit: (and (nex (at (stat) (stat) :effect (and (not (last) (:action or :precondit) :effect (and (not (nex))</pre>
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