
Concurrent Reactive Plans Anticipating And Forestalling Execution Failures

reactive and proactive sharing across concurrent ... - reactive and proactive sharing across concurrent analytical queries ... sharing among concurrent queries. sharing can be reactive to the inherently existing sharing opportunities, or proactive by redesign- ... sp identifies common sub-plans among concurrent queries at run-time, evaluates only one and pipelines the results to the rest ... **causal models of mobile service robot behavior** - nize parallel actions, make plans reactive, and so on. structured reactive delivery plans to illustrate the advantages of high-level plans that specify concurrent reactive behavior, we sketch a plan that specifies how r.i[mo (see fig. 1) is to deliver mail to the rooms a-120, a-113, a-121, and a-110. ini- **executing structured reactive plans** - executing structured reactive plans* michael beetz institut fiir informatik iii, universit&t bonn, rsmstr. 164, ... to synchronize its concurrent actions, and to recover from execution failures (fir89). in this kind ... plans were to be executed in a situation where more **structured reactive controllers and transformational ...** - concurrent execution. williams et al. [25] developed the reactive model-based programming language (rmpl) to represent reactive plans, however the plans are not explicit and transparent. one of the best-known reactive planning languages is rap [5] which is very robust and can also monitor the desired and actual outcome of the given plan. **structured reactive communication plans — integrating ...** - in g eneral, concurrent reactive plans specify how an agent is to interact with its environment in order to accomplish its jobsa consequence, modern reactive plan languages ... **lecture notes in artificial intelligence 1772 - springer** - tured reactive plans (srps), concurrent control programs that can not only be interpreted but also reasoned about and manipulated. these plans specify how the robot is to respond to sensory input in order to accomplish its jobs. in this book we describe a computational model of forestalling common flaws in autonomous robot behavior. **planning, scheduling, and plan execution for autonomous ...** - activity by employing concurrent reactive plans that reschedulethe course of action whenever necessaryand while performing their actions. the plans are repre-sented modularly and transparently to allow for easy transformation. scheduling and schedule repair meth-ods are implemented as plan transformation rules. introduction **probabilistic hybrid action models for predicting ...** - beetz & grosskreutz ners cannot exploit the control structures provided by reactive plan languages to make plans more flexible and reliable. in this article we develop phams (probabilistic hybrid action models), action models that have the expressiveness for the accurate prediction of behavior generated by concurrent reactive **executing reactive, model-based programs through graph ...** - executing reactive, model-based programs through graph-based temporal planning phil kim and brian c. williams mit rm. 37-381 ... gramming game plans and contingencies that in the pro-grammer's experience will ensure a high degree of suc- ... and concurrent threads of activities, such as going to a se- ... **model-based reactive planning for autonomous systems** - model-based reactive planning for autonomous systems seung h. chung & brian c. williams ... methods for precompiling reactive plans are efficient, such as universal plans. however, universal plans have size quadratic in the number of system states, and are impractical ... modeled by a set of concurrent state machines that communicate through **probabilistic hybrid action models for predicting ...** - rent reactive plans (crps). it models the interactions be-tween multiple concurrent processes, the temporal structure of continuous processes, percept-driven control, and inter-ferencebetweeneffects ofconcurrentcontrolprocesses. the main contributions of this paper are (1) phams, a model of concurrentpercept-drivenbehavior, its formalization, and **learning structured reactive navigation plans from ...** - plans that specify and synchronize concurrent percept-driven be-havior. concurrent plans are represented in a transparent and modu-lar form so that automatic planning techniques can make inferences about them and revise them. reactive collision avoidance mdp-based path planner rhino navigation system srpa library models xfrm-learn structured ... **a decomposed symbolic approach to reactive planning** - a decomposed symbolic approach to reactive planning 3 that takes advantage of the obdd. since then, several obdd-based universal planning algorithms have been introduced for operating within nondeterministic domains [11-13]. in our approach, we also take advantage of obdd, but unlike **a decomposed symbolic approach to reactive planning** - conquer" approach introduced by the burton reactive planner to systems with interde-pendent components, where a system with interdependent components is characterized by cycles within its tdg. second, it generalizes obdd plan encodings from universal plans, which are conditioned on all possible initial states, to goal-directed plans that **obias christian rittweiler may 5, 2010** - a new incarnation of the reactive plan language (rpl) by mcdermott et al. cpl is a modernized, truly common lisp based, compiled domain speci c language to express robots' execution plans as concurrent reactive control programs with rich control structures for perception-guided control and failure detection, classi cation and handling.

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