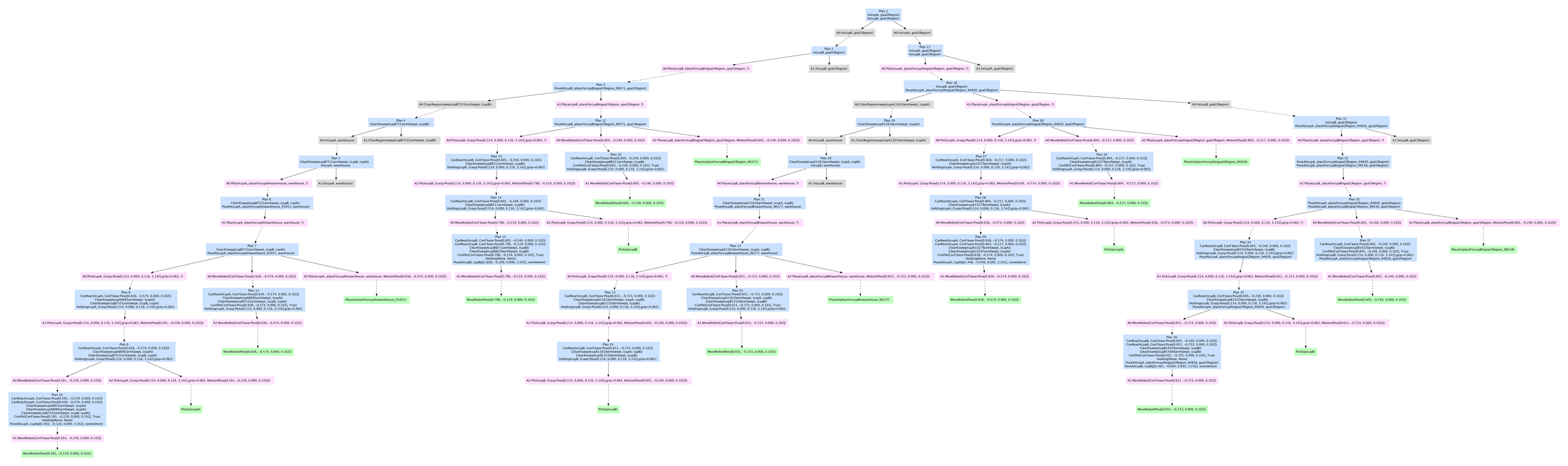
Plan 1
Init(cupA, goal2Region)
Init(cupB, goal1Region)
A0 Init(cupB, goal1Region)
A0 Init(cupA, goal2Region)
Plan 2
Init(cupB, goal1Region)
Plan 17
Init(cupA, goal2Region)
Init(cupB, goal1Region)
A0 Place(cupB, placeForcupBingoal1Region, goal1Region, ?)
A1 Init(cupB, goal1Region)
A0 Place(cupA, placeForcupAingoal2Region, goal2Region, ?)
A1 Init(cupA, goal2Region)
Plan 3
PoseAt(cupB, placeForcupBingoal1Region_90471, goal1Region)
Plan 18
Init(cupA, goal2Region)
PoseAt(cupA, placeForcupAingoal2Region_94830, goal2Region)
A0 ClearRegion(sweptcupB7513armSwept, (cupB))
A1 Place(cupB, placeForcupBingoal1Region, goal1Region, ?)
A0 ClearRegion(sweptcupA11610armSwept, (cupA))
A1 Place(cupA, placeForcupAingoal2Region, goal2Region, ?)
A0 Init(cupB, goal1Region)
Plan 4
ClearXsweptcupB7513armSwept, (cupB)
Plan 12
PoseAt(cupB, placeForcupBingoal1Region_90471, goal1Region)
Plan 19
ClearXsweptcupA11610armSwept, (cupA)
Plan 26
PoseAt(cupA, placeForcupAingoal2Region_94830, goal2Region)
Plan 31
Init(cupB, goal1Region)
PoseAt(cupA, placeForcupAingoal2Region_94830, goal2Region)
A0 Init(cupA, warehouse)
A1 ClearRegion(sweptcupB7513armSwept, (cupB))
A0 Pick(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.605, −0.240, 0.000, 0.102])
A2 Place(cupB, placeForcupBingoal1Region, goal1Region, MotionPose(0.605, −0.240, 0.000, 0.102])
A0 Init(cupB, warehouse)
A1 ClearRegion(sweptcupA11610armSwept, (cupA))
A0 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.804, −0.217, 0.000, 0.102])
A2 Place(cupA, placeForcupAingoal2Region, goal2Region, MotionPose(0.804, −0.217, 0.000, 0.102])
A0 Pick(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 Place(cupB, placeForcupBingoal1Region, goal1Region, ?)
A1 Init(cupB, goal1Region)
Plan 5
ClearXsweptcupB7513armSwept, (cupB, cupA)
Init(cupA, warehouse)
Plan 13
CanReach(cupB, Conf base Pose(0.605, −0.240, 0.000, 0.102])
ClearXsweptcupB8211armSwept, (cupB)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 18
CanReach(cupB, Conf base Pose(0.605, −0.240, 0.000, 0.102])
ClearXsweptcupB8211armSwept, (cupB)
ConfAttConf base Pose(0.605, −0.240, 0.000, 0.102], True)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 20
ClearXsweptcupA11610armSwept, (cupA, cupB)
Init(cupB, warehouse)
Plan 27
CanReach(cupA, Conf base Pose(0.804, −0.217, 0.000, 0.102])
ClearXsweptcupA1327armSwept, (cupA)
Holding(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 30
CanReach(cupA, Conf base Pose(0.804, −0.217, 0.000, 0.102])
ClearXsweptcupA1327armSwept, (cupA)
ConfAttConf base Pose(0.804, −0.217, 0.000, 0.102], True)
Holding(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 32
PoseAt(cupA, placeForcupAingoal2Region, 94830, goal2Region)
PoseAt(cupB, placeForcupBingoal1Region, 98538, goal1Region)
A0 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.605, −0.240, 0.000, 0.102])
A2 Place(cupB, placeForcupBingoal1Region, goal1Region, MotionPose(0.605, −0.240, 0.000, 0.102])
A0 Pick(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.790, −0.219, 0.000, 0.102])
A2 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, MotionPose(0.790, −0.219, 0.000, 0.102])
A0 MoveRobotConf base Pose(0.804, −0.217, 0.000, 0.102])
A2 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, MotionPose(0.804, −0.217, 0.000, 0.102])
A0 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.605, −0.240, 0.000, 0.102])
A2 Place(cupA, placeForcupAingoal2Region, goal2Region, MotionPose(0.605, −0.240, 0.000, 0.102])
Plan 6
ClearXsweptcupB7513armSwept, (cupB, cupA)
PoseAt(cupA, placeForcupAinwarehouse_91051, warehouse)
Plan 14
CanReach(cupB, Conf base Pose(0.605, −0.240, 0.000, 0.102])
ClearXsweptcupB8211armSwept, (cupB)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 21
ClearXsweptcupA11610armSwept, (cupA, cupB)
PoseAt(cupB, placeForcupBinwarehouse_96377, warehouse)
Plan 28
CanReach(cupA, Conf base Pose(0.804, −0.217, 0.000, 0.102])
ClearXsweptcupA1327armSwept, (cupA)
Holding(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 33
CanReach(cupA, Conf base Pose(0.804, −0.217, 0.000, 0.102])
ClearXsweptcupA1327armSwept, (cupA)
ConfAttConf base Pose(0.804, −0.217, 0.000, 0.102], True)
Holding(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 34
CanReach(cupB, Conf base Pose(0.605, −0.240, 0.000, 0.102])
ClearXsweptcupB14320armSwept, (cupB)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
PoseAt(cupA, placeForcupAingoal2Region, 94830, goal2Region)
Plan 37
CanReach(cupB, Conf base Pose(0.605, −0.240, 0.000, 0.102])
ClearXsweptcupB14320armSwept, (cupB)
ConfAttConf base Pose(0.605, −0.240, 0.000, 0.102], True)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
PoseAt(cupA, placeForcupAingoal2Region, 94830, goal2Region)
A0 Place(cupB, placeForcupBingoal1Region, goal1Region, ?)
PoseAt(cupA, placeForcupAingoal2Region, 94830, goal2Region)
PoseAt(cupB, placeForcupBingoal1Region, 98538, goal1Region)
A0 Pick(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.790, −0.219, 0.000, 0.102])
A2 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, MotionPose(0.790, −0.219, 0.000, 0.102])
A0 MoveRobotConf base Pose(0.636, −0.574, 0.000, 0.102])
A2 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, MotionPose(0.636, −0.574, 0.000, 0.102])
A0 Pick(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.605, −0.240, 0.000, 0.102])
A2 Place(cupB, placeForcupBingoal1Region, goal1Region, MotionPose(0.605, −0.240, 0.000, 0.102])
Plan 7
ClearXsweptcupB7513armSwept, (cupB, cupA)
PoseAt(cupA, placeForcupAinwarehouse_91051, warehouse)
Plan 15
CanReach(cupB, Conf base Pose(0.605, −0.240, 0.000, 0.102])
CanReach(cupB, Conf base Pose(0.790, −0.219, 0.000, 0.102])
ClearXsweptcupB8211armSwept, (cupB)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
ConfAttConf base Pose(0.790, −0.219, 0.000, 0.102], True)
Holding(None, None)
PoseAt(cupB, cupB)[1.600, −0.100, 0.690, 3.242], somewhere)
Plan 22
ClearXsweptcupA11610armSwept, (cupA, cupB)
PoseAt(cupB, placeForcupBinwarehouse_96377, warehouse)
Plan 29
CanReach(cupA, Conf base Pose(0.636, −0.574, 0.000, 0.102])
CanReach(cupA, Conf base Pose(0.804, −0.217, 0.000, 0.102])
ClearXsweptcupA1327armSwept, (cupA)
Holding(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
ConfAttConf base Pose(0.636, −0.574, 0.000, 0.102], True)
Holding(None, None)
PoseAt(cupA, cupA)[1.446, −0.456, 0.695, 3.242], somewhere)
Plan 35
CanReach(cupB, Conf base Pose(0.605, −0.240, 0.000, 0.102])
ClearXsweptcupB14320armSwept, (cupB)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
PoseAt(cupA, placeForcupAingoal2Region, 94830, goal2Region)
Plan 38
CanReach(cupB, Conf base Pose(0.605, −0.240, 0.000, 0.102])
ClearXsweptcupB14320armSwept, (cupB)
ConfAttConf base Pose(0.605, −0.240, 0.000, 0.102], True)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
PoseAt(cupA, placeForcupAingoal2Region, 94830, goal2Region)
A0 Place(cupA, placeForcupAinwarehouse, warehouse, ?)
A1 Init(cupA, warehouse)
A0 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.636, −0.574, 0.000, 0.102])
A2 Place(cupA, placeForcupAinwarehouse, warehouse, MotionPose(0.636, −0.574, 0.000, 0.102])
A0 Pick(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.651, −0.723, 0.000, 0.102])
A2 Place(cupB, placeForcupBinwarehouse, warehouse, MotionPose(0.651, −0.723, 0.000, 0.102])
A0 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.651, −0.723, 0.000, 0.102])
A2 Place(cupA, placeForcupAinwarehouse, warehouse, MotionPose(0.651, −0.723, 0.000, 0.102])
A0 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.651, −0.723, 0.000, 0.102])
A2 Pick(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, MotionPose(0.651, −0.723, 0.000, 0.102])
A0 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.651, −0.723, 0.000, 0.102])
A2 Pick(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, MotionPose(0.651, −0.723, 0.000, 0.102])
Plan 8
CanReach(cupA, Conf base Pose(0.636, −0.574, 0.000, 0.102])
ClearXsweptcupA808SarmSwept, (cupA)
Holding(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 11
CanReach(cupA, Conf base Pose(0.636, −0.574, 0.000, 0.102])
ClearXsweptcupA808SarmSwept, (cupA)
ClearXsweptcupB7513armSwept, (cupB, cupA)
ConfAttConf base Pose(0.636, −0.574, 0.000, 0.102], True)
Holding(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 23
CanReach(cupB, Conf base Pose(0.651, −0.723, 0.000, 0.102])
ClearXsweptcupA11610armSwept, (cupA, cupB)
ClearXsweptcupB13150armSwept, (cupB)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 25
CanReach(cupB, Conf base Pose(0.651, −0.723, 0.000, 0.102])
ClearXsweptcupA11610armSwept, (cupA, cupB)
ClearXsweptcupB13150armSwept, (cupB)
ConfAttConf base Pose(0.651, −0.723, 0.000, 0.102], True)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 36
CanReach(cupB, Conf base Pose(0.605, −0.240, 0.000, 0.102])
CanReach(cupB, Conf base Pose(0.651, −0.723, 0.000, 0.102])
ClearXsweptcupB14320armSwept, (cupB)
ClearXsweptcupB14366armSwept, (cupB)
ConfAttConf base Pose(0.651, −0.723, 0.000, 0.102], True)
Holding(None, None)
PoseAt(cupA, placeForcupAingoal2Region, 94830, goal2Region)
PoseAt(cupB, cupB)[1.461, −0.604, 0.691, 3.242], somewhere)
A0 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.651, −0.723, 0.000, 0.102])
A2 Pick(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, MotionPose(0.651, −0.723, 0.000, 0.102])
A0 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, ?)
A0 MoveRobotConf base Pose(0.591, −0.239, 0.000, 0.102])
A2 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, MotionPose(0.591, −0.239, 0.000, 0.102])
Plan 9
CanReach(cupA, Conf base Pose(0.636, −0.574, 0.000, 0.102])
ClearXsweptcupA808SarmSwept, (cupA)
ClearXsweptcupB7513armSwept, (cupB, cupA)
Holding(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
Plan 24
CanReach(cupB, Conf base Pose(0.651, −0.723, 0.000, 0.102])
ClearXsweptcupA11610armSwept, (cupA, cupB)
ClearXsweptcupB13150armSwept, (cupB)
Holding(cupB, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062)
A0 MoveRobotConf base Pose(0.591, −0.239, 0.000, 0.102])
A2 Pick(cupA, Grasp Pose(0.214, 0.000, 0.116, 3.142],grip=0.062, MotionPose(0.591, −0.239, 0.000, 0.102])
Pick(cupA)
Plan 10
CanReach(cupA, Conf base Pose(0.591, −0.239, 0.000, 0.102])
CanReach(cupA, Conf base Pose(0.636, −0.574, 0.000, 0.102])
ClearXsweptcupA805SarmSwept, (cupA)
ClearXsweptcupA808SarmSwept, (cupA)
ClearXsweptcupB7513armSwept, (cupB, cupA)
ConfAttConf base Pose(0.591, −0.239, 0.000, 0.102], True)
Holding(None, None)
PoseAt(cupA, cupA)[1.401, −0.120, 0.690, 3.242], somewhere)
A1 MoveRobotConf base Pose(0.591, −0.239, 0.000, 0.102])
MoveRobotPose(0.591, −0.239, 0.000, 0.102])
A1 MoveRobotConf base Pose(0.636, −0.574, 0.000, 0.102])
MoveRobotPose(0.636, −0.574, 0.000, 0.102])
A1 MoveRobotConf base Pose(0.790, −0.219, 0.000, 0.102])
MoveRobotPose(0.790, −0.219, 0.000, 0.102])
A1 MoveRobotConf base Pose(0.605, −0.240, 0.000, 0.102])
MoveRobotPose(0.605, −0.240, 0.000, 0.102])
A1 MoveRobotConf base Pose(0.804, −0.217, 0.000, 0.102])
MoveRobotPose(0.804, −0.217, 0.000, 0.102])
A1 MoveRobotConf base Pose(0.636, −0.574, 0.000, 0.102])
MoveRobotPose(0.636, −0.574, 0.000, 0.102])
A1 MoveRobotConf base Pose(0.605, −0.240, 0.000, 0.102])
MoveRobotPose(0.605, −0.240, 0.000, 0.102])
A1 MoveRobotConf base Pose(0.651, −0.723, 0.000, 0.102])
MoveRobotPose(0.651, −0.723, 0.000, 0.102])
PlaceInPlaceforcupBingoal1Region(98538)
PlaceInPlaceforcupBingoal1Region(94471)
PlaceInPlaceforcupAingoal2Region(94830)
PlaceInPlaceforcupAinwarehouse(91051)
PlaceInPlaceforcupBinwarehouse(96377)
Pick(cupB)
Pick(cupA)
Pick(cupB)
Pick(cupA)
Pick(cupB)
Pick(cupA)
Pick(cupB)