



Corrigendum: Task Roadmaps: Speeding Up Task Replanning

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A Corrigendum on

Task Roadmaps: Speeding Up Task Replanning

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In the original article, **Listings 1** and **2** were not included during the typesetting process and were overlooked during production. The missing listings appear below.

Listing 1. PDDL domain

```

(define (domain RTSG)
  (:types
    node - object
    task logical andjoin2 - node
    startcond goalcond robtask - task
    andfork orfork orjoin - logical
    nofork - orfork)
  (:predicates
    (edge ?n1 ?n2 - node)
    (orfork-branch ?orf - orfork ?to - node)
    (not-locked ?from ?to - task)
    (andjoin2=inputs ?n1 ?n2 - node)
    (fired ?n - node)
    (latest-completed ?t - task)
    (branch-not-selected ?orf - orfork))
  (:functions
    (cost ?from ?to - task))
  (:durative-action RUN-TASK
    :parameters (?this ?prev - task ?input - node ?orf - orfork)
    :duration (= ?duration (cost ?prev ?this))
    :condition (and
      (at start (latest-completed ?prev))
      (at start (edge ?input ?this))
      (at start (fired ?input))
      (at start (orfork-branch ?orf ?this))
      (at start (branch-not-selected ?orf))
      (at start (not-locked ?prev ?this)))
    :effect (and
      (at start (not (latest-completed ?prev)))
      (at start (not (branch-not-selected ?orf)))
      (at end (latest-completed ?this))
      (at end (fired ?this)))
    (:durative-action FIRE-LOGICAL
      :parameters (?this - logical ?input - node ?orf - orfork)
      :duration (= ?duration 0)
      :condition (and
        (at start (edge ?input ?this))
        (at start (fired ?input))
        (at start (orfork-branch ?orf ?this))
        (at start (branch-not-selected ?orf)))
      :effect (and
        (at start (not (branch-not-selected ?orf)))
        (at end (fired ?this)))
    (:durative-action FIRE-ANDJOIN2
      :parameters (?this - andjoin2 ?input1 ?input2 - node ?orf - orfork)
      :duration (= ?duration 0)
      :condition (and
        (at start (edge ?input1 ?this))
        (at start (edge ?input2 ?this))
        (at start (fired ?input1))
        (at start (fired ?input2))
        (at start (andjoin2=inputs ?input1 ?input2))
        (at start (orfork-branch ?orf ?this))
        (at start (branch-not-selected ?orf)))
      :effect (and
        (at start (not (branch-not-selected ?orf)))
        (at end (fired ?this))))))

```

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Listing 2. PDDL problem

```

(define (problem RTSG-config)
  (:domain RTSG)
  (:objects
    s - startcond
    g - goalcond
    af1 - andfork
    aj1 aj2 - andjoin2
    of1 - orfork
    oj1 - orjoin
    ta tb tc td te tf - robtask
    nfs nfg ... nftd - nofork ; Dummy objects
  )
  (:init
    ; Static facts
    (edge s af1)
    (edge af1 ta) ... (edge aj2 g)
    (not-locked s ta) ... (not-locked tf g)
    (andjoin2-inputs ta tb)
    (andjoin2-inputs oj1 td)
    (orfork-branch of1 te)
    (orfork-branch of1 tf)
    (orfork-branch nfs s) ; Dummy fact
    ... ; ...
    (orfork-branch nfg g) ; Dummy fact
    ; Dynamic facts
    (fired s)
    (latest-completed s)
    (branch-not-selected of1)
    (branch-not-selected nfs) ; Dummy fact
    ... ; ...
    (branch-not-selected nftd) ; Dummy fact
    (= (cost s ta) 100) ... (= (cost tf g) 100))
  (:goal (fired g))
  (:metric minimize total-time)
)

```

The authors apologize for this error and state that this does not change the scientific conclusions of the article in any way. The original article has been updated.

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