

Name: Open (General)  
Participants: agent, obj  
AppCond: exist(agent) && exist(obj) && defined(Open, obj) && know(agent, Open)  
PrepSpec: {reachable(agent, obj), locomote(agent, obj)} //remote controls? Check object  
TermCond: posture(obj, Open) //or status  
PostAssert: location(agent, obj) && posture(obj, Open)  
DuringCond: opening(agent, obj)  
Purpose: open(agent, obj)  
Subactions: none //assuming atomic action  
ParentAction:?

Name: Open (Specific and Complex)  
Participants: Performer, Printer.Top\_cover, Printer.Front\_cover  
Subactions: Open(Performer, Printer.Top\_cover) &&  
Open(Performer, Printer.Front\_cover) (sequential) //just to eliminate resource issues  
ParentAction: Open (General)

Name: Open (Specific to Top\_cover)  
Participants: Performer, Printer.Top\_cover  
PrepSpec: default && {opened(Printer.Duplex\_unit), Open(Printer.Duplex\_unit)} &&  
{Unlatched(Printer.Slide\_latch), Operate(Performer, Printer.Slide\_latch)}  
ParentAction: Open

Notes:

1. Spatial reasoning needed in PrepSpecs.
2. Possible failure if not room to open.
3. Does the performer need to see the slide latch? Not in our system.
4. It will be good to have the objects and possibly agents add to the preparatory specifications.
5. Where does Open fit in the Actionary hierarchy?