# Towards Integrated Self-Maintenance in Domestic Robots

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**Keynote Address**

**Abstract:** In order for a robot to execute a given high-level program or plan more robustly we want to enable it to take care of its own self-maintenance requirements like making sure that the arm is calibrated before use. This requires the robot to know about the (internal) states of its components, constraints that restrict execution of certain actions and possibly also how to recover from faulty situations. Our approach is to specify constraints based on Allen's interval algebra and to transform a robot program written in the action language Golog so that the constraints will be met during execution.