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(* equal contribution)

Robotics for Chemistry

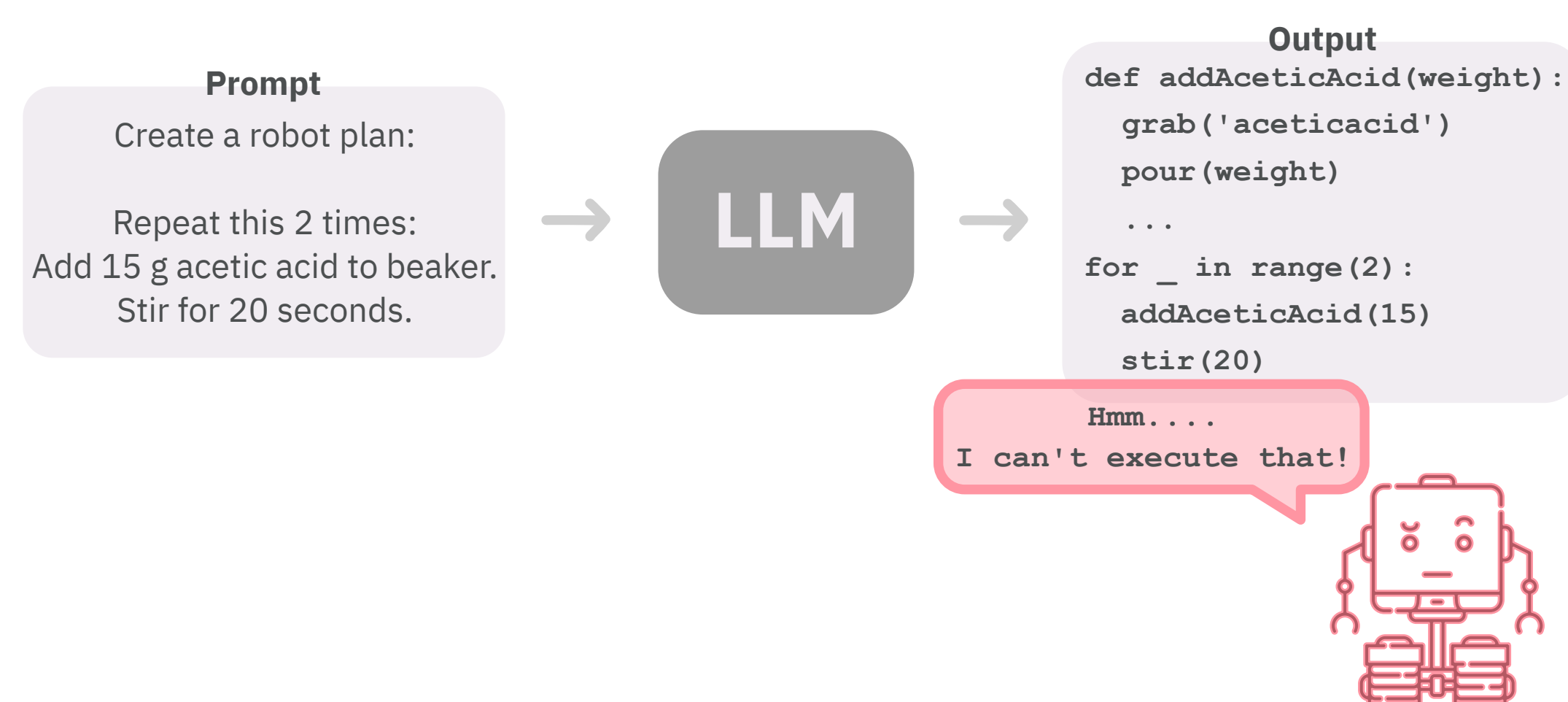
- Self-driving labs can accelerate molecular discovery¹
- Translating experiments from natural language to low level robotics language is nontrivial
- Large language models (LLMs) are able to generate structured outputs like code²
- Can we use LLMs for planning chemistry experiments?

Chemistry experiment
Repeat this 2 times:
Add 15 g acetic acid
to beaker. Stir for 20s.

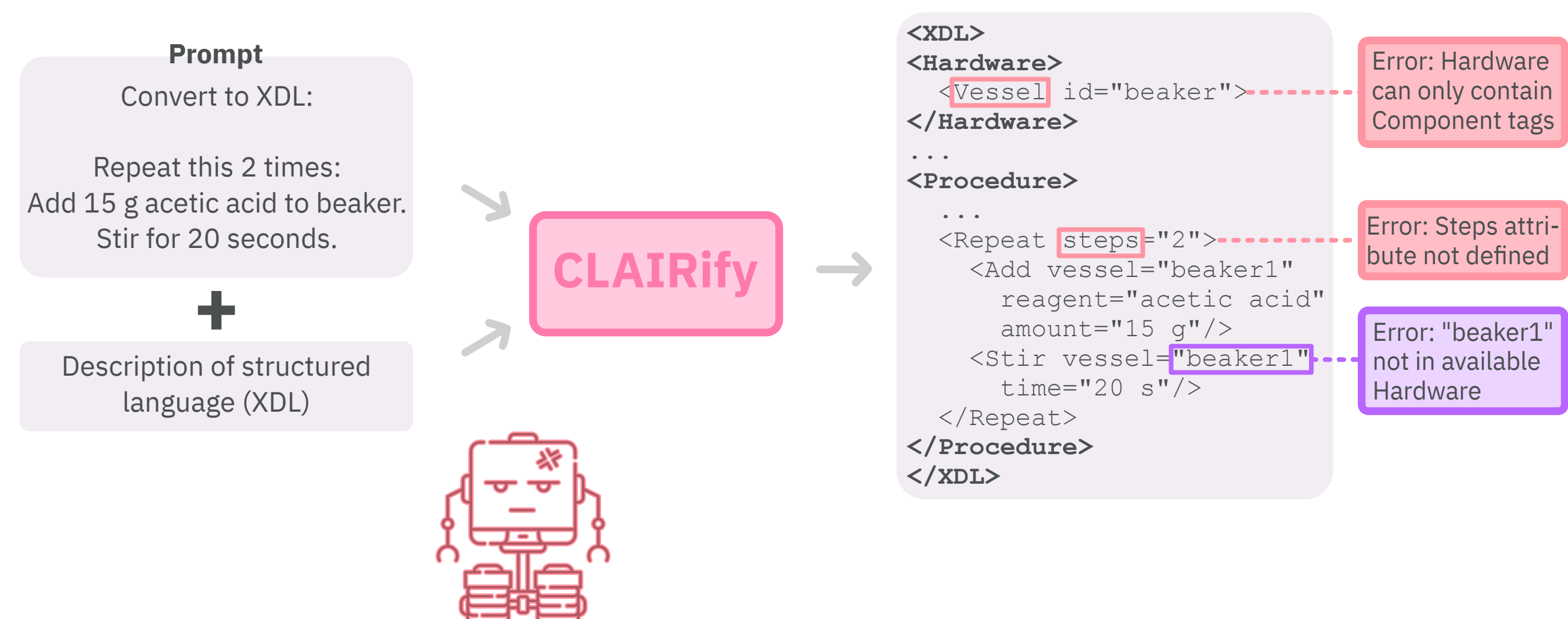


Problems with using LLMs for task plan generation

[1] **Poor performance for data-scarce domain-specific languages (DSLs)** --> for XDL, a language used in robotics for chemistry lab automation, vanilla zero-shot prompting of LLMs produces erroneous task plans.



[2] **Lack of task plan verification** --> generated task plans might be syntactically incorrect and/or incorporate resources not present in the environment.



References

- [1] M. Seifrid, et al., Autonomous chemical experiments: Challenges and perspectives on establishing a self-driving lab. *Acc. Chem. Res.*, 2022.
- [2] I. Singh, et al., "Progprompt: Generating situated robot task plans using large language models," in *IEEE Int. Conf. Robot. Autom.*, 2023.
- [3] N. Yoshikawa, et al., "An adaptive robotics framework for chemistry lab automation," *arXiv:2212.09672*, 2022.
- [4] S. H. M. Mehr, et al., "A universal system for digitization and automatic execution of the chemical synthesis literature," *Science*, vol. 370, no. 6512, pp. 101-108, 2020.

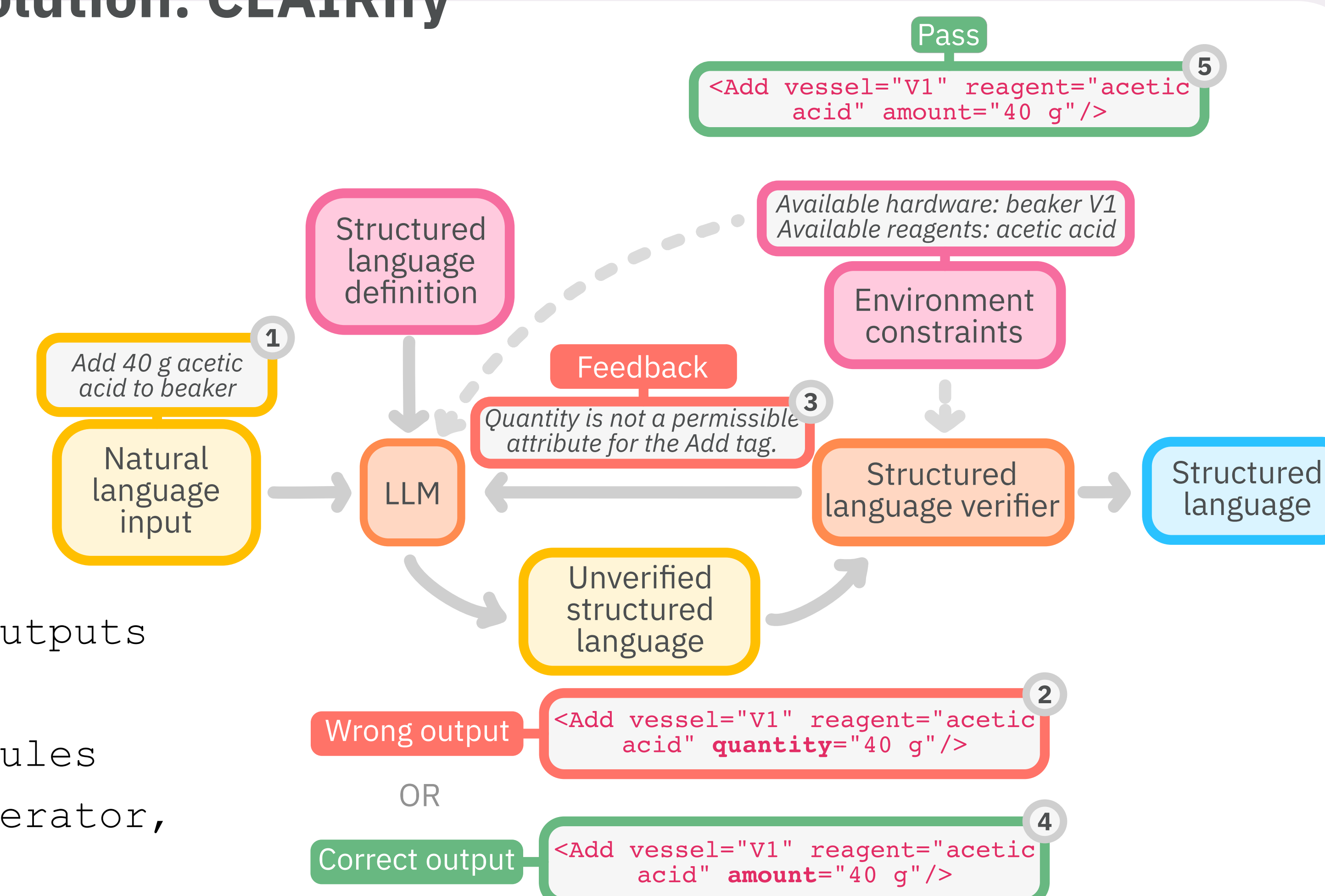
Our solution: CLAIRify

- CLAIRify is a **framework** that translates natural language into a domain-specific structured task plan using an **automated iterative verification** technique to ensure the plan is syntactically valid in the target DSL. It also **takes into account environment constraints** if provided.

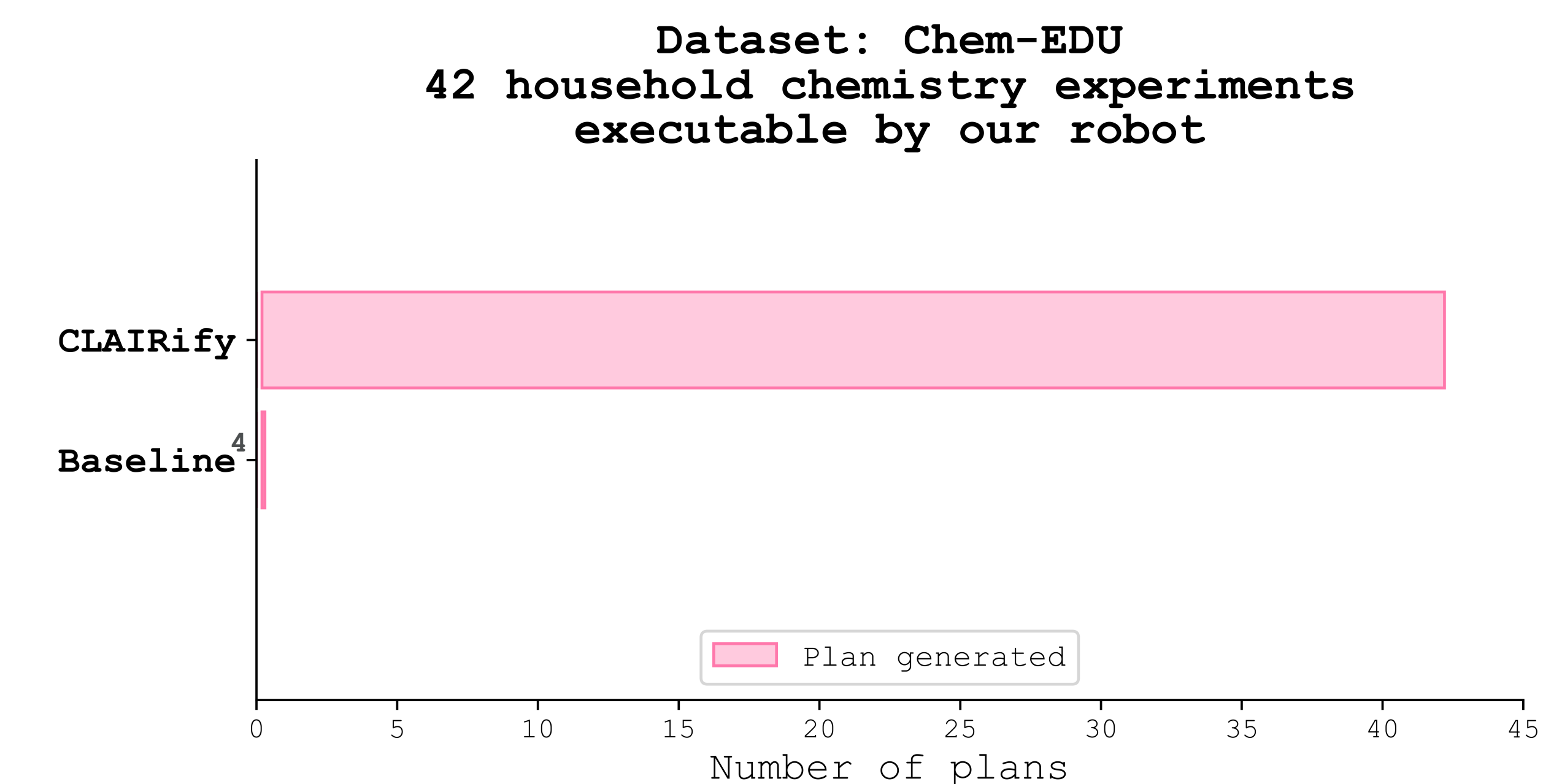
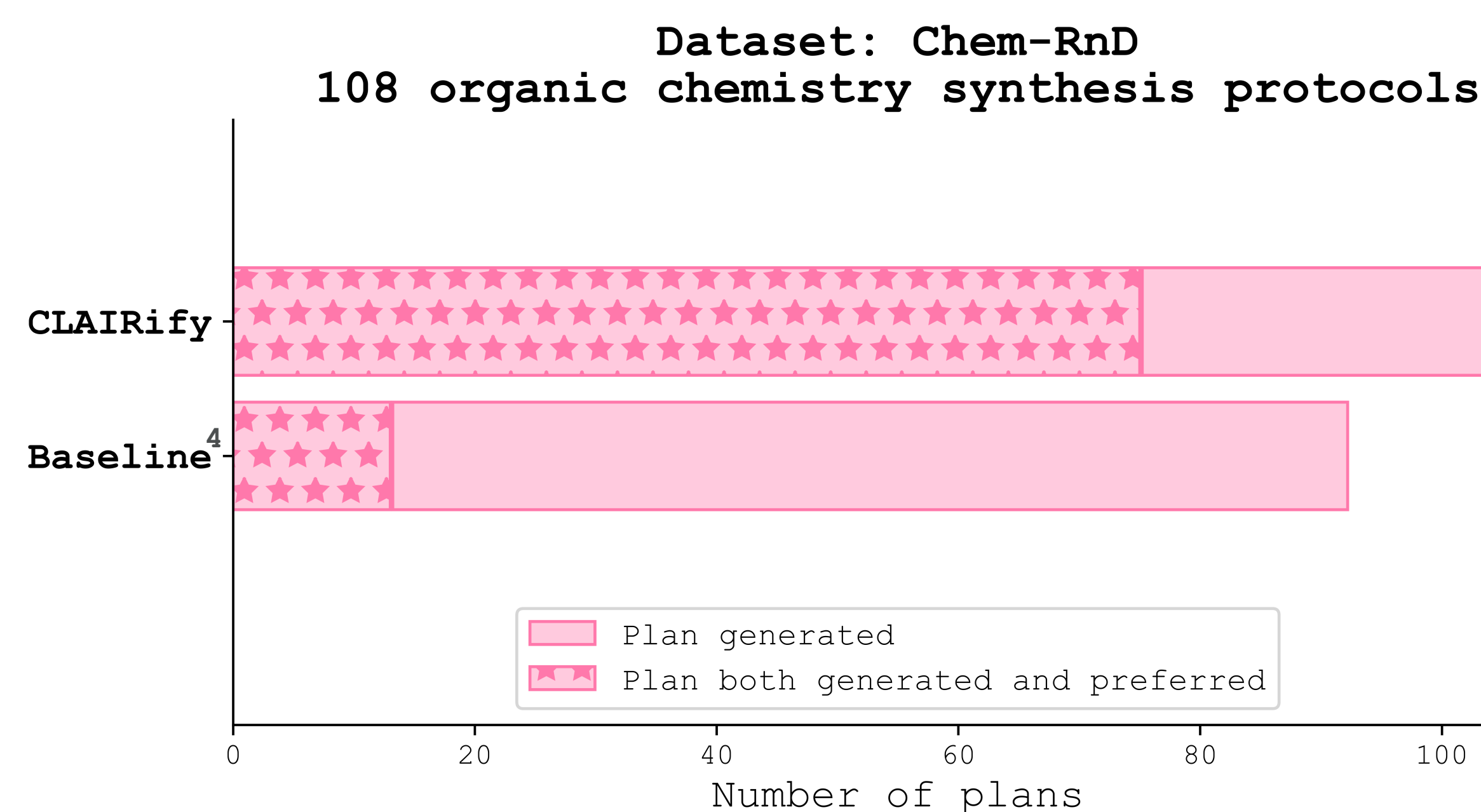
- It consists of two parts:

- [1] **Generator** which takes in DSL rules & natural language instruction, and outputs unverified structured language
- [2] **Verifier** which checks whether DSL rules are followed; returns feedback to Generator, which re-generates task plan

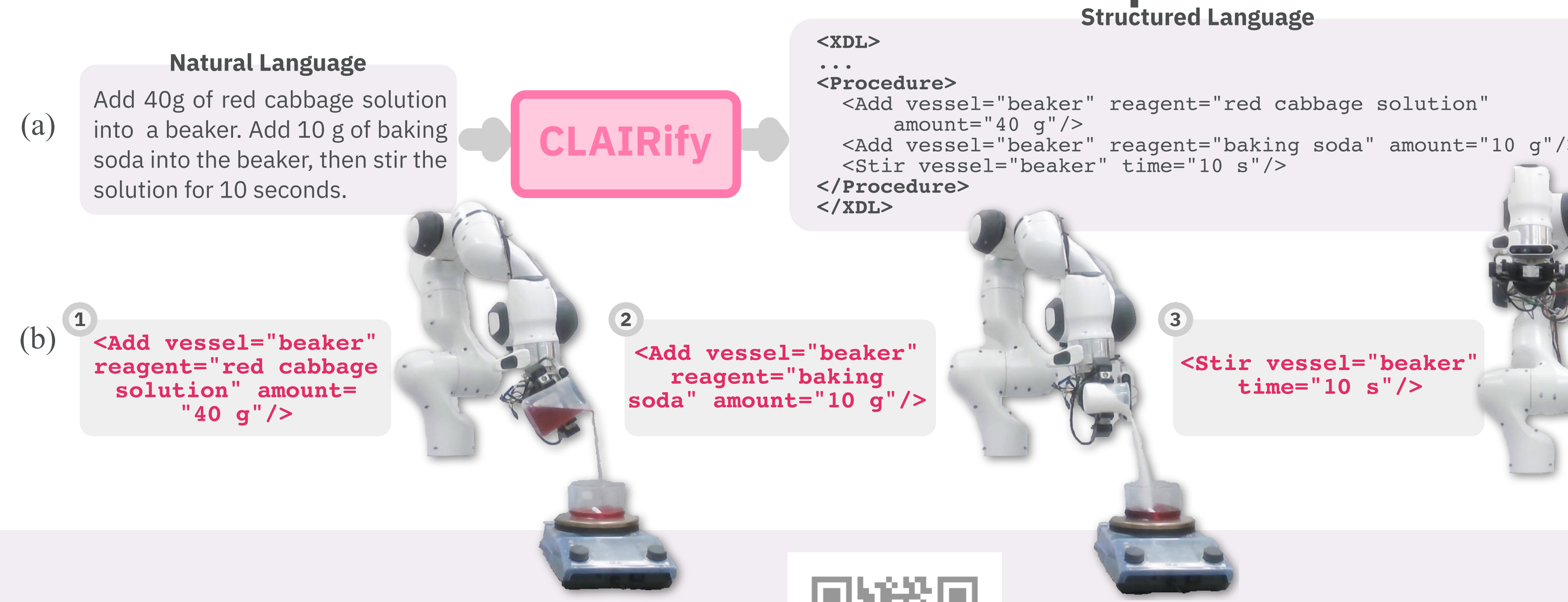
- To map the plan to robot actions, we use a **Task and Motion Planner**



Experiments & Results



Real-world Robotics Experiments



OUR WEBSITE

<https://ac-rad.github.io/clairify/>



ARXIV PAPER

<https://arxiv.org/pdf/2303.14100>



DEMO

<https://clairify.matter.toronto.edu/moml2023/>