Goal:
The goal of this exercise is to help you practice implementing Behaviors as Finite State Machines in the Tekkotsu framework.

Detail:
You are to use a FSM to implement a task similar to HW2. The original assignment can be found on the class web page. In this assignment, the three conditions to stop the walk should not be cumulative (e.g. a head button press should be ignored if the AIBO is off the ground already). In the spirit of all of the previous exercises, the focus here is meant to be on the Tekkotsu portion of the assignment, not on brain teasing algorithms. If the automata is constructed correctly, the program should almost write itself.

Hints:
• Begin by reviewing the requirements for HW2.
• List the key states and transitions on paper, and create a diagram of your FSM in order to get a clear view of how your nodes and transitions fit together.
• For an example of how to implement a FSM inside Tekkotsu, take a look at ExploreMachine, lecture notes, and Tekkotsu API/reference pages.
• Use WalkNodes for walking and stopping.
• Use the FSM viewer to watch/debug your FSM. (I will use it for grading.)
• SmoothCompareTrans can be used for transitions based on sensor readings.
  • There should be no need to write a custom transition (although you may).