Start

    Input power to robot

    Input walk that correctly uses walk technique of alternating legs

    Input robot body rotation 360° so robot can face any direction allowing to walk any direction

    Input standing from a seating position as well as sitting from a standing position

    Process stand up

    Process robot to rotate towards direction needed to walk to chair

    Process walking the distance required for the robot to be centered with chair to sit

    Process rotate robot back to position needed for correct sitting position

    Decision if robot can sit

    Output robot sit

    Output robot power off

    Else reposition robot to correct position to fulfill task

    Recheck Decision

    Output robot sit

    Output robot power off

Stop