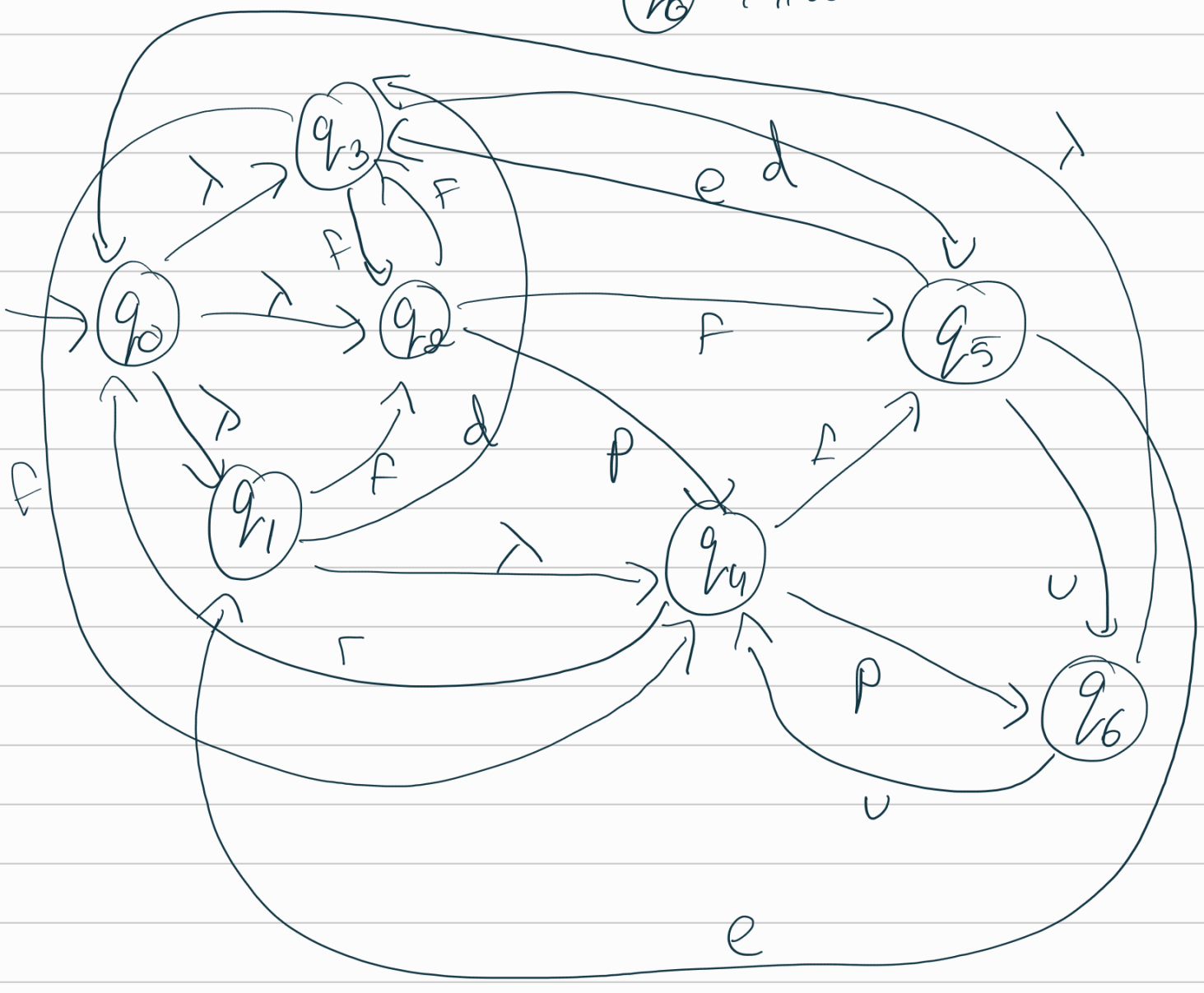
λ - NFA care modelează traseul unui robot într-o fabrică / un depozit

- f(ollow) path
- d(etect) obstacle
- p(ick) object
- r(eturn) to dock
- v(alidate) object
- e(rror)

- q_0 : dock
- q_1 : hall A
- q_2 : hall B
- q_3 : hall C
- q_4 : packing zone
- q_5 : CP
- q_6 : finalize task



	f	d	p	r	v	e
q_0	q_{12345}	q_5	q_4	q_ϕ	q_ϕ	q_ϕ
q_1	q_{25}	q_3	q_6	q_0	q_α	q_α
q_2	q_{35}	q_α	q_4	q_α	q_α	q_α
q_3	q_{24}	q_5	q_α	q_ϕ	q_ϕ	q_ϕ
q_4	q_5	q_ϕ	q_{06}	q_{023}	q_ϕ	q_ϕ
q_5	q_ϕ	q_ϕ	q_ϕ	q_ϕ	q_{0236}	q_{13}
q_6	q_{12345}	q_5	q_4	q_ϕ	q_4	q_ϕ

q_{12345}	q_{2345}	q_{35}	q_{046}	q_{023}	q_{0236}	q_{13}
q_{25}	q_{35}		q_4		q_{0236}	q_{13}
q_{35}	q_{24}	q_5			q_{0236}	q_{13}
q_{24}	q_{35}		q_{046}	q_{023}		
q_{06}	q_{12345}	q_5	q_4		q_4	
q_{023}	q_{12345}	q_5	q_4			
q_{0236}	q_{12345}	q_5	q_4		q_4	
q_{13}	q_{245}	q_{35}	q_6			
q_{245}	q_{35}		q_{046}		q_{0236}	q_{13}
q_{046}	q_{12345}	q_5	q_{046}	q_{023}	q_4	
q_{12345}	q_{2345}	q_5	q_{046}	q_{023}	q_{0236}	q_{13}