```python
def behave(self, sensors, motor):
    # State transition
    if self.t_follow > 1.0:
        self.follow_obstacle *= 0.5
    elif sensors.hit_obstacle():
        self.follow_obstacle += 1.0 * self.dt_coarse
    else:
        self.follow_obstacle -= self.follow_obstacle * self.dt_coarse

    # Behaviour implementation
    if self.follow_obstacle > 0.25:
        common.follow_obstacle(sensors, motor, self.radius)
        self.t_follow += self.dt_coarse
    else:
        self.t_follow = 0
        common.move_towards_goal(sensors, motor)
```