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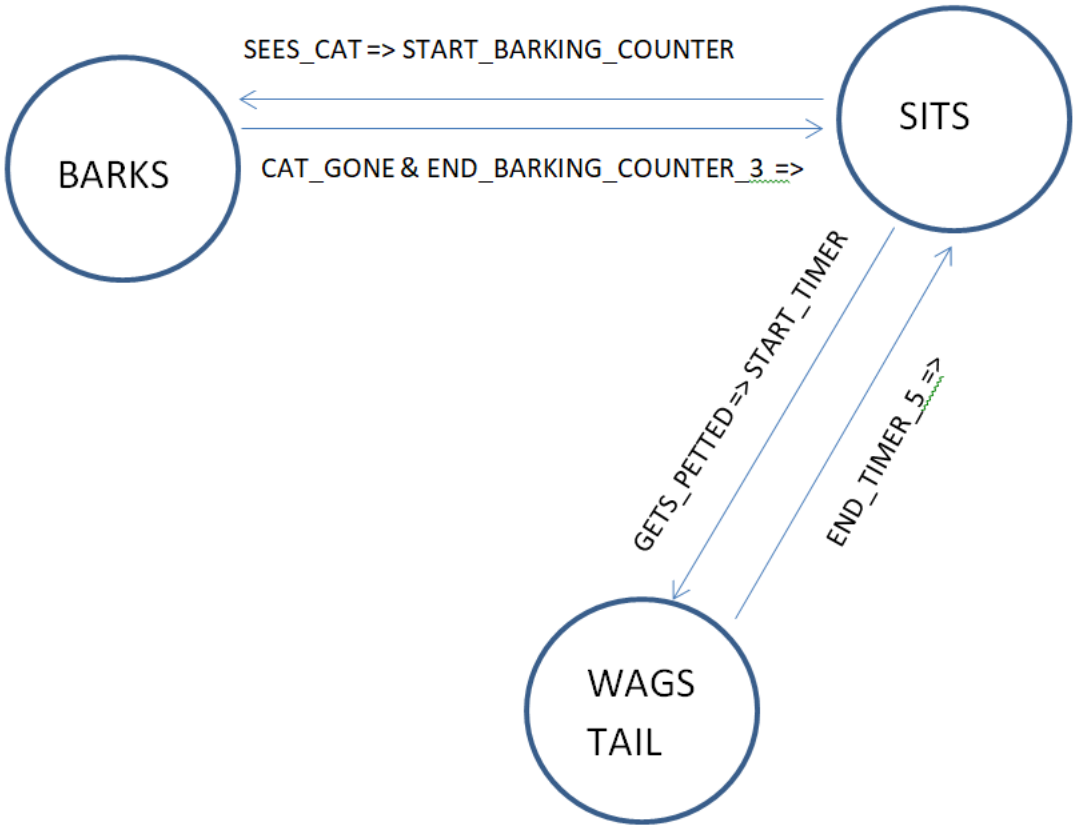

FSM = (I, O, S, r, δ, λ)

I = {SEES_CAT, CAT_GONE, END_BARKING_COUNTER_3, GETS_PETTED, END_TIMER_5}

O = {START_BARKING_COUNTER, START_TIMER}

S = {SITS, BARKS, WAGGS_TAIL}

r = {SITS}

δ: IxS→S –state transition function

e.g. ({SEES_CAT}, SITS) = BARKS

λ: IxS→O –output function

e.g. ({SEES_CAT}, SITS) = {START_BARKING_COUNTER}