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Lab 9 Submission

Finite State Machine (FSM):

- I modified the provided **Finite State Machine (FSM)** to control the robot's movement through different phases.
- The FSM has the following states:
 - **AT_START**
 - **MOVE_SQUARE**
 - **MOVE_TRIANGLE**
 - **RETURNING_FROM_TASK**
 - **TASK_DONE**

Movement Paths:

- I defined two paths for the robot to follow: a **square** and a **triangle** and stored the waypoints in two variables, **points_square** and, **points_triangle**. The lists holds the points and orientation the robot needs to follow for the respective path.

FSM Logic:

- In the **MOVE_SQUARE** state, the robot moves through the points defined in **points_square**.
- Once the square path is completed, the FSM transitions to **MOVE_TRIANGLE**.
- After completing the triangle, the robot returns to the start in the **RETURNING_FROM_TASK** state, then reaches the **TASK_DONE** state.

Video is provided with the submission and Screenshots are below:



