Note, I think I am just going to have all the variables held in the state node, and the only pointers will be to the Navigate_to state setup.

If something is in Fido's way when it is on the stop back home it doesn't matter, we will stop back, recalibrate path from where he is to home, and go, if the stop is still in the way it will bark again, and continue doing this till the object is not in the way anymore.

Wait for more command
Constructor: ConstructorBaby(MonkeyAnd/orOffice, Fido)]

Different reactions depending on the type of interaction. If someone gets it to work righting, it will sound some sort of alarm.

Fido's current location is updated to where he is at, so upon the next movement he will walk from whatever he is to the correct place.

If we get to it's visual recognition of human

Completion Event
Wait for further instructions

Navigate_toHome()}