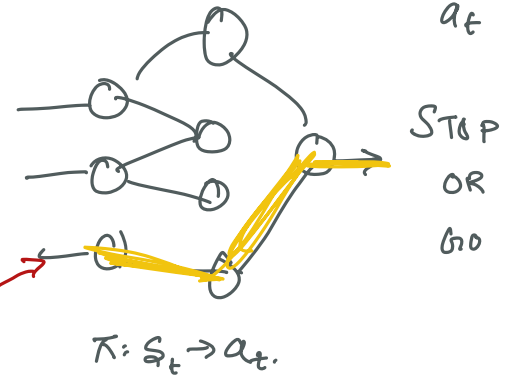


INPUT
(STATE) s_t

- TRAFFIC LIGHT STATE
- LOCATION OF OTHER ACTOR
- ROBOT STATE
 - Dis from light
 - Speed.
- **PREVIOUS ACTION**

OUTPUT
(ACTION) a_t



$\pi: s_t \rightarrow a_t$