

Ego-vehicle

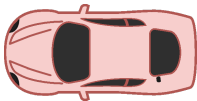
Unimodal Predictions

$S_{\text{pred},t} = \text{State}$

Drive, Stop

$A_t = \text{Actions}$

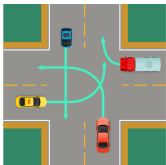
$\pi(s)$



R_t

Motion
Prediction

SMARTS



+



SUMO
SIMULATION OF URBAN MOBILITY

Environment

R_{t+1}

$S_{\text{obs},t+1}$