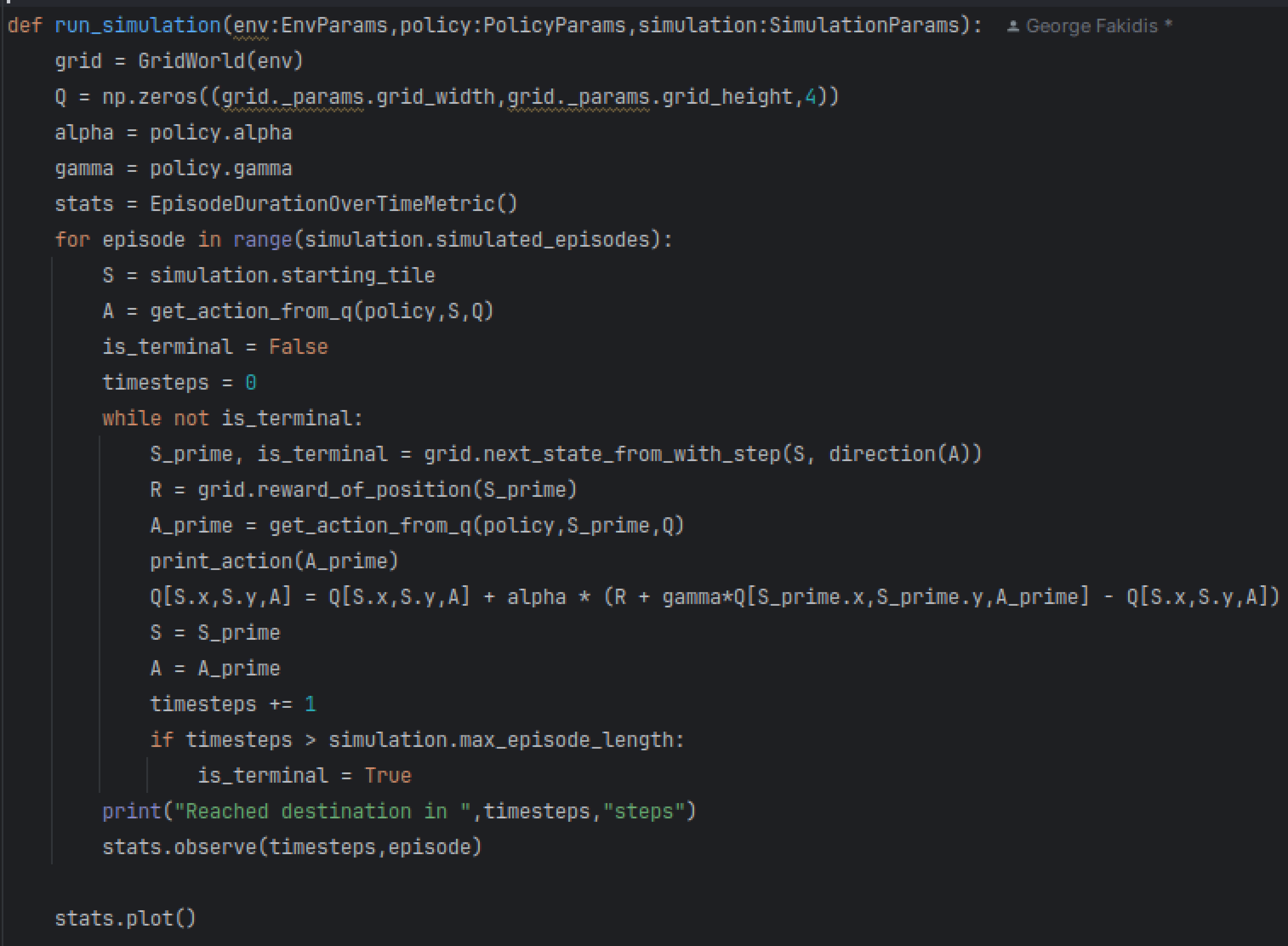

```python
def run_simulation(env:EnvParams,policy:PolicyParams,simulation:SimulationParams):
    grid = GridWorld(env)
    Q = np.zeros((grid._params.grid_width,grid._params.grid_height,4))
    alpha = policy.alpha
    gamma = policy.gamma
    stats = EpisodeDurationOverTimeMetric()
    for episode in range(simulation.simulated_episodes):
        S = simulation.starting_tile
        A = get_action_from_q(policy,S,Q)
        is_terminal = False
        timesteps = 0
        while not is_terminal:
            S_prime, is_terminal = grid.next_state_from_with_step(S, direction(A))
            R = grid.reward_of_position(S_prime)
            A_prime = get_action_from_q(policy,S_prime,Q)
            print_action(A_prime)
            Q[S.x,S.y,A] = Q[S.x,S.y,A] + alpha * (R + gamma*Q[S_prime.x,S_prime.y,A_prime] - Q[S.x,S.y,A])
            S = S_prime
            A = A_prime
            timesteps += 1
            if timesteps > simulation.max_episode_length:
                is_terminal = True
        print("Reached destination in ",timesteps,"steps")
        stats.observe(timesteps,episode)

    stats.plot()
```