Input:

    Map = [['G', 'G', 'G'],

        ['G', 'R', 'R'],

        ['G', 'G', 'G']]

    measurements = ['R','R']

    motions = [[0,0],[0,1]]

    sensor_right = 1.0

    p_move = 1.0

Output:

    [[0.00000,0.00000,0.00000],

     [0.00000,0.00000,1.00000],

     [0.00000,0.00000,0.00000]]

    [0. 0. 0.]