Navigation Algorithms

**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.]