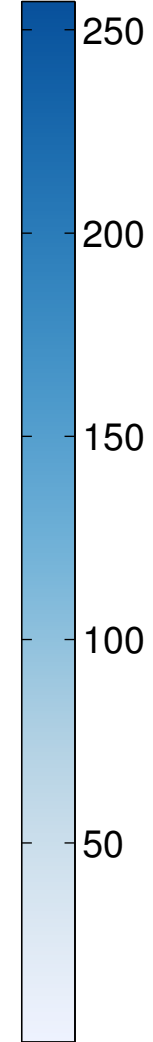
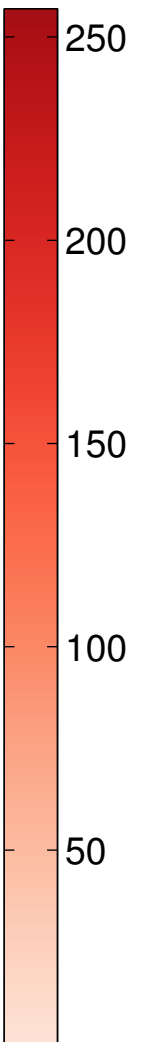


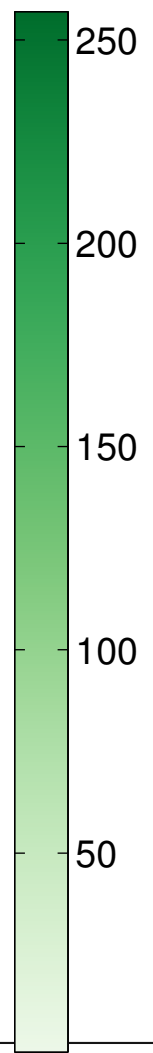
Agent  $P(A_t)$




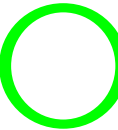


Object(1)  $P(O^{(1)})$



Object(2)  $P(O^{(2)})$



-  Agents position
-  Object(1) position
-  Object(2) position
-  range of Agents perception