**Adjusted Analysis Approach**

Since observed starting states can't be derived, here's the revised interpretation:

1. The robot’s movement depends on its transition probabilities (to be analyzed later). Starting states are tied to the sequence structure implied by these transitions.
2. The dominant learned start probability in both tasks likely reflects the reward distribution and transition dynamics that the model optimizes during training.
3. Task 15's start probabilities can be considered **more reliable** because true transition probabilities stabilize the learning process.