```
#================================first step:Parking decision=============================================
global image;
camera_sensor.listen(lambda image: parking_decision(image));

def parking_decision(data):
 camera_sensor.stop();
 cameraControl = carla.VehicleControl(throttle=0);
 vehicle.apply_control(cameraControl);
 output=interface.decision(data);
 overlapRatio = output['result'];
 print('the rate of Overlap:', overlapRatio);
 if overlapRatio < 0.1:
   print('the parking place is between the next 2 cars');
   parking_preparation();
 else:
   print('no parking place has been detected right now');
   cameraControl = carla.VehicleControl(throttle=0.5);
   vehicle.apply_control(cameraControl);
   print('car is moving');
   camera_sensor.listen(lambda image: parking_decision(image)); #camera-sensor's called iteratively
```