Step cost =
$$R(IfA) = 0.04$$

Probability - direction of action = 0.7

Propendicular to direction of action = 0.15

 $V_{control of action} = 0.001$
 $V_{control of action} = 0.15$
 $V_{control of action} = 0.15$

represents a all Iteration-11 in km iteration you col U, [0][0] 480(0) 0.950 (0.700+0.1501+0.150) man (-0.04) pman - lett 0.950(07/10150000150), 0.950 (050+0.1501+0.150), down 0.95° (07°0 +0.6°0 +0.15°0) right (cgdiz) direction propondiculars = -0.04 + man (0.1425, 0.76,0.1425,0) = -0.04 + 0.665 = = 0 -625 4, £07 £17 =-0.09 + 0.95 mate 10.75 U, EO) [17 = Uo [0] [1) (absorphin state U, CO3(2)= U2(6) [2]=-1 (" 9) UTI) [0] = -0.04+0.95 man 0.70+0.150+0.150, 10.7°0 + 0.15°0 + 0.15°0) 0-200 to 500 to 500 [0,0,3(0) = -0.04) 10.7° (+0.15°0+0.15°0) U, C13[1] = -0.04+0.75" man 0.700 + 0.1501+01500, x0.70 + 0150 + 0150) 0-70 + 0.15° 1+0.15°0 = -0.04 +0.95 (0.7)

2. 0 11 21 0 0.628 0.625 -0-049 0 =1 -0.04 Here as the agent adid
up but realled some all

The source of the agent all 2 -0.04 0 -0.04 3 -0.04 -0.04 -0.04 1 thus 4 (0)(1) 0.7°0.625 + 0.15°1 + 0.15°0, Iteration-2's 0.7° 0 615 + 0.15°0.62 J + 0.15 (-0.04) U_[0][0] = -0.04+0.95 man 0.97 (-0.04) + 0.15 + 0.625 + 0.15 + 1, 07° (0.625) + 0.15° 0.625 + 0.15° = -0.04+0.95" man (0.5875, 0.78775, 0.21575, 0.52525) =-0.04 + 0.95 0.7483625 1) [2] [1] = [Wall (W = 0.70836250 210 porce 1,(2)[2]= -0.04+0.7 U2 [0][1] = U, [0][1] = 1 02[0][2]=0,[0)[2]2-1 10-7°0,625 + 0.15°0.625 + 0.15°(-0.04) 0-9°0.625 + 0.17 00.625 + 0.15 6(-0.04), 0-78(00.04) +0.1500.025 +0.150(-0.04), U2[1][1] = -0.04 + 0.95 × man 0.70(-0.04) +0.1500627 +0.150604) 2-0.04 to.95 (0.52525) 42[1][0] 0.4589875 00,510 + 0,51.0+ 0,8V 0, 5/0 + 0, 5/0 + 0, to

U2(1)[1] = -0.04+0.95 man (0701+0.150(-0.04)+0.15060.04) 0.7x(-0.04) +0.15(-0.04) +0.15(-0.04) (0.04) + 0.15°(1) + 0.15°(0) = -0.04+0.95 \$ 0.688 (07°(-1) + 0.15°(0-625) Ports° (-0.04) = 0.6136 U2 (13(2) = -0-04 + 0.95 max 0-7" (-0.54) + 0.13= (-1) + 0.15= (-0.04) 0.7°(-0.04) +0.15°(0.625) +0.15°(004) 4.7° (0.625) +0, 15° (-1) +0.15 (0.04) = -0.04 + 0.95 \$ 0.2815 g (0.7° (0.04) to 15° (0.15° (-0.04) = 0.227425 0-7 600 40,150 (-0-04) 40,150 (-0.04) U_[2](0) z -0.04 + 0.95 man 0.4 p(-0.04) +0.12 = (-0.04) 0-7° (-vay) toils ~ (-v.04) toils ~ (-voy) (0-7+0.15+0.15) = 1000y) = 100-09 =-0.04+0.95 (-0.04) (0.7° (-0.04) to 15° (-0.04) to 15° (0.04) (0.7° (-0.04) to 15° (-0.04) to 15° (0.04) (0.7° (-0.04) to 15° (-0.04) to 15° (0.04) = -0.078 1,[2)[1] (wall) = 0 U_[2][2]=-0,04+0.950 max (0.7 (-0.04) + 0.150 (-0.04) +0.15°(-0.04) = -0.04 + 0.95 0 (-0.04) 350.0- =

07(0.04) p 015°(-0.04) tol19(0.04) U2 (3) (0) = -0.04 + 0.95 mare 07 (004) +0.15 (-0-04) for5 (-0-04) 00.7 (-0.04) + 0.15 (-0.04) + off (-0.04) oit (-0.04)+015 (-0.04) +015 (-0.04) = -0.04+0.950 (-0.04) = -0.078 10-70 (-0,04) -Po.15" (-v-04) fo.15 4-0-4) U_[3][1] = -0.04+0.95 man 0-76 (-0.04) +0.15 (-0.04) ANS (-0.04) 0-7°(-0.04) forts (-0.04) tols (-1.14) 10.3° (-0.04) for15'(004) for50f.04) = -0.04 + 0.95 0 (-0.04) 02 (3) (2) 2 -0.04 + 0.95 man (020 (-0.04) +015 (-0.04) +015 (-0.04) 0.00 (-0.00) to.15 (-0.04) fo.15 (-0.04) (07°(-0.04) + 0.15°(-0.04) folt (0.04), 8-7°(-0-04) + 015° (-0-04) +015°(-0:04) =-0.04+0.950(-0.04) 0 0.7083625 0.6136 0-227425 0, = 1 6.4589875 0 -0.078 2 _0.038 -0.078 -0.078 3 -0.078

Thus, we the values of U, vz match with the output of the code