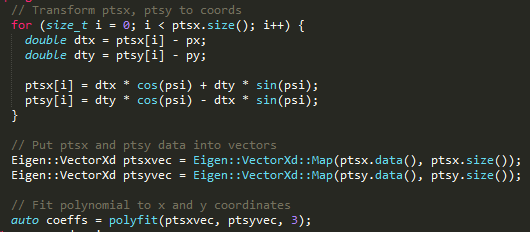
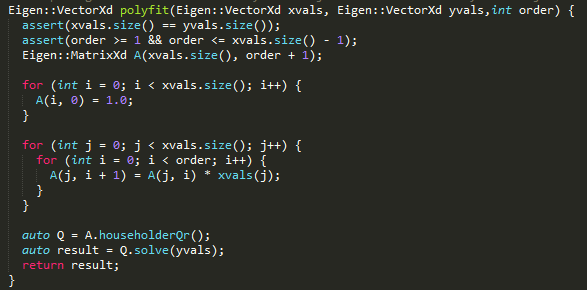
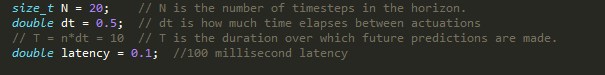
1. Preprocessing & Polynomial fitting

In a preprocessing step, the state values received from the environment are transformed into vehicle coordinates



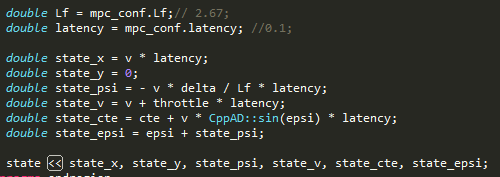


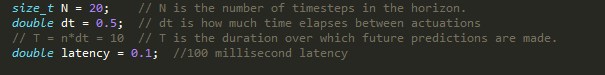
1. Timestep Length and Elapsed Duration



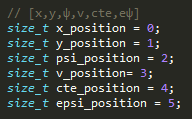
1. how latency is simulated

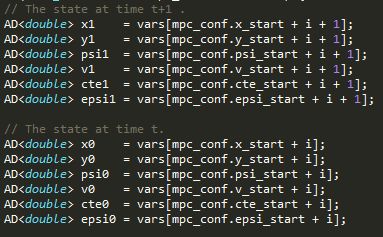
We add delay 100ms to simulate actuator response delay to state.



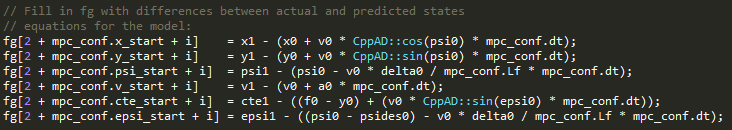


1. State Content





1. Model : State is updated by the following statements:



1. Tuning and configuration values

// Set cost tunning factors

int cost\_cte\_factor = 3000;

int cost\_epsi\_factor = 500; // made initial portion etc much less snaky

int cost\_v\_factor = 1;

int cost\_current\_delta\_factor = 1;

int cost\_diff\_delta\_factor = 200;

int cost\_current\_a\_factor = 1;

int cost\_diff\_a\_factor = 1;