

For running follow a similar structure to my testing files.

- `test_maze1 = Maze("maze1.maz")` # initialize a maze object that you want to test on
- `test_mp = <Problem name>Problem(<Maze>, <Goals>)` use this structure to initialize a problem either multi-robot or blind robot
- `result = astar_search(test_mp, <name of heuristic>)` use this to store the object solution returned by `astar_search`
- `print(result)` If you want a overview of the solution then you can directly print it out
- If you want to visualize the solution please either run Graphics for sensorless or if you want to see the belief state or want to animate path for multi robot problem, then run `test_mp.animate_path(result.path)`

For running GRAPHICS.PY which is my extracredit work:-

- you can specify the maze at the top stored in a variable name
- you can specify the start and goal using x,y format and MAKE SURE THEY ARE REACHABLE AND ARE FLOORS
- click the animate path button to see it
- PLEASE GIVE THE PROGRAM A BIT MORE if the map is big and when you resize your window, it'll take a second.

EXTRA CREDIT 2:-

- MY BLIND PROBLEM only needs to run Aster one to to localize and get to goal. The prof told me it would count as extra credit because it goes beyond the class demands and its more efficient.