### AI Princedocodes.

# MAP coloring.

open[]: array containing all the colour to be und open[]: all the modes that are not colour yet elose[]: all the modes that are colourd.

STEP1: Create a graph with each map element as a writin and connect the weighboring element using edges.

STEP2: Repeat while (open[]! = EMPTY)

for (i=0; i < len. open; i++)

i) = find all nodes connected to open[i]

ii) bliminate all used colors

iii) chaose color for 'i' from the sumaining available colors

end of loop

if (open = = EMPTY) goto STEP 4:

> elu print ( could not color entire map) goto STEP 5:

STEPY: Print color requence of all map elements STEPS: END

# WATER JUG - BFS.

#### Poucondi tions

J1: Man capacity of jug 1

J2: Man capacity of jug 2

G1: Value of Jug 1 in goal state

G2: Value of Jug 2 in goal state

open[]: modes whose children are not Calculated

close []: children are calculated

24: current value of Jug 1

1/2: current value of Jug 2

- Initially with jugs are empty - rules have been declared

STEP1: Accept values of J1, J2, G1, G2 from the user I uset root node as n=0 bl n=0.

STEP2; i) Apply all rules on about node to find the possible child modes

ii) ij (child\_node == GOAL) goto STEP #4

iii) update open[], usse[]

STEP 3: i) Find left most leaf mode of most, repeat the

ii) apply all rules to find all possible child nodes

City Destance 8 PUZZLE - Hill Climbing. Puesela · mispland-tills () - no. of mispland tills from the goal state STEP1: Let the root node as initial state. STEP2: Repeat while ( node ( misplaced\_tile) ] = 0 11 local marima) i) get uncessors by checking neighboring empty tiles
ii) calculate heuristic value for each fucusor for (i=0; i < child\_nodes; i++) C change = 0 if (child (misphered tile) = = 0) print (goal State achieved) 900 STEP 3: if (child (misplaced\_tile) & (parent (misplaced\_tile) parent = child change = 1 if (change ==0)

print (Local manima)

goto STEP 3:

TEP 3: LND

## Robot Navigation A\*

Loard []: a (9x5) matrin supresenting the about Duna

class Node: for (x,y) with parent & manhottan dist.
open []: open priority que to store path. close []: normal June to show shut down nodes

STEP! define wini Hal made with the wini tial coordinates of the hobot and get the manhattan distance (). as well as the goal

STEP2: Start warch with initial wode

Learch (init) (

open - append (init)

while (open not EHPTY)

if (open.top == (rOAL)

return NODE ell.

1) get possible successors (i) add but choice to open it its not in close []

sust choice - g(h) = f(h) + h(n)

STH3: Prient all parents of the node to get the path

STIPLE END.

iii) if (child-node = = (rOAL) golo STEP & 4 update clave[], apen[] hacktrack to parent node find neut left most node. STEPY: Print open[] to use the path from swoot to goal. WATER JUG - OFS freconditions: same as BFS. STEP 1: Take J1, J2, G1, G2 as unput and yet root nade as x1=00 &l x2=0 STEP 2: Repeat while (child-node == warsur) find child\_node of parent if (child\_node == GOAL) else goto STEP4 update open[], close[] end loop. STEP3: Backtrack to parent of current leg rude & find neut child node. golo step 2: STEPY: Print open[] for path END .

512P3: Repeat utep 2 Jill (q1=n+1) Grepu: display board STEPS: END. Magic Square pre conditions: N = Size of matrix n = possible number to be field i,j = cell co-ordinatesSTEPL: let i=0, j=N/2 initially (to place the numb in the top now, combi are [i][j]= n, nH neuti = (i-1)·1·N neutj = (j+1)·1·N STEP 2: ij (X (neuti, neutj)) else i j = neuti, neutj TH3: print over.

N Queens. pre conditions: arrEJEJ: Sward & n: 400 of queens to be placed quo : green number. STEPS: Accept the value of 'n' from user. Quate a 20 matrix with nxn as dimension and yet the values to zero. ('0') STEP 2: 1=0, 1=q-1 if (arr [i][j] == 0) i) over [i][j]=9 ii) set all board tiles in the row, column and diagonal of quun (2) to il (i == n &2 1 = 9-1) i) net all dward tiles in the now, colurn and diagonal of quen (q-1) to i) Remove quen (q-1) & but tale to-1 STEP3: Repeat utep 2 Jul (q6=n+1)

STEP4: display board

STEPS: END.