```
def aStarAlgo(start_node, stop_node):
    open_set = set(start_node)
    closed_set = set()
    g = \{\}
    parents = \{\}
    q[start_node] = 0
    parents[start_node] = start_node
    while len(open_set)>0:
         n = None
         for v in open_set:
    if n == None or g[v] +
heuristic(v) < g[n] + heuristic(n):
                  n = v
         if n == stop_node or Graph_nodes[n]
== None:
             pass
         else:
             for(m, weight) in
get_neighbors(n):
                  if m not in open_set and m
not in closed set:
                      open_set.add(m)
                      parents[m] = n
                      g[m] = g[n] + weight
                  else:
    if g[m] > g[n] + weight:
        g[m] = g[n] + weight
                           parents[m] = n
                           if m in closed_set:
closed_set.remove(m)
                                open_set.add(m)
         if n == None:
             print('Path does not exist!')
             return None
```

```
if n == stop_node:
            path = []
            while parents[n] != n:
                 path.append(n)
                 n = parents[n]
            path.append(start_node)
            path.reverse()
            print('Path found:
{}' format(path))
            return path
        open_set.remove(n)
        closed_set.add(n)
    print('Path does not exist!')
    return None
def get_neighbors(v):
    if v in Graph_nodes:
        return Graph_nodes[v]
    else:
        return None
def heuristic(n):
    H_dist = {
              11,
    return H_dist[n]
Graph_nodes = {
```