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# Python (L1)

## Darbo užduotis

<https://onlinejudge.org/index.php?option=com_onlinejudge&Itemid=8&category=3&page=show_problem&problem=75>

## Programos tekstas

**class** TelephoneInfo:  
 **def** \_\_init\_\_(self, code, name, price):  
 self.code = code  
 self.name = name  
 self.price = price  
  
 **def** priceSeconds(self):  
 **return** round(self.price \* 0.1, 2)  
  
**class** TelephoneCalls:  
 **def** \_\_init\_\_(self, number, time):  
 self.number = number  
 self.time = time  
  
**class** Data (TelephoneInfo, TelephoneCalls):  
 **def** \_\_init\_\_(self, number, code, name, price, time):  
 self.number = number  
 self.code = code  
 self.name = name  
 self.price = price  
 self.time = time  
  
 **def** calcuPrice(self):  
 **return** float(self.price) \* 0.1 \* float(self.time)  
  
 **def** \_\_str\_\_(self):  
 **if** self.code != -1:  
 **return "{0:15} {1:16} {2:8} {3:6} {4:6} {5:.2f}\n"**.format(self.number, self.name, self.code, self.time, str(self.priceSeconds()), self.calcuPrice())  
 **else**:  
 **return "{0:15} {1:16} {2:8} {3:6} {4:6} {5:.2f}\n"**.format(self.number, self.name, **""**, self.time, **""**, float(self.price))  
  
  
**class** Main:  
  
 **def** \_\_init\_\_(self, read, write):  
 self.readFromFile = read  
 self.writeToFile = write  
  
 **def** dataRead(self):  
 data = []  
 file = open(self.readFromFile, **"r"**)  
 **for** dataFromFile **in** file:  
 data.append(dataFromFile)  
 file.close()  
 **return** data  
  
 **def** splitLine(self,dataFromFile):  
 split = []  
 listForInfo = []  
 listForCalls = []  
 info = **False  
 for** i **in** dataFromFile:  
  
 index = 0  
 **if** len(split) == 2 **and** info:  
 split = []  
 **elif not** info:  
 split = []  
  
 **for** string **in** i:  
 **if** string == **" "**:  
 split.append(i[0:index])  
 split.append(i[index + 1: len(i)])  
 **break** index += 1  
 **if** index == len(i):  
 split.append(i.strip())  
split[0] = split[0].strip()  
 **if** len(split) > 1 **and not** bool(info):split[1] = split[1].strip()  
 data = split[1].split(**'$'**)  
 telephoneInfo = TelephoneInfo(split[0], data[0], float(data[1]) \* 0.1)  
 listForInfo.append(telephoneInfo)  
 **elif** len(split) == 1 **and** split[0] == **"000000" and not** bool(info):split = []  
 info = **True  
 elif** len(split) > 1 **and** bool(info):  
 split[1] = split[1].strip()  
 calls = TelephoneCalls(split[0], split[1])  
 listForCalls.append(calls)  
 **return** listForInfo, listForCalls  
  
 **def** calculatePrice(self, listOfCall, listOfInfo):  
 calculatedData = []  
 **for** calls **in** listOfCall:  
 state = **False  
 for** info **in** listOfInfo:  
 **if** calls.number[0:len(info.code)] == info.code:  
 data = Data(calls.number, calls.number[len(info.code):len(calls.number)], info.name, info.price,  
 calls.time)  
 calculatedData.append(data)  
 state = **True  
 break  
 elif** calls.number[0] != **"0"**:  
 tempInfo = TelephoneInfo(calls.number, **"Local"**, 0)  
 data = Data(calls.number, tempInfo.code, tempInfo.name, tempInfo.price, calls.time)  
 calculatedData.append(data)  
 state = **True  
 break  
 if not** bool(state):  
 data = Data(calls.number, -1, **"Unknown"**, -1, calls.time)  
 calculatedData.append(data)  
 **return** calculatedData  
  
 **def** saveData(self, calculatedData):  
 fSave = open(self.writeToFile, **"w+"**)**for** data **in** calculatedData:  
 fSave.write(str(data))  
 fSave.close()  
  
 **def** run(self):  
 fileData = self.dataRead()  
 infoList, callsList = self.splitLine(fileData)  
 dataList = self.calculatePrice(callsList, infoList)  
 self.saveData(dataList)  
  
main = Main(**"test.txt"**, **"data.txt"**)  
main.run()

## Pradiniai duomenys ir rezultatai

|  |  |
| --- | --- |
| **Pradiniai duomenys** | **Rezultatai** |
| 088925 Broadwood$81 03 Arrowtown$38 0061 Australia$140 000000 031526 22 0061853279 3 0889256287213 122 779760 1 002832769 5 # | 031526 Arrowtown 1526 22 0.38 8.36 0061853279 Australia 853279 3 1.4 4.20 0889256287213 Broadwood 6287213 122 0.81 98.82 779760 Local 779760 1 0.0 0.00 002832769 Unknown 5 -1.00 |

# Scalatron botas

## Darbo užduotis

Sukurti Scalatron botą.

Reikalavimai:

1. Panaudoti bent kelis master boto išleidžiamus botų padėjėjų tipus (pvz.: minos, raketos į priešus, "kamikadzės", rinkikai, masalas ir pan.)
2. Panaudoti bet kurį vieną iš kelio radimo algoritmų (DFS, BFS, A\*, Greedy, Dijkstra).

Realizuotos minos, gyvųnų gaudytojai/rinkikai ir „Kamimadzė“ akytvus botai, modifikuotos agresyvios ir apsauginės raketos.

Master botas, gyvųnų gaudytojai/rinkikai ir „Kamikadzė“, kelio radimui naudoja Djikstros algoritmą.

## Programos tekstas

import scala.util.control.Breaks.\_

import scala.math.sqrt

import java.util

import scala.collection.mutable.ListBuffer

object ControlFunction

{

def forMaster(bot: Bot) {

val (directionValue, nearestEnemyMaster, nearestEnemySlave) = analyzeViewAsMaster(bot)

val dontFireAggressiveMissileUntil = bot.inputAsIntOrElse("dontFireAggressiveMissileUntil", -1)

val dontFireDefensiveMissileUntil = bot.inputAsIntOrElse("dontFireDefensiveMissileUntil", -1)

val lastDirection = bot.inputAsIntOrElse("lastDirection", 0)

val dontPlantMineUntil = bot.inputAsIntOrElse("dontPlantMineUntil", -1)

val dontReleaseKamekadzeUntil = bot.inputAsIntOrElse("dontReleaseKamekadzeUntil", -1)

val dontGatherFood = bot.inputAsIntOrElse("dontGatherFood", -1)

val direction = XY.fromDirection45(directionValue)

bot.move(direction) //give straight direction

bot.set("lastDirection" -> directionValue)

// food gathering bot, this bot gathers 1500 energy with givven and try return back to master

if(dontGatherFood < bot.time && bot.energy > 500){

bot.view.offsetToNearest('P') match {

case Some(delta: XY) =>

bot.set("rx" -> delta.x, "ry" -> delta.y)

val unitDelta = XY.fromDirection45((lastDirection + 4) % 8)

bot.spawn(unitDelta, "energy" -> 400, "mood" -> "Gather")

bot.set("dontGatherFood" -> (bot.time + delta.stepCount + 1))

case None =>

}

bot.view.offsetToNearest('B') match {

case Some(delta: XY) =>

bot.set("rx" -> delta.x, "ry" -> delta.y)

val unitDelta = XY.fromDirection45((lastDirection + 4) % 8)

bot.spawn(unitDelta, "energy" -> 500, "mood" -> "Gather")

bot.set("dontGatherFood" -> (bot.time + delta.stepCount + 1))

case None =>

}

}

// mine planting

if(dontPlantMineUntil < bot.time && bot.energy > 600){

val unitDelta = XY.fromDirection45((lastDirection + 4) % 8)

bot.spawn(unitDelta, "energy" -> 400, "mood" -> "Mine")

bot.set("dontPlantMineUntil" -> (bot.time + 20))

}

// kamekadze if master sees other master kamikaze go to straight slave bot or him self

if(dontReleaseKamekadzeUntil < bot.time && bot.energy > 200) { // fire defensive missile?

bot.view.offsetToNearest('m') match {

case Some(delta: XY) =>

bot.set("rx" -> delta.x, "ry" -> delta.y)

val unitDelta = XY.fromDirection45((lastDirection + 4) % 8)

bot.spawn(unitDelta, "energy" -> 200, "mood" -> "Kamikadze")

bot.set("dontReleaseKamekadzeUntil" -> (bot.time + delta.stepCount + 1))

case None =>

}

}

if(dontFireAggressiveMissileUntil < bot.time && bot.energy > 100) { // fire attack missile?

nearestEnemyMaster match {

case None => // no-on nearby

case Some(relPos) => // a master is nearby

val unitDelta = relPos.signum

val remainder = relPos - unitDelta // we place slave nearer target, so subtract that from overall delta

bot.spawn(unitDelta, "mood" -> "Aggressive", "target" -> remainder)

bot.set("dontFireAggressiveMissileUntil" -> (bot.time + relPos.stepCount + 1))

}

}

else

if(dontFireDefensiveMissileUntil < bot.time && bot.energy > 100) { // fire defensive missile?

nearestEnemySlave match {

case None => // no-on nearby

case Some(relPos) => // an enemy slave is nearby

if(relPos.stepCount < 8) {

// this one's getting too close!

val unitDelta = relPos.signum

val remainder = relPos - unitDelta // we place slave nearer target, so subtract that from overall delta

bot.spawn(unitDelta, "mood" -> "Defensive", "target" -> remainder)

bot.set("dontFireDefensiveMissileUntil" -> (bot.time + relPos.stepCount + 1))

}

}

// vieta kazkokiai atakai

}

}

def forSlave(bot: MiniBot) {

bot.inputOrElse("mood", "Lurking") match {

case "Aggressive" => reactAsAggressiveMissile(bot)

case "Defensive" => reactAsDefensiveMissile(bot)

case "Mine" => reactAsMine(bot)

case "Kamikadze" => reactAsKamekaze(bot)

case "Gather" => reactAsHarvest(bot)

case s: String => bot.log("unknown mood: " + s)

}

}

// mine plant logic

def reactAsMine(bot: MiniBot) {

bot.view.offsetToNearest('m') match {

case Some(delta: XY) =>

bot.set("rx" -> delta.x, "ry" -> delta.y)

if (delta.length <= 3) {

// yes -- blow it up!

bot.explode(4)

}

case None =>

}

bot.view.offsetToNearest('s') match {

case Some(delta: XY) =>

bot.set("rx" -> delta.x, "ry" -> delta.y)

if (delta.length <= 3) {

// yes -- blow it up!

bot.explode(4)

}

case None =>

}

bot.view.offsetToNearest('b') match {

case Some(delta: XY) =>

bot.set("rx" -> delta.x, "ry" -> delta.y)

if (delta.length < 2) {

// yes -- blow it up!

bot.explode(4)

}

case None =>

}

}

// kamikadze exploads near master or slave if it cant find any of them then kamekazde self distructs

def reactAsKamekaze(bot: MiniBot) {

val direction45 = analyzeViewAsBot(bot, 1000)

val direction = XY.fromDirection45(direction45)

if(direction != XY(0,0))

{

bot.move(direction)

bot.view.offsetToNearest('m') match {

case Some(delta: XY) =>

bot.set("rx" -> delta.x, "ry" -> delta.y)

if (delta.length <= 4) {

// yes -- blow it up!

bot.explode(4)

}

case None =>

}

}

else

{

bot.explode(4)

}

}

// start react gathering bot move by found location and obsticles

def reactAsHarvest(bot: MiniBot) {

val (directionValue, nearestEnemyMaster, nearestEnemySlave) = analyzeViewAsMaster(bot)

val direction = XY.fromDirection45(directionValue)

bot.move(direction)

bot.set("lastDirection" -> direction.toDirection45)

}

def reactAsAggressiveMissile(bot: MiniBot) {

bot.view.offsetToNearest('m') match {

case Some(delta: XY) =>

// another master is visible at the given relative position (i.e. position delta)

// close enough to blow it up?

if(delta.length <= 2) {

// yes -- blow it up!

bot.explode(4)

} else {

// no -- move closer!

bot.move(delta.signum)

bot.set("rx" -> delta.x, "ry" -> delta.y)

}

case None =>

// no target visible -- follow our targeting strategy

val target = bot.inputAsXYOrElse("target", XY.Zero)

// did we arrive at the target?

if(target.isNonZero) {

// no -- keep going

val unitDelta = target.signum // e.g. CellPos(-8,6) => CellPos(-1,1)

bot.move(unitDelta)

// compute the remaining delta and encode it into a new 'target' property

val remainder = target - unitDelta // e.g. = CellPos(-7,5)

bot.set("target" -> remainder)

} else

}

}

def reactAsDefensiveMissile(bot: MiniBot) {

bot.view.offsetToNearest('s') match {

case Some(delta: XY) =>

// another slave is visible at the given relative position (i.e. position delta)

// move closer!

bot.move(delta.signum)

bot.set("rx" -> delta.x, "ry" -> delta.y)

case None =>

// no target visible -- follow our targeting strategy

val target = bot.inputAsXYOrElse("target", XY.Zero)

// did we arrive at the target?

if(target.isNonZero) {

// no -- keep going

val unitDelta = target.signum // e.g. CellPos(-8,6) => CellPos(-1,1)

bot.move(unitDelta)

// compute the remaining delta and encode it into a new 'target' property

val remainder = target - unitDelta // e.g. = CellPos(-7,5)

bot.set("target" -> remainder)

}

}

}

def analyzeViewAsMaster(bot: Bot) = {

var view = bot.view

val directionValue = Array.ofDim[Double](8)

var nearestEnemyMaster: Option[XY] = None

var nearestEnemySlave: Option[XY] = None

val cells = view.cells

val cellCount = cells.length

val cellWeights = Array.ofDim[Double](cellCount)

val indexRel = view.indexFromRelPos(XY(0,0))

//view.aStarPathfind(cellWeights, bot)

//bot.log(cells.contains('P').toString)

//bot.log(cells)

// this for creates heatmap for helping a\* algorith find road to position with weights

for(i <- 0 until cellCount) {

val cellRelPos = view.relPosFromIndex(i)

if(cellRelPos.isNonZero && !view.outOfBoundsRel(cellRelPos)) {

cells(i) match {

case 'm' => // another master: not dangerous, but an obstacle

nearestEnemyMaster = Some(cellRelPos)

for (x <- -4 to 4) {

for (y <- -4 to 4) {

val pos = cellRelPos + XY(x, y)

if (pos.isNonZero && !view.outOfBoundsRel(pos)) {

cellWeights(view.indexFromRelPos(pos)) += 10000

}

}

}

case 's' => // another slave: potentially dangerous?

nearestEnemySlave = Some(cellRelPos)

for (j <- 0 until cellCount) {

val pos = view.relPosFromIndex(j)

if(!bot.view.outOfBoundsRel(pos))

{

val stepDistance = cellRelPos.stepsTo(pos)

if (pos.isNonZero && stepDistance != 0) {

val stepDistance = cellRelPos.stepsTo(pos)

cellWeights(j) += 1000 / stepDistance

}

}

}

case 'P' =>

val pos = view.relPosFromIndex(i)

if(!bot.view.outOfBoundsRel(pos))

{

val stepDistance = cellRelPos.stepsTo(pos)

if (stepDistance == 1) cellWeights(i) += 100

else if (stepDistance == 2) cellWeights(i) += 300

else cellWeights(i) += 500

}

case 'B' =>

val pos = view.relPosFromIndex(i)

val stepDistance = cellRelPos.stepsTo(pos)

if (stepDistance == 1) cellWeights(i) += 50

else if (stepDistance == 2) cellWeights(i) += 200

else cellWeights(i) += 520

case 'b' =>

for (x <- -2 to 2) {

for (y <- -2 to 2) {

val pos = view.relPosFromIndex(i) + XY(x,y)

if(pos.isNonZero && !view.outOfBoundsRel(pos))

{

val index = view.indexFromRelPos(pos)

cellWeights(index) += 2500000

}

}

}

/\*case 'p' => // bad plant: bad, but only if I step on it

cellWeights(i) += 100000\*/

case 'W' => // wall: harmless, just don't walk into it

for (x <- -1 to 1) {

for (y <- -1 to 1) {

val pos = cellRelPos + XY(x, y)

if (pos.isNonZero && !view.outOfBoundsRel(pos)) {

cellWeights(view.indexFromRelPos(pos)) += 1500000

}

}

}

case '?' =>

cellWeights(i) += 1500000

case '\_' =>

cellWeights(i) += 2

case \_ => cellWeights(i) += 1

}

}

}

var direction45 = 0

val lastDirection = bot.inputAsIntOrElse("lastDirection", 0)

val lastCount = bot.inputAsIntOrElse("lastCount", 0).toInt

val previuosStepCount = bot.inputAsIntOrElse("PreviousStepCount", 0).toInt

if ((cells.contains('P') || cells.contains('B')) || (lastCount < 1 && lastCount > 2)) {

// finding closest target by weights around target and distance between target and master

var (closestFood) = findClosestThings(cellCount, cells, view, cellWeights, bot)

if(!closestFood.isZero)

{

var (path, path\_index, found) = aStarPathfind(cells, XY.Zero, view, closestFood, bot, cellWeights)

if(found && path.size > 0)

{

if(path(path.size - 1) != XY(0,0))

{

if(previuosStepCount == path.size)

{

bot.set("lastCount" -> 1.toString)

}

bot.set("PreviousStepCount" -> path.size)

direction45 = path(path.size - 1).toDirection45

bot.log(direction45.toString)

directionValue(direction45)

}

}

else

{

// if path not found it starts refrence bot algorithn

bot.set("lastCount" -> 1.toString)

}

}

else{

// after failed search of closest target it try again by adding bigger weight to previuos target

var (temp\_closestFood) = findClosestThings(cellCount, cells, view, cellWeights, bot)

if(!bot.view.outOfBoundsRel(temp\_closestFood) && !temp\_closestFood.isZero)

{

var index\_tmp = view.indexFromRelPos(temp\_closestFood)

cellWeights(index\_tmp) += cellWeights(index\_tmp) \* 2

var (closestFood) = findClosestThings(cellCount, cells, view, cellWeights, bot)

var (path, path\_index, found) = aStarPathfind(cells, XY.Zero, view, closestFood, bot, cellWeights)

if(found && path.size > 0)

{

if(path(path.size - 1) != XY(0,0))

{

if(previuosStepCount == path.size)

{

bot.set("lastCount" -> 1.toString)

}

bot.set("PreviousStepCount" -> path.size)

direction45 = path(path.size - 1).toDirection45

bot.log(direction45.toString)

directionValue(direction45)

}

}

else

{

// if path not found it starts refrence bot algorithn

bot.set("lastCount" -> 1.toString)

}

}

}

}

//refrence algorithm is used by bot when there are any targets in screnn or when playres last step is the same

else if((!cells.contains('P') && !cells.contains('B')) || (lastCount > 0 && lastCount < 3))

{

for(i <- 0 until cellCount) {

val cellRelPos = view.relPosFromIndex(i)

if(cellRelPos.isNonZero && !view.outOfBoundsRel(cellRelPos)) {

val stepDistance = cellRelPos.stepCount

val value: Double = cells(i) match {

case 'M' =>

1500000

case 'm' => // another master: not dangerous, but an obstacle

nearestEnemyMaster = Some(cellRelPos)

if(stepDistance < 2) -1000 else 0

case 's' => // another slave: potentially dangerous?

nearestEnemySlave = Some(cellRelPos)

-100 / stepDistance

case 'S' => // out own slave

0.0

case 'B' => // good beast: valuable, but runs away

if(stepDistance == 1) 600

else if(stepDistance == 2) 300

else (150 - stepDistance \* 15).max(10)

case 'P' => // good plant: less valuable, but does not run

if(stepDistance == 1) 500

else if(stepDistance == 2) 300

else (150 - stepDistance \* 10).max(10)

case 'b' => // bad beast: dangerous, but only if very close

if(stepDistance < 4) -400 / stepDistance else -50 / stepDistance

case 'p' => // bad plant: bad, but only if I step on it

if(stepDistance < 2) -1000 else 0

case 'W' => // wall: harmless, just don't walk into it

if(stepDistance < 3) -1000 else 0

case '?' =>

-1000

case '\_' => 10

case \_ => 0.0

}

direction45 = cellRelPos.toDirection45

directionValue(direction45) += value

val bestDirection45 = directionValue.zipWithIndex.maxBy(\_.\_1).\_2

direction45 = bestDirection45

}

}

bot.set("lastCount" -> (lastCount + 1).toString)

}

(direction45, nearestEnemyMaster, nearestEnemySlave)

}

// closest thing search

def findClosestThings(cellCount: Int, cells: String, view: View, weights: Array[Double], bot: Bot): (XY) = {

var distances = ListBuffer[Double]() // list of targets distances

var indexes = ListBuffer[Int]() // list of target indexes

var weightsForFood = ListBuffer[Double]() // target weights

for (i <- 0 until cellCount) {

val cellRelPos = view.relPosFromIndex(i)

if(cellRelPos.isNonZero && !view.outOfBoundsRel(cellRelPos)) {

cells(i) match {

case 'P' =>

indexes = indexes :+ i

var testWeight = 0.0

var cnt = 0

for (x <- -4 to 4) {

for (y <- -4 to 4) {

val pos = cellRelPos + XY(x, y)

if (pos.isNonZero && !view.outOfBoundsRel(pos)) {

testWeight += weights(view.indexFromRelPos(pos))

cnt += 1

}

}

}

var avgWeight = testWeight / cnt

val stepDistance = cellRelPos.stepCount

distances = distances :+ stepDistance.toDouble

// change distance by weights

if(avgWeight > 1500000)

{

distances(distances.size-1) += stepDistance / 2

}

if(avgWeight < 1500000 && avgWeight > 1000000 && bot.energy > 2500)

{

distances(distances.size-1) -= stepDistance / 3

}

if(avgWeight < 1000000)

{

distances(distances.size-1) -= stepDistance / 2

}

case 'B' =>

indexes = indexes :+ i

var testWeight = 0.0

var cnt = 0

for (x <- -4 to 4) {

for (y <- -4 to 4) {

val pos = cellRelPos + XY(x, y)

if (pos.isNonZero && !view.outOfBoundsRel(pos)) {

testWeight += weights(view.indexFromRelPos(pos))

cnt += 1

}

}

}

var avgWeight = testWeight / cnt

val stepDistance = cellRelPos.stepCount

distances = distances :+ stepDistance.toDouble

// by weights make shorter or longer distance

if(avgWeight > 1500000)

{

distances(distances.size-1) += stepDistance / 2

}

if(avgWeight < 1500000 && avgWeight > 1000000 && bot.energy > 2500)

{

distances(distances.size-1) -= stepDistance / 3

}

if(avgWeight < 1000000)

{

distances(distances.size-1) -= stepDistance / 2

}

case \_ =>

}

}

}

if(distances.nonEmpty)

{

// searching minimum distance index

val temp\_index = distances.indexOf(distances.min)

// geting from indexed real position index, then from this index get position where is target

(view.relPosFromIndex(indexes(temp\_index)))

}

else

{

(XY(0,1))

}

}

// a\* path finding algorithm

def aStarPathfind(cells: String, startingPoint: XY, view: View, destination: XY, bot: Bot, weights: Array[Double]) = {

var open\_list = ListBuffer[XY]() // list where coordinates are added after it selected

var open\_list\_f = ListBuffer[Double]() // list where coordinates weight is added after selection

// open lists are constantly changing because this is temporary lis for value saving

var closed\_list = ListBuffer[Boolean]() // boolean list for checking if coordinates is used

var parent = ListBuffer[Int]() // previous index list for ex. parent(child index) = parent index

var parent\_coordinates = ListBuffer[XY]() // previous coordinates list for ex. parent(child index) = parent coordinates

var g = ListBuffer[Float]() // g weight list for finding path. g is distance fom center to other move pair

var f = ListBuffer[Float]() // g + h weight list for finding path

var h = ListBuffer[Float]() // h weight list for finding path. h is distance between last and other position pair

var foundDest = false // boolean for returning if destination is found

var loopingPos = startingPoint; // current position

var path = ListBuffer[XY]() // founded path coordinates

var path\_index = ListBuffer[Int]() // first coordinates index of path list

// init of lists

for(i <- 0 until cells.length)

{

closed\_list = closed\_list :+ false

parent = parent :+ -1

parent\_coordinates = parent\_coordinates :+ XY(-1,-1)

g = g :+ Float.MaxValue

f = f :+ Float.MaxValue

h = h :+ Float.MaxValue

}

//bot.log(cells.size.toString)

// setuping first element

var index = view.indexFromRelPos(startingPoint)

f.update(index, (0.0).toFloat)

g.update(index, (0.0).toFloat)

h.update(index, (0.0).toFloat)

parent.update(index, index)

parent\_coordinates.update(index, startingPoint)

open\_list = open\_list :+ startingPoint

open\_list\_f = open\_list\_f :+ 0.0

var count = 0

// breakable ussage for breaking while when end is found

breakable{

while(!open\_list.isEmpty)

{

// get element from temporary list and the delete it

loopingPos = open\_list(0)

var parentIndex = view.indexFromRelPos(loopingPos)

open\_list.remove(0)

open\_list\_f.remove(0)

// set that position is visited

closed\_list.update(index, false)

// checking neighbours around selected element for finding next element

for(x <- -1 to 1)

{

for(y <- -1 to 1)

{

// prevent form adding zero coordinates

if((x != 0 && y != 0) ||(x == 0 && y != 0) || (x != 0 && y == 0))

{

var pos = loopingPos + XY(x, y)

index = view.indexFromRelPos(pos)

if (!view.outOfBoundsRel(pos))

{

// destination found

if(pos == destination)

{

// add last coordinates and index

parent\_coordinates.update(index, pos)

parent.update(index, parentIndex)

// trace path

var (temp\_path, temp\_path\_index) = tracePath(parent, parent\_coordinates, pos, startingPoint, view, bot)

path = temp\_path

path\_index = temp\_path\_index

foundDest = true

break

}

else if(closed\_list(index) == false && isUnBlocked(cells, index)) // check if element is not blocked and coordinates ins not used

{

// calculate vaerage weight around new element. this helps decide new coordinates with geat map

var average\_weight = 0.0

var count = 0

for(x\_tmp <- -1 to 1)

{

for(y\_tmp <- -1 to 1)

{

var temp\_pos = pos + XY(x\_tmp, y\_tmp)

if(!bot.view.outOfBoundsRel(temp\_pos))

{

var temp\_index = view.indexFromRelPos(pos)

average\_weight = average\_weight + weights(temp\_index)

average\_weight += weights(index)

count += 1

}

}

}

average\_weight = average\_weight / count

// calculating weight for coordinates

var gNew = 0.0

if((x == 0 && y != 0) || (x != 0 && y == 0))

{

gNew = g(parentIndex) + 1.0;

}

else

{

gNew = g(parentIndex) + 1.414;

}

gNew = gNew

var hNew = calculateHValue(pos, destination)

hNew = hNew

var fNew = gNew + hNew + average\_weight;

// check if use this coordinates or more efficent coordinates is already selected

if (f(index) == Float.MaxValue || f(index) > fNew)

{

// add new coordinates for next coordinates

open\_list = open\_list :+ pos

open\_list\_f = open\_list\_f :+ fNew

//bot.log(index.toString)

// update all values fom init to real values

f.update(index, fNew.toFloat)

g.update(index, gNew.toFloat)

h.update(index, hNew.toFloat)

parent.update(index, parentIndex)

parent\_coordinates.update(index, loopingPos)

}

}

}

}

}

}

}

}

(path, path\_index, foundDest)

}

def isUnBlocked(colums: String, index\_check: Int): (Boolean) =

{

// Returns true if the cell is not blocked else false

if (colums(index\_check) != 'w' && colums(index\_check) != '?' && colums(index\_check) != 'b')

{

(true)

}

else

{

(false)

}

}

def calculateHValue(pos: XY, dest: XY): (Double)=

{

// Return using the distance formula

(sqrt((pos.x-dest.x)\*(pos.x-dest.x) + (pos.y-dest.y)\*(pos.y-dest.y)))

}

def tracePath(parent: ListBuffer[Int], parent\_coordinates: ListBuffer[XY], last: XY, dest: XY, view: View, bot: Bot) = {

// go from back to beggining and return reversed list as path

var Path = ListBuffer[XY]()

var index = view.indexFromRelPos(last)

var indexGo = ListBuffer[Int]()

while(parent(index) != view.indexFromRelPos(dest))

{

Path = parent\_coordinates(index) +=: Path

indexGo = index +=: indexGo

index = parent(index)

}

Path = parent\_coordinates(index) +=: Path

indexGo = index +=: indexGo

(Path, indexGo)

}

// almoust the same as master bot changed target search

def analyzeViewAsBot(bot: Bot, masterVal: Int) = {

var view = bot.view

val directionValue = Array.ofDim[Double](8)

var nearestEnemyMaster: XY = XY(0,0)

var nearestEnemySlave: XY = XY(0,0)

var nearestEnemy: XY = XY(0,0)

var nearestEnemyIndex: Int = 0

var nearestDistance: Int = 0

val cells = view.cells

val cellCount = cells.length

val cellWeights = Array.ofDim[Double](cellCount)

val indexRel = view.indexFromRelPos(XY(0,0))

// this for creates heatmap for helping a\* algorith find road to position with weight. When heatmap ia updating closest enemy is updating too

for(i <- 0 until cellCount) {

val cellRelPos = view.relPosFromIndex(i)

if(cellRelPos.isNonZero && !view.outOfBoundsRel(cellRelPos)) {

cells(i) match {

case 'M' =>

cellWeights(i) += 1500000

case 'm' => // another master: not dangerous, but an obstacle

nearestEnemyMaster = cellRelPos

if(!bot.view.outOfBoundsRel(cellRelPos))

{

for (x <- -4 to 4) {

for (y <- -4 to 4) {

val pos = cellRelPos + XY(x, y)

val stepDistance = cellRelPos.stepsTo(pos)

if (pos.isNonZero && !view.outOfBoundsRel(pos) && stepDistance != 0) {

cellWeights(view.indexFromRelPos(pos)) += 10000

}

}

}

}

nearestEnemy = nearestEnemyMaster

nearestEnemyIndex = i

nearestDistance = cellRelPos.stepCount

case 's' => // another slave: potentially dangerous?

nearestEnemySlave = cellRelPos

for (j <- 0 until cellCount) {

val pos = view.relPosFromIndex(j)

if(!bot.view.outOfBoundsRel(pos))

{

val stepDistance = cellRelPos.stepsTo(pos)

if (pos.isNonZero && !view.outOfBoundsRel(pos) && stepDistance != 0) {

val stepDistance = cellRelPos.stepsTo(pos)

cellWeights(j) += 1000 / stepDistance

}

}

}

if(nearestDistance > cellRelPos.stepCount)

{

nearestEnemy = nearestEnemySlave

nearestEnemyIndex = i

}

case 'P' =>

val pos = view.relPosFromIndex(i)

val stepDistance = cellRelPos.stepsTo(pos)

if(pos.isNonZero && !view.outOfBoundsRel(pos) && stepDistance != 0)

{

if (stepDistance == 1) cellWeights(i) += 100

else if (stepDistance == 2) cellWeights(i) += 300

else cellWeights(i) += 500

}

case 'B' =>

val pos = view.relPosFromIndex(i)

val stepDistance = cellRelPos.stepsTo(pos)

if (stepDistance == 1) cellWeights(i) += 50

else if (stepDistance == 2) cellWeights(i) += 200

else cellWeights(i) += 520

case 'b' =>

for (x <- -2 to 2) {

for (y <- -2 to 2) {

val pos = view.relPosFromIndex(i) + XY(x,y)

val stepDistance = cellRelPos.stepsTo(pos)

if(pos.isNonZero && !view.outOfBoundsRel(pos) && stepDistance != 0)

{

val index = view.indexFromRelPos(pos)

cellWeights(index) += 2500000

}

}

}

/\*case 'p' => // bad plant: bad, but only if I step on it

cellWeights(i) += 100000\*/

case 'W' => // wall: harmless, just don't walk into it

for (x <- -1 to 1) {

for (y <- -1 to 1) {

val pos = cellRelPos + XY(x, y)

val stepDistance = cellRelPos.stepsTo(pos)

if(pos.isNonZero && !view.outOfBoundsRel(pos) && stepDistance != 0)

{

cellWeights(view.indexFromRelPos(pos)) += 1500000

}

}

}

case '?' =>

cellWeights(i) += 1500000

case '\_' =>

cellWeights(i) += 2

case \_ => cellWeights(i) += 1

}

}

}

var direction45 = 0

val lastDirection = bot.inputAsIntOrElse("lastDirection", 0)

val lastCount = bot.inputAsIntOrElse("lastCount", 0).toInt

val previuosStepCount = bot.inputAsIntOrElse("PreviousStepCount", 0).toInt

if ((cells.contains('m') || cells.contains('s')) || (lastCount < 1 && lastCount > 2)) {

// check if nearest enemy is not at master position

if(!nearestEnemy.isZero)

{

var (path, path\_index, found) = aStarPathfind(cells, XY.Zero, view, nearestEnemy, bot, cellWeights)

if(found && path.size > 0)

{

if(path(path.size - 1) != XY(0,0))

{

if(previuosStepCount == path.size)

{

bot.set("lastCount" -> 1.toString)

}

bot.set("PreviousStepCount" -> path.size)

direction45 = path(path.size - 1).toDirection45

bot.log(direction45.toString)

directionValue(direction45)

}

}

else

{

bot.set("lastCount" -> 1.toString)

}

}

else{

// check if enemy is still in view

if(!bot.view.outOfBoundsRel(nearestEnemy) && !nearestEnemy.isZero)

{

// update weights after enemy is at master position

var index\_tmp = view.indexFromRelPos(nearestEnemy)

cellWeights(index\_tmp) += cellWeights(index\_tmp) \* 2

// search for path

var (path, path\_index, found) = aStarPathfind(cells, XY.Zero, view, nearestEnemy, bot, cellWeights)

if(found && path.size > 0)

{

if(path(path.size - 1) != XY(0,0))

{

if(previuosStepCount == path.size)

{

bot.set("lastCount" -> 1.toString)

}

bot.set("PreviousStepCount" -> path.size)

direction45 = path(path.size - 1).toDirection45

bot.log(direction45.toString)

directionValue(direction45)

}

}

else

{

bot.set("lastCount" -> 1.toString)

}

}

}

}

else if((!cells.contains('m') && !cells.contains('s')) || (lastCount > 0 && lastCount < 3)) // use refrence algorithm if enemy is not in view or path by a\* is not found

{

for(i <- 0 until cellCount) {

val cellRelPos = view.relPosFromIndex(i)

if(cellRelPos.isNonZero && !view.outOfBoundsRel(cellRelPos)) {

val stepDistance = cellRelPos.stepCount

val value: Double = cells(i) match {

case 'm' =>

700

case 's' => // another slave: potentially dangerous?

700 / stepDistance

case 'S' => // out own slave

0.0

case 'B' => // good beast: valuable, but runs away

if(stepDistance == 1) -600

else if(stepDistance == 2) -300

else -(150 - stepDistance \* 15).max(10)

case 'P' => // good plant: less valuable, but does not run

if(stepDistance == 1) -500

else if(stepDistance == 2) -00

else -(150 - stepDistance \* 10).max(10)

case 'b' => // bad beast: dangerous, but only if very close

if(stepDistance < 4) -400 / stepDistance else -50 / stepDistance

case 'p' => // bad plant: bad, but only if I step on it

if(stepDistance < 2) -1000 else 0

case 'W' => // wall: harmless, just don't walk into it

if(stepDistance < 3) -1000 else 0

case '?' =>

-1000

case '\_' => 10

case \_ => 0.0

}

direction45 = cellRelPos.toDirection45

directionValue(direction45) += value

val bestDirection45 = directionValue.zipWithIndex.maxBy(\_.\_1).\_2

direction45 = bestDirection45

}

}

}

(direction45)

}

// almoust the same as master bot target changes if harvest bot have 1500 energy adn is vissable by bot

def analyzeViewAsHarvest(bot: Bot) = {

var view = bot.view

// cia suranda vieta kur eiti

val directionValue = Array.ofDim[Double](8)

var nearestEnemyMaster: Option[XY] = None

var nearestEnemySlave: Option[XY] = None

var nearestMaster: XY = XY(0,0)

val cells = view.cells

val cellCount = cells.length

val cellWeights = Array.ofDim[Double](cellCount)

val indexRel = view.indexFromRelPos(XY(0,0))

// heat map

for(i <- 0 until cellCount) {

val cellRelPos = view.relPosFromIndex(i)

if(cellRelPos.isNonZero && !view.outOfBoundsRel(cellRelPos)) {

cells(i) match {

case 'M' =>

nearestMaster = cellRelPos

case 'm' =>

nearestEnemyMaster = Some(cellRelPos)

for (x <- -4 to 4) {

for (y <- -4 to 4) {

val pos = cellRelPos + XY(x, y)

if (pos.isNonZero && !view.outOfBoundsRel(pos)) {

cellWeights(view.indexFromRelPos(pos)) += 10000

}

}

}

case 's' =>

nearestEnemySlave = Some(cellRelPos)

for (j <- 0 until cellCount) {

val pos = view.relPosFromIndex(j)

if(!bot.view.outOfBoundsRel(pos))

{

val stepDistance = cellRelPos.stepsTo(pos)

if (pos.isNonZero && stepDistance != 0) {

val stepDistance = cellRelPos.stepsTo(pos)

cellWeights(j) += 1000 / stepDistance

}

}

}

case 'P' =>

val pos = view.relPosFromIndex(i)

if(!bot.view.outOfBoundsRel(pos))

{

val stepDistance = cellRelPos.stepsTo(pos)

if (stepDistance == 1) cellWeights(i) += 100

else if (stepDistance == 2) cellWeights(i) += 300

else cellWeights(i) += 500

}

case 'B' =>

val pos = view.relPosFromIndex(i)

val stepDistance = cellRelPos.stepsTo(pos)

if (stepDistance == 1) cellWeights(i) += 50

else if (stepDistance == 2) cellWeights(i) += 200

else cellWeights(i) += 520

case 'b' =>

for (x <- -2 to 2) {

for (y <- -2 to 2) {

val pos = view.relPosFromIndex(i) + XY(x,y)

if(pos.isNonZero && !view.outOfBoundsRel(pos))

{

val index = view.indexFromRelPos(pos)

cellWeights(index) += 2500000

}

}

}

case 'W' => // wall: harmless, just don't walk into it

for (x <- -1 to 1) {

for (y <- -1 to 1) {

val pos = cellRelPos + XY(x, y)

if (pos.isNonZero && !view.outOfBoundsRel(pos)) {

cellWeights(view.indexFromRelPos(pos)) += 1500000

}

}

}

case '?' =>

cellWeights(i) += 1500000

case '\_' =>

cellWeights(i) += 2

case \_ => cellWeights(i) += 1

}

}

}

var direction45 = 0

val lastDirection = bot.inputAsIntOrElse("lastDirection", 0)

val lastCount = bot.inputAsIntOrElse("lastCount", 0).toInt

val previuosStepCount = bot.inputAsIntOrElse("PreviousStepCount", 0).toInt

if ((cells.contains('P') || cells.contains('B') || (cells.contains('M') && bot.energy > 1500)) || (lastCount < 1 && lastCount > 2)) {

var (closestFood) = findClosestThings(cellCount, cells, view, cellWeights, bot)

if(cells.contains('M') && bot.energy > 1500)

{

closestFood = nearestMaster

}

if(!closestFood.isZero)

{

var (path, path\_index, found) = aStarPathfind(cells, XY.Zero, view, closestFood, bot, cellWeights)

if(found && path.size > 0)

{

if(path(path.size - 1) != XY(0,0))

{

if(previuosStepCount == path.size)

{

bot.set("lastCount" -> 1.toString)

}

bot.set("PreviousStepCount" -> path.size)

direction45 = path(path.size - 1).toDirection45

bot.log(direction45.toString)

directionValue(direction45)

}

}

else

{

bot.set("lastCount" -> 1.toString)

}

}

else{

var (temp\_closestFood) = findClosestThings(cellCount, cells, view, cellWeights, bot)

if(cells.contains('M') && bot.energy > 1500)

{

var closestFood = nearestMaster

var (path, path\_index, found) = aStarPathfind(cells, XY.Zero, view, closestFood, bot, cellWeights)

if(found && path.size > 0)

{

if(path(path.size - 1) != XY(0,0))

{

if(previuosStepCount == path.size)

{

bot.set("lastCount" -> 1.toString)

}

bot.set("PreviousStepCount" -> path.size)

direction45 = path(path.size - 1).toDirection45

bot.log(direction45.toString)

directionValue(direction45)

}

}

else

{

bot.set("lastCount" -> 1.toString)

}

}

else

{

if(!bot.view.outOfBoundsRel(temp\_closestFood) && !temp\_closestFood.isZero)

{

var index\_tmp = view.indexFromRelPos(temp\_closestFood)

cellWeights(index\_tmp) += cellWeights(index\_tmp) \* 2

var (closestFood) = findClosestThings(cellCount, cells, view, cellWeights, bot)

var (path, path\_index, found) = aStarPathfind(cells, XY.Zero, view, closestFood, bot, cellWeights)

if(found && path.size > 0)

{

if(path(path.size - 1) != XY(0,0))

{

if(previuosStepCount == path.size)

{

bot.set("lastCount" -> 1.toString)

}

bot.set("PreviousStepCount" -> path.size)

direction45 = path(path.size - 1).toDirection45

bot.log(direction45.toString)

directionValue(direction45)

}

}

else

{

bot.set("lastCount" -> 1.toString)

}

}

}

}

}

else if((!cells.contains('P') && !cells.contains('B') && !cells.contains('M')) || (lastCount > 0 && lastCount < 3))

{

for(i <- 0 until cellCount) {

val cellRelPos = view.relPosFromIndex(i)

if(cellRelPos.isNonZero && !view.outOfBoundsRel(cellRelPos)) {

val stepDistance = cellRelPos.stepCount

val value: Double = cells(i) match {

case 'M' =>

1500000

case 'm' => // another master: not dangerous, but an obstacle

nearestEnemyMaster = Some(cellRelPos)

if(stepDistance < 2) -1000 else 0

case 's' => // another slave: potentially dangerous?

nearestEnemySlave = Some(cellRelPos)

-100 / stepDistance

case 'S' => // out own slave

0.0

case 'B' => // good beast: valuable, but runs away

if(stepDistance == 1) 600

else if(stepDistance == 2) 300

else (150 - stepDistance \* 15).max(10)

case 'P' => // good plant: less valuable, but does not run

if(stepDistance == 1) 500

else if(stepDistance == 2) 300

else (150 - stepDistance \* 10).max(10)

case 'b' => // bad beast: dangerous, but only if very close

if(stepDistance < 4) -400 / stepDistance else -50 / stepDistance

case 'p' => // bad plant: bad, but only if I step on it

if(stepDistance < 2) -1000 else 0

case 'W' => // wall: harmless, just don't walk into it

if(stepDistance < 3) -1000 else 0

case '?' =>

-1000

case '\_' => 10

case \_ => 0.0

}

direction45 = cellRelPos.toDirection45

directionValue(direction45) += value

val bestDirection45 = directionValue.zipWithIndex.maxBy(\_.\_1).\_2

direction45 = bestDirection45

}

}

bot.set("lastCount" -> (lastCount + 1).toString)

}

(direction45)

}

}

// -------------------------------------------------------------------------------------------------

// Framework

// -------------------------------------------------------------------------------------------------

class ControlFunctionFactory {

def create = (input: String) => {

val (opcode, params) = CommandParser(input)

opcode match {

case "React" =>

val bot = new BotImpl(params)

if( bot.generation == 0 ) {

ControlFunction.forMaster(bot)

} else {

ControlFunction.forSlave(bot)

}

bot.toString

case \_ => "" // OK

}

}

}

// -------------------------------------------------------------------------------------------------

trait Bot {

// inputs

def inputOrElse(key: String, fallback: String): String

def inputAsIntOrElse(key: String, fallback: Int): Int

def inputAsXYOrElse(keyPrefix: String, fallback: XY): XY

def view: View

def energy: Int

def time: Int

def generation: Int

// outputs

def move(delta: XY) : Bot

def say(text: String) : Bot

def status(text: String) : Bot

def spawn(offset: XY, params: (String,Any)\*) : Bot

def set(params: (String,Any)\*) : Bot

def log(text: String) : Bot

}

trait MiniBot extends Bot {

// inputs

def offsetToMaster: XY

// outputs

def explode(blastRadius: Int) : Bot

}

case class BotImpl(inputParams: Map[String, String]) extends MiniBot {

// input

def inputOrElse(key: String, fallback: String) = inputParams.getOrElse(key, fallback)

def inputAsIntOrElse(key: String, fallback: Int) = inputParams.get(key).map(\_.toInt).getOrElse(fallback)

def inputAsXYOrElse(key: String, fallback: XY) = inputParams.get(key).map(s => XY(s)).getOrElse(fallback)

val view = View(inputParams("view"))

val energy = inputParams("energy").toInt

val time = inputParams("time").toInt

val generation = inputParams("generation").toInt

def offsetToMaster = inputAsXYOrElse("master", XY.Zero)

// output

private var stateParams = Map.empty[String,Any] // holds "Set()" commands

private var commands = "" // holds all other commands

private var debugOutput = "" // holds all "Log()" output

/\*\* Appends a new command to the command string; returns 'this' for fluent API. \*/

private def append(s: String) : Bot = { commands += (if(commands.isEmpty) s else "|" + s); this }

/\*\* Renders commands and stateParams into a control function return string. \*/

override def toString = {

var result = commands

if(!stateParams.isEmpty) {

if(!result.isEmpty) result += "|"

result += stateParams.map(e => e.\_1 + "=" + e.\_2).mkString("Set(",",",")")

}

if(!debugOutput.isEmpty) {

if(!result.isEmpty) result += "|"

result += "Log(text=" + debugOutput + ")"

}

result

}

def log(text: String) = { debugOutput += text + "\n"; this }

def move(direction: XY) = append("Move(direction=" + direction + ")")

def say(text: String) = append("Say(text=" + text + ")")

def status(text: String) = append("Status(text=" + text + ")")

def explode(blastRadius: Int) = append("Explode(size=" + blastRadius + ")")

def spawn(offset: XY, params: (String,Any)\*) =

append("Spawn(direction=" + offset +

(if(params.isEmpty) "" else "," + params.map(e => e.\_1 + "=" + e.\_2).mkString(",")) +

")")

def set(params: (String,Any)\*) = { stateParams ++= params; this }

def set(keyPrefix: String, xy: XY) = { stateParams ++= List(keyPrefix+"x" -> xy.x, keyPrefix+"y" -> xy.y); this }

}

// -------------------------------------------------------------------------------------------------

/\*\* Utility methods for parsing strings containing a single command of the format

\* "Command(key=value,key=value,...)"

\*/

object CommandParser {

/\*\* "Command(..)" => ("Command", Map( ("key" -> "value"), ("key" -> "value"), ..}) \*/

def apply(command: String): (String, Map[String, String]) = {

/\*\* "key=value" => ("key","value") \*/

def splitParameterIntoKeyValue(param: String): (String, String) = {

val segments = param.split('=')

(segments(0), if(segments.length>=2) segments(1) else "")

}

val segments = command.split('(')

if( segments.length != 2 )

throw new IllegalStateException("invalid command: " + command)

val opcode = segments(0)

val params = segments(1).dropRight(1).split(',')

val keyValuePairs = params.map(splitParameterIntoKeyValue).toMap

(opcode, keyValuePairs)

}

}

// -------------------------------------------------------------------------------------------------

/\*\* Utility class for managing 2D cell coordinates.

\* The coordinate (0,0) corresponds to the top-left corner of the arena on screen.

\* The direction (1,-1) points right and up.

\*/

case class XY(x: Int, y: Int) {

override def toString = x + ":" + y

def isNonZero = x != 0 || y != 0

def isZero = x == 0 && y == 0

def isNonNegative = x >= 0 && y >= 0

def updateX(newX: Int) = XY(newX, y)

def updateY(newY: Int) = XY(x, newY)

def addToX(dx: Int) = XY(x + dx, y)

def addToY(dy: Int) = XY(x, y + dy)

def +(pos: XY) = XY(x + pos.x, y + pos.y)

def -(pos: XY) = XY(x - pos.x, y - pos.y)

def \*(factor: Double) = XY((x \* factor).intValue, (y \* factor).intValue)

def distanceTo(pos: XY): Double = (this - pos).length // Phythagorean

def length: Double = math.sqrt(x \* x + y \* y) // Phythagorean

def stepsTo(pos: XY): Int = (this - pos).stepCount // steps to reach pos: max delta X or Y

def stepCount: Int = x.abs.max(y.abs) // steps from (0,0) to get here: max X or Y

def signum = XY(x.signum, y.signum)

def negate = XY(-x, -y)

def negateX = XY(-x, y)

def negateY = XY(x, -y)

/\*\* Returns the direction index with 'Right' being index 0, then clockwise in 45 degree steps. \*/

def toDirection45: Int = {

val unit = signum

unit.x match {

case -1 =>

unit.y match {

case -1 =>

if(x < y \* 3) Direction45.Left

else if(y < x \* 3) Direction45.Up

else Direction45.UpLeft

case 0 =>

Direction45.Left

case 1 =>

if(-x > y \* 3) Direction45.Left

else if(y > -x \* 3) Direction45.Down

else Direction45.LeftDown

}

case 0 =>

unit.y match {

case 1 => Direction45.Down

case 0 => throw new IllegalArgumentException("cannot compute direction index for (0,0)")

case -1 => Direction45.Up

}

case 1 =>

unit.y match {

case -1 =>

if(x > -y \* 3) Direction45.Right

else if(-y > x \* 3) Direction45.Up

else Direction45.RightUp

case 0 =>

Direction45.Right

case 1 =>

if(x > y \* 3) Direction45.Right

else if(y > x \* 3) Direction45.Down

else Direction45.DownRight

}

}

}

def rotateCounterClockwise45 = XY.fromDirection45((signum.toDirection45 + 1) % 8)

def rotateCounterClockwise90 = XY.fromDirection45((signum.toDirection45 + 2) % 8)

def rotateClockwise45 = XY.fromDirection45((signum.toDirection45 + 7) % 8)

def rotateClockwise90 = XY.fromDirection45((signum.toDirection45 + 6) % 8)

def wrap(boardSize: XY) = {

val fixedX = if(x < 0) boardSize.x + x else if(x >= boardSize.x) x - boardSize.x else x

val fixedY = if(y < 0) boardSize.y + y else if(y >= boardSize.y) y - boardSize.y else y

if(fixedX != x || fixedY != y) XY(fixedX, fixedY) else this

}

}

object XY {

/\*\* Parse an XY value from XY.toString format, e.g. "2:3". \*/

def apply(s: String) : XY = { val a = s.split(':'); XY(a(0).toInt,a(1).toInt) }

val Zero = XY(0, 0)

val One = XY(1, 1)

val Right = XY( 1, 0)

val RightUp = XY( 1, -1)

val Up = XY( 0, -1)

val UpLeft = XY(-1, -1)

val Left = XY(-1, 0)

val LeftDown = XY(-1, 1)

val Down = XY( 0, 1)

val DownRight = XY( 1, 1)

def fromDirection45(index: Int): XY = index match {

case Direction45.Right => Right

case Direction45.RightUp => RightUp

case Direction45.Up => Up

case Direction45.UpLeft => UpLeft

case Direction45.Left => Left

case Direction45.LeftDown => LeftDown

case Direction45.Down => Down

case Direction45.DownRight => DownRight

}

def fromDirection90(index: Int): XY = index match {

case Direction90.Right => Right

case Direction90.Up => Up

case Direction90.Left => Left

case Direction90.Down => Down

}

def apply(array: Array[Int]): XY = XY(array(0), array(1))

}

object Direction45 {

val Right = 0

val RightUp = 1

val Up = 2

val UpLeft = 3

val Left = 4

val LeftDown = 5

val Down = 6

val DownRight = 7

}

object Direction90 {

val Right = 0

val Up = 1

val Left = 2

val Down = 3

}

// -------------------------------------------------------------------------------------------------

case class View(cells: String) {

val size = math.sqrt(cells.length).toInt

val center = XY(size / 2, size / 2)

val cellCount = cells.length

def apply(relPos: XY) = cellAtRelPos(relPos)

def indexFromAbsPos(absPos: XY) = absPos.x + absPos.y \* size

def absPosFromIndex(index: Int) = XY(index % size, index / size)

def absPosFromRelPos(relPos: XY) = relPos + center

def cellAtAbsPos(absPos: XY) = cells.charAt(indexFromAbsPos(absPos))

def indexFromRelPos(relPos: XY) = indexFromAbsPos(absPosFromRelPos(relPos))

def relPosFromAbsPos(absPos: XY) = absPos - center

def relPosFromIndex(index: Int) = relPosFromAbsPos(absPosFromIndex(index))

def cellAtRelPos(relPos: XY) = cells.charAt(indexFromRelPos(relPos))

def offsetToNearest(c: Char) = {

val matchingXY = cells.view.zipWithIndex.filter(\_.\_1 == c)

if( matchingXY.isEmpty )

None

else {

val nearest = matchingXY.map(p => relPosFromIndex(p.\_2)).minBy(\_.length)

Some(nearest)

}

}

def outOfBoundsRel(relPos: XY) = {

if(math.abs(relPos.x) > center.x || math.abs(relPos.y) > center.y){

true

}

else{

false

}

}

def outOfBoundsAbs(absPos: XY) = {

if(absPos.x < 0 || absPos.x > (size-1) || absPos.y < 0 || absPos.y > (size-1)){

true

}

else{

false

}

}

}

## Pardiniai duomenys ir rezultatai

 