```python
from queue import PriorityQueue
v = 14
graph = [[] for i in range(v)]


def best_first_search(actual_Src, target, n):
    visited = [False] * n
    pq = PriorityQueue()
    pq.put((0, actual_Src))
    visited[actual_Src] = True

    while pq.empty() == False:
        u = pq.get()[1]
        print(u, end=" ")
        if u == target:
            break

        for v, c in graph[u]:
            if visited[v] == False:
                visited[v] = True
                pq.put((c, v))
    print()


def addedge(x, y, cost):
    graph[x].append((y, cost))
    graph[y].append((x, cost))

addedge(0, 1, 3)
addedge(0, 2, 6)
addedge(0, 3, 5)
addedge(1, 4, 9)
addedge(1, 5, 8)
addedge(2, 6, 12)
addedge(2, 7, 14)
addedge(3, 8, 7)
addedge(8, 9, 5)
addedge(8, 10, 6)
addedge(9, 11, 1)
addedge(9, 12, 10)
addedge(9, 13, 2)

source = 0
target = 9
best_first_search(source, target, v)
```

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0 1 3 2 8 9
```

```python
from collections import deque

class Graph:

    def __init__(self, adjacency_list):
        self.adjacency_list = adjacency_list

    def get_neighbors(self, v):
        return self.adjacency_list[v]
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    def h(self, n):
        H = {
            'A': 10,
            'B': 5,
            'C': 4,
            'D': 6,
            'E': 4
        }

        return H[n]

    def a_star_algorithm(self, start_node, stop_node):
        open_list = set([start_node])
        closed_list = set([])

        g = {}

        g[start_node] = 0

        parents = {}
        parents[start_node] = start_node

        while len(open_list) > 0:
            n = None

            for v in open_list:
                if n == None or g[v] + self.h(v) < g[n] + self.h(n):
                    n = v;

            if n == None:
                print('Path does not exist!')
                return None

            if n == stop_node:
                reconst_path = []

                while parents[n] != n:
                    reconst_path.append(n)
                    n = parents[n]

                reconst_path.append(start_node)

                reconst_path.reverse()

                print('Path found: {}'.format(reconst_path))
                return reconst_path

            for (m, weight) in self.get_neighbors(n):

                if m not in open_list and m not in closed_list:
                    open_list.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_list:
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                                closed_list.remove(m)
                                open_list.add(m)

                open_list.remove(n)
                closed_list.add(n)

            print('Path does not exist!')
            return None

adjacency_list = {
    'A': [('B', 1), ('C', 3), ('D', 7)],
    'B': [('D', 5)],
    'C': [('E', 12)],
    'D': [('E', 6)]
}
graph1 = Graph(adjacency_list)
graph1.a_star_algorithm('A', 'E')
```

```
Path found: ['A', 'B', 'D', 'E']
['A', 'B', 'D', 'E']
```