activity 1

```
class node:
  def __init__(self, state, parent, actions, totalcost):
    self.state = state
    self.parent = parent
    self.actions = actions
    self.totalcost = totalcost

graph = {'A': node('A', None, ['B','C','E'], None),
         'B': node('B', None, ['A','D','E'], None),
         'C': node('C', None, ['A','F','G'], None),
         'D': node('D', None, ['B','E'], None),
         'E': node('E', None, ['A','B','D'], None),
         'F': node('F', None, ['C'], None),
         'G': node('G', None, ['C'], None)
        }
```

Activity 2

```
class node:
  def __init__(self, state, parent, actions, totalcost):
    self.state = state
    self.parent = parent
    self.actions = actions
    self.totalcost = totalcost

def actionSequence(graph, initialstate, goalstate):
  solution = [goalstate]
  currentparent = graph[goalstate].parent
  while currentparent != None:
    solution.append(currentparent)
    currentparent = graph[currentparent].parent
  solution.reverse()
  return solution

def bfs(initialstate, goalstate):
  graph = {
    'A': node('A', None, ['B', 'C', 'E'], None),
    'B': node('B', None, ['A', 'D', 'E'], None),
    'C': node('C', None, ['A', 'F', 'G'], None),
    'D': node('D', None, ['B', 'E'], None),
    'E': node('E', None, ['A', 'B', 'D'], None),
    'F': node('F', None, ['C'], None),
    'G': node('G', None, ['C'], None)
  }

  frontier = [initialstate]
  explored = []

  while frontier:
    currentnode = frontier.pop(0)
    explored.append(currentnode)
    for child in graph[currentnode].actions:
      if child not in frontier and child not in explored:
        graph[child].parent = currentnode
        if graph[child].state == goalstate:
          return actionSequence(graph, initialstate, goalstate)
        frontier.append(child)

  return None

solution = bfs('D', 'C')
print(solution)
```

```
['D', 'B', 'A', 'C']
```

activity 3

```
class node:
  def __init__(self, state, parent, actions, totalcost):
    self.state = state
    self.parent = parent
    self.actions = actions
    self.totalcost = totalcost

def actionSequence(graph, initialstate, goalstate):
  solution = [goalstate]
  currentparent = graph[goalstate].parent

  while currentparent is not None:
    solution.append(currentparent)
    currentparent = graph[currentparent].parent

  solution.reverse()
  return solution

def bfs(initialstate, goalstate):
  graph = {
    'A': node('A', None, ['B', 'C', 'E'], None),
    'B': node('B', None, ['A', 'D', 'E'], None),
    'C': node('C', None, ['A', 'F', 'G'], None),
    'D': node('D', None, ['B', 'E'], None),
    'E': node('E', None, ['A', 'B', 'D'], None),
    'F': node('F', None, ['C'], None),
    'G': node('G', None, ['C'], None)
  }

  frontier = [initialstate]
  explored = []

  while frontier:
    currentnode = frontier.pop(0)
    explored.append(currentnode)
    for child in graph[currentnode].actions:
      if child not in frontier and child not in explored:
        graph[child].parent = currentnode
        if graph[child].state == goalstate:
          return actionSequence(graph, initialstate, goalstate)
        frontier.append(child)

  return None

solution = bfs('D', 'C')
print(solution)
```

```
['D', 'B', 'A', 'C']
```

activity 4

```
import heapq

# Define the graph as a dictionary
graph = {
    'Arad': [('Zerind', 75), ('Timisoara', 118), ('Sibiu', 140)],
    'Zerind': [('Oradea', 71), ('Arad', 75)],
    'Oradea': [('Sibiu', 151), ('Zerind', 71)],
    'Timisoara': [('Arad', 118), ('Lugoj', 111)],
    'Lugoj': [('Timisoara', 111), ('Mehadia', 70)],
    'Mehadia': [('Lugoj', 70), ('Drobeta', 75)],
    'Drobeta': [('Mehadia', 75), ('Craiova', 120)],
    'Sibiu': [('Arad', 140), ('Oradea', 151), ('Fagaras', 99), ('Rimnicu Vilcea', 80)],
    'Fagaras': [('Sibiu', 99), ('Bucharest', 211)],
    'Rimnicu Vilcea': [('Sibiu', 80), ('Craiova', 146), ('Pitesti', 97)],
    'Craiova': [('Drobeta', 120), ('Rimnicu Vilcea', 146), ('Pitesti', 138)],
    'Pitesti': [('Rimnicu Vilcea', 97), ('Craiova', 138), ('Bucharest', 101)],
    'Bucharest': [('Fagaras', 211), ('Pitesti', 101)]
}

def uniform_cost_search(start, goal):
    # Keep track of visited nodes and their distances from the start node
    visited = {start: 0}
    # Keep track of the nodes in the path from the start node to the current node
    path = {start: [start]}
```

```
    # Initialize the heap with the start node and its cost
    heap = [(0, start)]

    while heap:
        # Pop the node with the lowest cost from the heap
        (cost, current) = heapq.heappop(heap)

        # If we have reached the goal node, return the path
        if current == goal:
            return path[current]

        # Loop through the neighboring nodes
        for (neighbor, neighbor_cost) in graph[current]:
            # Calculate the new cost to reach the neighboring node
            new_cost = visited[current] + neighbor_cost

            # If the neighboring node hasn't been visited yet or the new cost is lower than the current cost
            if neighbor not in visited or new_cost < visited[neighbor]:
                # Update the visited dictionary and the path dictionary
                visited[neighbor] = new_cost
                path[neighbor] = path[current] + [neighbor]
                # Add the neighboring node and its cost to the heap
                heapq.heappush(heap, (new_cost, neighbor))


    return None


start = 'Arad'
goal = 'Bucharest'
path = uniform_cost_search(start, goal)
print(path)
```

```
['Arad', 'Sibiu', 'Rimnicu Vilcea', 'Pitesti', 'Bucharest']
```

Activity no 4

```
import math

def findmin(frontier):
    minV = math.inf
    node = ''
    for i in frontier:
        if minV > frontier[i][1]:
            minV = frontier[i][1]
            node = i
    return node

def actionSequence(graph, initialstate, goalstate):
    solution = [goalstate]
    currentparent = graph[goalstate].parent
    while currentparent is not None:
        solution.append(currentparent)
        currentparent = graph[currentparent].parent
    solution.reverse()
    return solution

class node:
    def __init__(self, state, parent, actions, totalcost):
        self.state = state
        self.parent = parent
        self.actions = actions
        self.totalcost = totalcost

def UCS(initialstate, goalstate):
    graph = {
        'A': node('A', None, [('B', 6), ('C', 9), ('E', 1)], 0),
        'B': node('B', None, [('A', 6), ('D', 3), ('E', 4)], 0),
        'C': node('C', None, [('A', 9), ('F', 2), ('G', 3)], 0),
        'D': node('D', None, [('B', 3), ('E', 5), ('F', 7)], 0),
        'E': node('E', None, [('A', 1), ('B', 4), ('D', 5), ('F', 6)], 0),
        'F': node('F', None, [('C', 2), ('E', 6), ('D', 7)], 0),
        'G': node('G', None, [('C', 3)], 0)
    }
    frontier = dict()
    frontier[initialstate] = (None, 0)
```

```
    explored = []

    while frontier:
        currentnode = findmin(frontier)
        del frontier[currentnode]
        if graph[currentnode].state == goalstate:
            return actionSequence(graph, initialstate, goalstate)
        explored.append(currentnode)
        for child in graph[currentnode].actions:
            currentcost = child[1] + graph[currentnode].totalcost
            if child[0] not in frontier and child[0] not in explored:
                graph[child[0]].parent = currentnode
                graph[child[0]].totalcost = currentcost
                frontier[child[0]] = (graph[child[0]].parent, graph[child[0]].totalcost)
            elif child[0] in frontier:
                if frontier[child[0]][1] > currentcost:
                    graph[child[0]].parent = currentnode
                    graph[child[0]].totalcost = currentcost
                    frontier[child[0]] = (graph[child[0]].parent, graph[child[0]].totalcost)

solution = UCS('C', 'B')
print(solution)
```

```
['C', 'F', 'E', 'B']
```