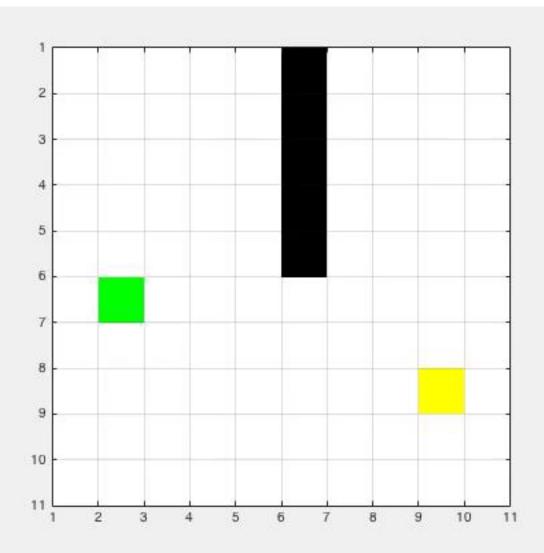
A-Star Procedure

SECTION 1.4



Dijkstra/Grassfire Algorithm





Dijkstra/Grassfire Algorithm

- When applied on a grid graph where all of the edges have the same length, Dijkstra's algorithm and the grassfire procedure have similar behaviors.
- They both explore nodes in order based on their distance from the starting node until they encounter the goal.



A* Search

 A* Search attempts to improve upon the performance of grassfire and Dijkstra by incorporating a heuristic function that guides the path planner.



Heuristic Functions

- Heuristic functions are used to map every node in the graph to a non-negative value
- Heuristic Function Criteria:
 - o H(goal) = 0
 - o For any 2 adjacent nodes x and y

$$H(x) <= H(y) + d(x,y)$$

d(x,y) = weight/length of edge from x to y

- These properties ensure that for all nodes, n
 - o $H(n) \le length of shortest path from n to goal.$



Example Heuristic Functions

- For path planning on a grid the following 2 heuristic functions are often used
 - Euclidean Distance

$$H(x_n, y_n) = \sqrt{((x_n - x_g)^2 + (y_n - y_g)^2)}$$
 (1)

- Manhattan Distance

$$H(x_n, y_n) = |(x_n - x_g)| + |(y_n - y_g)|$$
 (2)

- where (x_n, y_n) denotes the coordinates of the node n and (x_g, y_g) denotes the coordinate of the goal

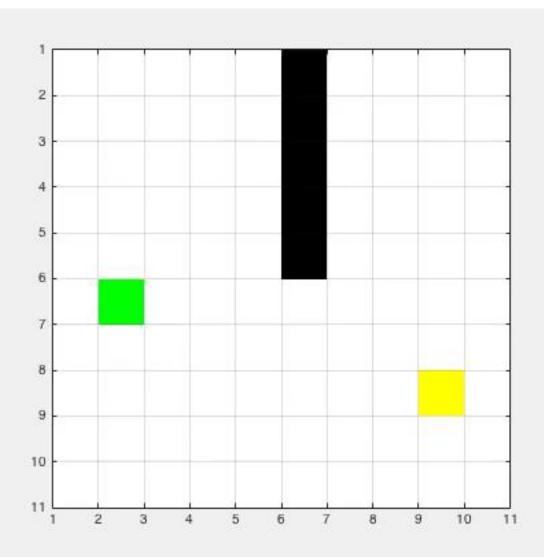


A* algorithm – pseudo code

- For each node n in the graph
 o n.f = Infinity, n.g = Infinity
- Create an empty list.
- start.g = 0, start.f = H(start) add start to list.
- While list not empty
 - o Let current = node in the list with the smallest f value, remove current from list
 - o If (current == goal node) report success
 - o For each node, n that is adjacent to current
 If (n.g > (current.g + cost of edge from n to current))
 n.g = current.g + cost of edge from n to current
 n.f = n.g + H(n)
 n.parent = current
 add n to list if it isn't there already



Dijkstra's Algorithm





A* Algorithm

