

1. Write a python program to trace out how the searching process works for the given graph using bidirectional Search.



**Program :**

```
from collections import deque
```

```
def bidirectional_search(graph, start, goal):
```

```
    forward_queue = deque([(start, [start])])
```

```
    backward_queue = deque([(goal, [goal])])
```

```
    forward_visited = set([start])
```

```
    backward_visited = set([goal])
```

```
    while forward_queue and backward_queue:
```

```
        forward_node, forward_path = forward_queue.popleft()
```

```
        backward_node, backward_path = backward_queue.popleft()
```

```
        if forward_node in backward_visited:
```

```
            intersection_node = forward_node
```

```
            intersection_path = forward_path + backward_path[::-1]
```

```
            return intersection_path
```

```
for neighbor in graph[forward_node]:  
    if neighbor not in forward_visited:  
        forward_visited.add(neighbor)  
        forward_queue.append((neighbor, forward_path + [neighbor]))
```

```
if backward_node in forward_visited:  
    intersection_node = backward_node  
    intersection_path = forward_path + backward_path[::-1]  
    return intersection_path
```

```
for neighbor in graph[backward_node]:  
    if neighbor not in backward_visited:  
        backward_visited.add(neighbor)  
        backward_queue.append((neighbor, backward_path + [neighbor]))
```

```
return None # No intersection found
```

```
def main():  
    # Example graph represented as an adjacency list  
    graph = {  
        'A': ['B', 'C'],  
        'B': ['A', 'D', 'E'],  
        'C': ['A', 'F', 'G'],  
        'D': ['B'],
```

```
'E': ['B', 'H'],  
'F': ['C', 'I'],  
'G': ['C'],  
'H': ['E', 'J'],  
'I': ['F'],  
'J': ['H']  
}
```

```
start_node = 'A'
```

```
goal_node = 'J'
```

```
result_path = bidirectional_search(graph, start_node, goal_node)
```

```
if result_path:
```

```
    print(f"Path from {start_node} to {goal_node}: {result_path}")
```

```
else:
```

```
    print("No path found between the start and goal nodes.")
```

```
if __name__ == "__main__":
```

```
    main()
```

**Output :**

Path from A to J: ['A', 'C', 'E', 'H', 'J']