Report

April 8, 2022

1 Team Members

Name	ID	Department
Ahmed Ashraf	2022446758	Business
Abdelrhman Mohamed Abdelhady	2022513643	Intelligent Systems
Antonuose Gerges Nageh	20221903971	Intelligent Systems

2 Data Structures used

- Node custom made structure
- Tree custom made structure
- ArrayList
- Queue
- Stack
- Priority Queue
- HashTable
- Enumeration
- ActionPath custom made structure

2.1 Action Enumeration

It's used to represent that action taken by the parent node to reach the child node and it contains the following

- Up
- Down
- Left
- Right

2.2 Creating the Node

The Node will contain the following data fields:

- Parent:Node
- Children:ArrayList
- state:int[][]
- stringState:String which will be used to generate a hash code and compare it the goal state
- ullet Direction:Action $Action\ taken\ to\ reach\ this\ node$

• depth:int

• missingTileRow:int

- missingTileCol:int
- cost:int

It contains the following methods:

- CreateStringBoard(): String which creates a string of the state of the node
- addChild(Node child): void which is a helper function when creating a child'
- CreateChild(int a, int b):void Creates a child where paramaters a,b represent the position of missing tile
- getRowCol(int value):int[] returns an array of size two, the method is used in calculating the herustic functions
- equals(Object obj):boolean Override It overrides the default equals method
- isGoal():boolean checks if the Node state is the goal state
- hashCode():int Override overrides the default hashCode method so that it returns the hash code of the string state
- toString:String Override Overrides the default toString method and makes use of the string builder object

2.3 Creating the ActionPath class

The main goal of this class is to use backtracking the print the path from the goal node to the root node with the neccessary information. The class uses the Stack data-structure *LIFO* where we are going to use the property that the last element that enters the stack is the first element that exits.

The methods the class contains are as follows:

- getPath:Stack
- printPath:void

getpath functions takes both the root node and goal node as inputs and pushes the goal node parents inside it till it reaches the root node.

printPath function returns nothing, it is only used for printing the path from the root to the goal.

2.4 Creating the Tree

The tree class will contain the search functions as well as the expand function for the nodes.

Moreover, it contains the $f_1 \& f_2$ Comparator objects that will be used in the priority queue.

It has only one data field: root:Node

The inner classes:

- **f_1** which implements Comparator used to determine whic node should enter the priorty queue first, It uses the manhattan distance herustic
- f_2 has the same functionality as f_1 but uses the Euclidean distance herustic

The methods:

• expand(Node node):List<Node> returns a list of the children of the given node i.e. it expands it

- breadthFirstSearch(): boolean returns true if the search is successful otherwise return false
- depthFirstSearch():boolean returns true if the search is successful otherwise return false
- manhattanDistance(Node n):int which calculates the manhattan distance
- euclideanDistance(Node n):int which calculates the euclidean distance
- aStar(int i):boolean which implements the A* star search, i paramter is used to determine which herustic to use

3 Breadth First Search: 1 2 3 4 0 5 6 7 8

Testing the Breadth first search.

Breadth frist search was implemented with an early goal test.

Welcome to 8 puzzle Solver

Enter the puzzle : 1 2 3 4 0 5 6 7 8

Choose the Algorithm

- 1. BFS
- 2. DFS
- 3. A*

Enter your choice: 1

The root node

- 1 2 3 4 0 5 6 7 8
- _____

Current Node:

1 2 3 0 4 5 6 7 8

Direction Moved: Left

Depth: 1 Cost: 1

Current Node:

0 2 3 1 4 5 6 7 8

Direction Moved: Up

Depth: 2 Cost: 2

Current Node:

2	0	3
1	4	5
6	7	8

Direction Moved: Right

Depth: 3 Cost: 3

Current Node:

2 3 0 1 4 5 6 7 8

Direction Moved: Right

Depth: 4
Cost: 4

Current Node:

2 3 5 1 4 0 6 7 8

Direction Moved: Down

Depth: 5 Cost: 5

Current Node:

2 3 5 1 0 4 6 7 8

Direction Moved: Left

Depth: 6 Cost: 6

Current Node:

2 0 5 1 3 4 6 7 8

Direction Moved: Up

Depth: 7 Cost: 7

Current	t Node	:
0 1 6	2 3 7	5 4 8
Depth: Cost: 8	8	ved: Left
Current	t Node	:
1 0 6	2 3 7	5 4 8
Direct: Depth: Cost: 9	9 9	ved: Down
Current	t Node	:
1 3 6	2 0 7	5 4 8
Direct: Depth: Cost:	10	ved: Right
Curren	t Node	:
1 3 6	2 4 7	5 0 8
Direct: Depth: Cost:	11	ved: Right

Current Node:

1 2 0 3 4 5 6 7 8

Direction Moved: Up

Depth: 12 Cost: 12

Current Node:

1 0 2 3 4 5 6 7 8

Direction Moved: Left

Depth: 13 Cost: 13

Current Node:

0 1 2 3 4 5 6 7 8

Direction Moved: Left

Depth: 14 Cost: 14

Time: 82.0 millie seconds

Space: 3718

4 Depth First Search: 1 0 2 3 4 5 6 7 8

The implementation contains an early goal test even though that might not result in the optimal solution but it results in better search time.

Welcome to 8 puzzle Solver

Enter the puzzle : 1 0 2 3 4 5 6 7 8 $\,$

Choose the Algorithm

- 1. BFS
- 2. DFS
- 3. A*

Enter your choice: 2

The root node

1 0 2 3 4 5 6 7 8

Current Node:

0 1 2

3 4 5 6 7 8

Direction Moved: Left

Depth: 1 Cost: 1

Time: 0.0 millie seconds

Space: 2

5 A* search

5.1 Manhattan distance - puzzle : 1 2 3 4 5 6 7 8 0

The first Search -Manhatten distance- using the following puzzle : 1 2 3 4 5 6 7 8 0

Welcome to 8 puzzle Solver

Enter the puzzle : 1 2 3 4 5 6 7 8 0

Choose the Algorithm

- 1. BFS
- 2. DFS
- 3. A*

Enter your choice: 3

Choose the Heuristic function

- 1. Manhattan Distance
- 2. Euclidean Distance

Enter your choice: 1

The root node

1 2 3 4 5 6 7 8 0

Current Node:

1 2 3 4 5 6 7 0 8

Direction Moved: Left

Depth: 1 Cost: 1

Current Node:

1	2	3	
4	0	6	
7	5	8	

Direction Moved: Up

Depth: 2 Cost: 2

Current Node:

1 2 3 4 6 0 7 5 8

Direction Moved: Right

Depth: 3 Cost: 3

Current Node:

1 2 0 4 6 3 7 5 8

Direction Moved: Up

Depth: 4 Cost: 4

Current Node:

1 0 2 4 6 3 7 5 8

Direction Moved: Left

Depth: 5 Cost: 5

Current Node:

0 1 2 4 6 3 7 5 8

Direction Moved: Left

Depth: 6 Cost: 6

Current Node:

4 1 2 0 6 3 7 5 8

Direction Moved: Down

Depth: 7 Cost: 7

Current Node:

4 1 2 6 0 3 7 5 8

Direction Moved: Right

Depth: 8 Cost: 8

Current Node:

4 1 2 6 3 0 7 5 8

Direction Moved: Right

Depth: 9
Cost: 9

Current Node:

4 1 0 6 3 2 7 5 8

Direction Moved: Up

Depth: 10 Cost: 10

Current Node:

4 0 1 6 3 2 7 5 8

Direction Moved: Left

Depth: 11

Cost: 1:	1	
Current		
4 6 7	3 0 5	1 2 8
Depth: 1		: Down
Current		
4 6 7	3 5 0	1 2 8
Direction Depth: 1		: Down
Current	Node:	
4 6 0	3 5 7	1 2 8
Depth: 1		
Current		
4 0 6	3 5 7	1 2 8
Depth: 1		_
Current		

 Direction Moved: Up

Depth: 16 Cost: 16

Current Node:

3 0 1 4 5 2 6 7 8

Direction Moved: Right

Depth: 17 Cost: 17

Current Node:

3 1 0 4 5 2 6 7 8

Direction Moved: Right

Depth: 18 Cost: 18

Current Node:

3 1 2 4 5 0 6 7 8

Direction Moved: Down

Depth: 19 Cost: 19

Current Node:

3 1 2 4 0 5 6 7 8

Direction Moved: Left

Depth: 20 Cost: 20

Current Node:

3 1 2 0 4 5 6 7 8

Direction Moved: Left

Depth: 21 Cost: 21

Current Node:

0 1 2 3 4 5 6 7 8

Direction Moved: Up

Depth: 22 Cost: 22

Time: 21.0 millie seconds

Space: 1529

5.2 Euclidean distance - puzzle : 1 2 3 4 5 6 7 8 0

The second search uses the ecludiean distance to find goal node. It uses the same puzzle as the manhattan herustic

Welcome to 8 puzzle Solver

Enter the puzzle : 1 2 3 4 5 6 7 8 0

Choose the Algorithm

- 1. BFS
- 2. DFS
- 3. A*

Enter your choice: 3

Choose the Heuristic function

- 1. Manhattan Distance
- 2. Euclidean Distance

Enter your choice: 2

The root node

1 2 3 4 5 6 7 8 0

Current Node:

1 2 3 4 5 6 7 0 8 Direction Moved: Left Depth: 1 Cost: 1 _____ Current Node: 2 3 4 0 6 7 5 8 Direction Moved: Up Depth: 2 Cost: 2 -----Current Node:

1 2 3 4 6 0 7 5 8

Direction Moved: Right

Depth: 3 Cost: 3

Current Node:

1 2 0 4 6 3 7 5 8

Direction Moved: Up

Depth: 4
Cost: 4

Current Node:

1 0 2 4 6 3 7 5 8

Direction Moved: Left

Depth: 5 Cost: 5

Current Node:

0	1	2
4	6	3
7	5	8

Direction Moved: Left

Depth: 6 Cost: 6

Current Node:

4 1 2 0 6 3 7 5 8

Direction Moved: Down

Depth: 7 Cost: 7

Current Node:

4 1 2 6 0 3 7 5 8

Direction Moved: Right

Depth: 8 Cost: 8

Current Node:

4 1 2 6 3 0 7 5 8

Direction Moved: Right

Depth: 9 Cost: 9

Current Node:

4 1 0 6 3 2 7 5 8

Direction Moved: Up

Depth: 10 Cost: 10

Current Node:

4	0	1
6	3	2
7	5	8

Direction Moved: Left

Depth: 11 Cost: 11

Current Node:

4	3	1	
6	0	2	
7	5	8	

Direction Moved: Down

Depth: 12 Cost: 12

Current Node:

4	3	1	
6	5	2	
7	0	8	

Direction Moved: Down

Depth: 13 Cost: 13

Current Node:

4	3	1
6	5	2
0	7	8

Direction Moved: Left

Depth: 14 Cost: 14

Current Node:

4	3	1
0	5	2
6	7	8

Direction Moved: Up

Depth: 15

Cost: 1	5	
Current	Node:	
0 4 6	3 5 7	1 2 8
Directi Depth: Cost: 1	16 6	ed: Up
Current		
3 4 6	0 5 7	1 2 8
Directi Depth: Cost: 1	17 7	ed: Right
Current	Node:	
3 4 6	1 5 7	0 2 8
Directi Depth: Cost: 1	18	ed: Right
Current	Node:	
3 4 6	1 5 7	2 0 8
Directi Depth: Cost: 1	19	ed: Down

Current Node:

3 1 2 4 0 5 6 7 8 Direction Moved: Left

Depth: 20 Cost: 20

Current Node:

3 1 2 0 4 5 6 7 8

Direction Moved: Left

Depth: 21 Cost: 21

Current Node:

0 1 2 3 4 5 6 7 8

Direction Moved: Up

Depth: 22 Cost: 22

Time: 70 0 millio accorde

Time: 79.0 millie seconds

Space: 5827