A* Algorthim for path planning for the rescue robot

Given: robot_pos, goal_pos, map

```
robot_node = Node(robot.get_pos(), parent_Node=None);
open_list = PriorityQueue(robot_node);
CheckedNodes = List(robot_node);
while open_list.!empty() do
        currentNode = open_list.pop();
        if currentNode.position == goal.position then
                CheckedNode.add(currentNode);
                break;
        end
        foreach aNeighborNode in neighborNodesOf(currentNode, map) do
                priority = get_cost_of(aNeighborNode);
                open_list.add_with_priority(aNeighborNode, priority);
                CheckedNodes.add(aNeighborNode);
        end
end
path_to_follow = calc_path_to_follow(CheckedNodes);
return path_to_follow
```