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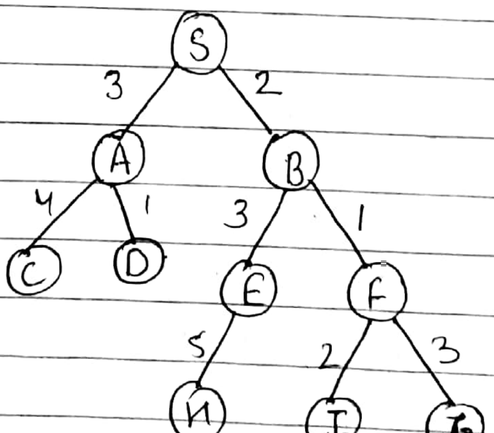
Lab-5

Aim - Developing Best First search and A* algorithm for real world problems.

(i) Developing Best First search Algorithm for real world problem

Problem Formulation

Given a graph, starting node and h(n), use the evaluation function to decide which is the most promising node for reaching to the destination and explore it till reaches the destination.
Display the path and cost function



Node	h(n)
A	12
B	4
C	7
D	3
E	8
F	2
G	0
H	4
I	9
S	13

Initial state
Open: [S]
Closed: [ ]

Final State
Open: [I, E, A]
Closed: [S, B, F, G]

Path : S → B → F → G
Cost : 2 + 1 + 3 + 0
= 6

Problem Solving

- Open : [S]
  Priority Queue ($h(n)$) : [13]
  Closed : [ ] $f(S) = h(S) = 13$.

- Open : [B, A]
  Priority Queue ($h(n)$) : [4, 12]
  Closed : [S] $f(B) = h(B) = 4$

- Open : [F, E, A]
  Priority Queue ($h(n)$) : [2, 8, 12]
  Closed : [S, B]

- Open : [G, E, I, A]
  Priority Queue ($h(n)$) : [0, 8, 9, 12]
  Closed : [S, B, F] $f(F) = h(F) = 2$

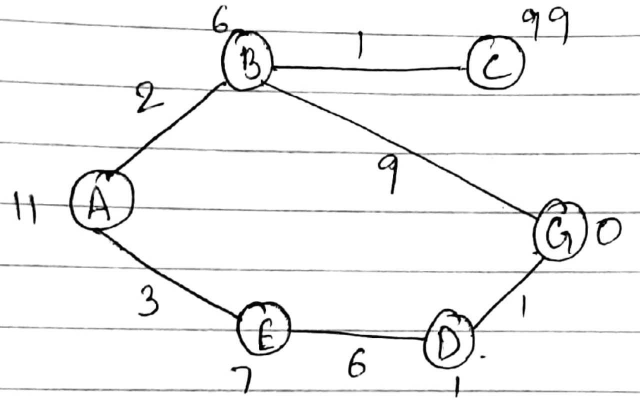
- Open : [E, I, A]
  Priority Queue ($h(n)$) : [8, 9, 12]
  Closed : [S, B, F, G] $f(G) = h(G) = 0$

Goal state reached

ii) Developing A* Algorithm for real world problems.

Problem Formulation

Given a graph with the numbers written on edges representing the distance between the nodes while the numbers written on nodes representing heuristic values.
Find the most cost-effective path to reach from start A to final state G using A* Algorithm.



Initial State

→(A) Open: [A]
Closed: [ ]

Final State

Open: [ ]
Closed: [A, E, D, G]

Path: A → E → D → G
Cost: 3 + 6 + 1 + 0
= 10

Problem solving

- Open : [A]
  Closed : [ ]

  $g(A) = 0$
  $h(A) = 11$
  $f(A) = 11$

- A has two nodes B and E

  $f(B) = 2 + 6 = 8$
  $f(E) = 3 + 7 = 10$
  $f(B) < f(E)$, so B is selected

- Open : [B, E]
  Closed : [A]

- B has two nodes C and G
  $f(C) = 2 + 1 + 99 = 102$
  $f(G) = 2 + 9 + 0 = 11$

  But $f(G) > f(E)$
  ∴ we explore path from E

- Open : [E]
  Closed : [A]

- E has only one node D
  $f(D) = 3 + 6 + 1 = 10$
  Open : [D]
  Closed : [A, E]

- D has only one node G

$f(G) = 3 + 6 + 1 + 0$

$= \underline{\underline{10}}$

Open: [G]
Closed: [A, E, D]

→ Since goal state is reached.
Open: [ ]
Closed: [A, E, D, G]

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ARTIFICIAL INTELLIGENCE LAB

EXPERIMENT NO: 5

DEVELOPING BEST FIRST SEARCH AND A* ALGORITHM FOR REAL WORLD PROBLEMS

(i) Developing Best first search for real world problems

Algorithm:

Step-1: Start

Step-2: Create 2 empty lists: OPEN and CLOSED

Step-3: Start from the initial node (say N) and put it in the 'ordered' OPEN list

Step-4: Repeat the next steps until GOAL node is reached

a. If OPEN list is empty, then EXIT the loop returning 'False'
b. Select the first/top node (say N) in the OPEN list and move it to the CLOSED list. Also capture the information of the parent node
c. If N is a GOAL node, then move the node to the Closed list and exit the loop returning 'True'. The solution can be found by backtracking the path
d. If N is not the GOAL node, expand node N to generate the 'immediate' next nodes linked to node N and add all those to the OPEN list
e. Reorder the nodes in the OPEN list in ascending order according to an evaluation function f(n)

Step-5: Stop

Source code:

```
class Graph:
   # Initialize the class     def __init__(self,
graph_dict=None, directed=True):
self.graph_dict = graph_dict or {}        self.directed =
directed        if not directed:
          self.make_undirected()
   # Create an undirected graph by adding symmetric edges
def make_undirected(self):        for a in
list(self.graph_dict.keys()):            for (b, dist) in
self.graph_dict[a].items():
self.graph_dict.setdefault(b, {})[a] = dist
   # Add a link from A and B of given distance, and also add the inverse link if
the graph is undirected     def connect(self, A, B, distance=1):
self.graph_dict.setdefault(A, {})[B] = distance        if not self.directed:
          self.graph_dict.setdefault(B, {})[A] = distance
   # Get neighbors or a neighbor     def
get(self, a, b=None):        links =
self.graph_dict.setdefault(a, {})        if b is
None:            return links        else:
          return links.get(b)
   # Return a list of nodes in the graph
def nodes(self):
       s1 = set([k for k in self.graph_dict.keys()])        s2 = set([k2 for v in
self.graph_dict.values() for k2, v2 in v.items()])        nodes =
s1.union(s2)        return list(nodes)
# This class represent a node class
Node:
   # Initialize the class     def
__init__(self, name:str, parent:str):
self.name = name        self.parent =
parent        self.g = 0 # Distance to start
node        self.h = 0 # Distance to goal
node        self.f = 0 # Total cost
   # Compare nodes     def
__eq__(self, other):        return
self.name == other.name
```

```
   # Sort nodes     def
__lt__(self, other):
return self.f < other.f
   # Print node     def __repr__(self):         return
('({0},{1})'.format(self.position, self.f))
# Best-first search def best_first_search(graph,
heuristics, start, end):

   # Create lists for open nodes and closed nodes
open = []     closed = []
   # Create a start node and an goal node
start_node = Node(start, None)
goal_node = Node(end, None)     # Add
the start node
   open.append(start_node)

   # Loop until the open list is empty
while len(open) > 0:
       # Sort the open list to get the node with the lowest cost first
open.sort()
       # Get the node with the lowest cost
current_node = open.pop(0)
       # Add the current node to the closed list
closed.append(current_node)

       # Check if we have reached the goal, return the path
if current_node == goal_node:            path = []
while current_node != start_node:
               path.append(current_node.name + ': ' + str(current_node.g))
current_node = current_node.parent
           path.append(start_node.name + ': ' + str(start_node.g))
           # Return reversed path
return path[::-1]            # Get
neighbours
       neighbors = graph.get(current_node.name)
       # Loop neighbors        for key,
value in neighbors.items():            #
Create a neighbor node
           neighbor = Node(key, current_node)
# Check if the neighbor is in the closed list
if(neighbor in closed):               continue
```

```
            # Calculate cost to goal
            neighbor.g = current_node.g + graph.get(current_node.name,
neighbor.name)
            neighbor.h = heuristics.get(neighbor.name)
neighbor.f = neighbor.h
            # Check if neighbor is in open list and if it has a lower f value
if(add_to_open(open, neighbor) == True):                # Everything is
green, add neighbor to open list                open.append(neighbor)
# Return None, no path is found     return None
# Check if a neighbor should be added to open list
def add_to_open(open, neighbor):     for node in
open:        if (neighbor == node and neighbor.f >=
node.f):
            return False
return True
# The main entry point for this module
def main():     # Create a graph
graph = Graph()
   # Create graph connections (Actual distance)
graph.connect('Frankfurt', 'Wurzburg', 111)
graph.connect('Frankfurt', 'Mannheim', 85)
graph.connect('Wurzburg', 'Nurnberg', 104)
graph.connect('Wurzburg', 'Stuttgart', 140)
graph.connect('Wurzburg', 'Ulm', 183)
graph.connect('Mannheim', 'Nurnberg', 230)
graph.connect('Mannheim', 'Karlsruhe', 67)
graph.connect('Karlsruhe', 'Basel', 191)
graph.connect('Karlsruhe', 'Stuttgart', 64)
graph.connect('Nurnberg', 'Ulm', 171)
graph.connect('Nurnberg', 'Munchen', 170)
graph.connect('Nurnberg', 'Passau', 220)
graph.connect('Stuttgart', 'Ulm', 107)
graph.connect('Basel', 'Bern', 91)     graph.connect('Basel',
'Zurich', 85)     graph.connect('Bern', 'Zurich', 120)
graph.connect('Zurich', 'Memmingen', 184)
graph.connect('Memmingen', 'Ulm', 55)
graph.connect('Memmingen', 'Munchen', 115)
graph.connect('Munchen', 'Ulm', 123)
graph.connect('Munchen', 'Passau', 189)
graph.connect('Munchen', 'Rosenheim', 59)
graph.connect('Rosenheim', 'Salzburg', 81)
```

```
graph.connect('Passau', 'Linz', 102)
graph.connect('Salzburg', 'Linz', 126)
    # Make graph undirected, create symmetric connections
graph.make_undirected()
    # Create heuristics (straight-line distance, air-travel distance)
heuristics = {}     heuristics['Basel'] = 204     heuristics['Bern']
= 247     heuristics['Frankfurt'] = 215     heuristics['Karlsruhe']
= 137     heuristics['Linz'] = 318     heuristics['Mannheim'] =
164     heuristics['Munchen'] = 120     heuristics['Memmingen']
= 47     heuristics['Nurnberg'] = 132     heuristics['Passau'] =
257     heuristics['Rosenheim'] = 168     heuristics['Stuttgart'] =
75     heuristics['Salzburg'] = 236     heuristics['Wurzburg'] =
153     heuristics['Zurich'] = 157     heuristics['Ulm'] = 0     #
Run search algorithm     path = best_first_search(graph,
heuristics, 'Frankfurt', 'Ulm')     print(path)
    print()
# Tell python to run main method if
__name__ == "__main__": main()
```

Output:

(ii) Developing A Algorithm for real world problems*

Algorithm:

Step-1: Start.
Step-2: Firstly, add the beginning node to the open list
Step-3: Then repeat the following step
– In the open list, find the square with the lowest F cost – and this denotes the current square.
– Now we move to the closed square.
– Consider 8 squares adjacent to the current square and

- Ignore it if it is on the closed list, or if it is not workable. Do the following if it is workable
- Check if it is on the open list; if not, add it. You need to make the current square as this square's a parent. You will now record the different costs of the square like the F, G and H costs.
- If it is on the open list, use G cost to measure the better path. Lower the G cost, the better the path. If this path is better, make the current square as the parent square. Now you need to recalculate the other scores – the G and F scores of this square. – You'll stop:
- If you find the path, you need to check the closed list and add the target square to it.
- There is no path if the open list is empty and you could not find the target square.

Step-4: Now you can save the path and work backwards starting from the target square, going to the parent square from each square you go, till it takes you to the starting square. You've found your path now. **Step-5** Stop.

Source code:

```
def aStarAlgo(start_node, stop_node):

        open_set = set(start_node)
closed_set = set()
        g = {} #store distance from starting node
        parents = {}# parents contains an adjacency map of all nodes

        #ditance of starting node from itself is zero
g[start_node] = 0
```

```
        #start_node is root node i.e it has no parent nodes
        #so start_node is set to its own parent node
parents[start_node] = start_node


        while len(open_set) > 0:
            n = None

            #node with lowest f() is found            for v in open_set:
if n == None or g[v] + heuristic(v) < g[n] + heuristic(n):
n = v


            if n == stop_node or Graph_nodes[n] == None:
pass            else:                for (m, weight) in
get_neighbors(n):
                    #nodes 'm' not in first and last set are added to first
                    #n is set its parent                    if m not in
open_set and m not in closed_set:
                        open_set.add(m)
parents[m] = n                        g[m]
= g[n] + weight


                    #for each node m,compare its distance from start i.e g(m) to the
                    #from start through n node
else:
                        if g[m] > g[n] + weight:
                            #update g(m)
g[m] = g[n] + weight
#change parent of m to n
parents[m] = n

                            #if m in closed set,remove and add to open
if m in closed_set:                            closed_set.remove(m)
open_set.add(m)

            if n == None:
print('Path does not exist!')
return None
```

```
            # if the current node is the stop_node
            # then we begin reconstructin the path from it to the start_node
    if n == stop_node:
                path = []

                while parents[n] != n:
                    path.append(n)
                    n = parents[n]

                path.append(start_node)

                path.reverse()

                print('Path found: {}'.format(path))
                return path


            # remove n from the open_list, and add it to closed_list
    # because all of his neighbors were inspected
    open_set.remove(n)
            closed_set.add(n)

        print('Path does not exist!')
    return None

#define fuction to return neighbor and its distance
#from the passed node
def get_neighbors(v):
    if v in Graph_nodes:
        return Graph_nodes[v]
    else:
        return None
#for simplicity we ll consider heuristic distances given
#and this function returns heuristic distance for all nodes
def heuristic(n):        H_dist = {
            'A': 11,
            'B': 6,
            'C': 99,
            'D': 1,
            'E': 7,
            'G': 0,
```

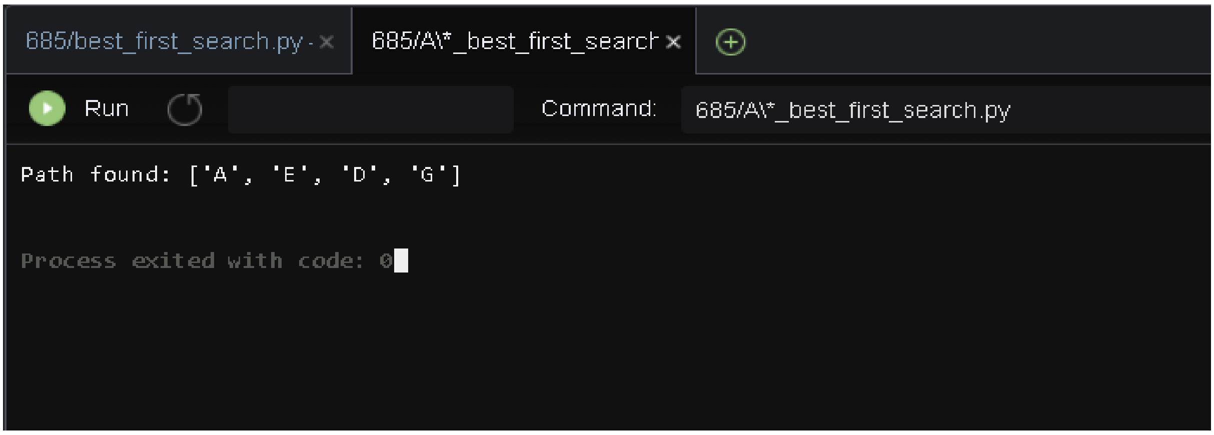
```
        }

        return H_dist[n]

#Describe your graph here
Graph_nodes = {
    'A': [('B', 2), ('E', 3)],
    'B': [('C', 1),('G', 9)],
    'C': None,
    'E': [('D', 6)],
    'D': [('G', 1)],

}
aStarAlgo('A', 'G')
```

OUTPUT



Result:

Hence, the Development of Best first search and A* Algorithm for real world problems is done successfully.