

Project 1: Robot Path Planning

How to run the source file

Assuming that input files are in the same directory as `astar.py`, run the program in command line:

```
py astar.py
```

Source code

```
import math
import heapq as hq
import copy

# Constant variables
ACTIONS = [(1, 0), (1, 1), (0, 1), (-1, 1), (-1, 0), (-1, -1), (0, -1), (1, -1)]
NUM_COL = 50
NUM_ROW = 30

def parse_file(filename):
    """
    Function to read through an input file, store start and goal coordinates, and the initial workspace.

    Params:
    filename: string

    Returns:
    start: tuple
    goal: tuple
    workspace: nested list
    """
    file = open(filename, "r")
    line1 = file.readline()
    coords = line1.split()

    start = (int(coords[0]), int(coords[1]))
    goal = (int(coords[2]), int(coords[3]))
    workspace = []

    for line in file:
        line = line.strip()
        if line:
            workspace.append(line.split())
```

```

        file.close()
        return start, goal, workspace

def write_output(filename, start, goal, workspace, solution_path, solution_f, depth, generated):
    """
    Creates and writes to a txt file, following designated format. Also modifies workspace to
    reflect solution.

    Params:
    filename: string file
    start: tuple of coordinates
    goal: tuple of coordinates
    workspace: nested list
    solution_path: list of actions
    solution_f: list of f(n) function values
    depth: depth of goal node
    generated: number of generated nodes added to search tree
    """
    file = open(filename, "w")
    file.write(str(depth) + "\n")
    file.write(str(generated) + "\n")
    file.write(" ".join([str(a) for a in solution_path]) + "\n")
    file.write(" ".join([str(f) for f in solution_f]) + "\n")

    curr = start
    for a in solution_path:
        curr = (curr[0] + ACTIONS[a][0], curr[1] + ACTIONS[a][1])
        if curr == goal:
            break
        i, j = coord_to_pos(curr)
        workspace[i][j] = "4"

    for row in workspace:
        file.write(" ".join(row) + "\n")
    file.close()

def coord_to_pos(coord):
    """
    Converts workspace coordinates to i, j positions used to index the nested list workspace

    Params:
    coord: tuple of coordinates

    Returns:
    i, j: positions for indexing
    """

```

```

    """
    return NUM_ROW - 1 - coord[1], coord[0]

def print_workspace(workspace):
    """
    Function for testing purposes. Prints out current workspace.
    """
    for row in workspace:
        print(row)

def angle_cost(before, after):
    """
    Calculates change in angle and divides result by 4. Equivalent to (delta theta) / 180.

    Params:
    before: current angle
    after: angle to change to

    Returns:
    change / 4: value used to calculate step cost of angle.
    """
    change = abs(after - before)
    if change > 4:
        change = 8 - change
    return change / 4

def heuristic(curr, goal):
    """
    Calculates euclidean distance of two coordinates.

    Params:
    curr: tuple of current coordinates
    goal: tuple of goal coordinates
    """
    return math.sqrt((goal[0] - curr[0])**2 + (goal[1] - curr[1])**2)

def astar(start, goal, workspace, k):
    """
    A* search algorithm.  $f(n) = g(n) + h(n)$  where  $f(n)$  is search function,  $g(n)$  is path cost

    Params:
    start: tuple of coordinates

```

goal: tuple of coordinates
workspace: nested list
k: weight of angle step cost

Returns:

path: list of actions along solution path
f_path: f(n) values of nodes along path
d: depth of goal node
generated: total number of generated nodes

"""

```
h_root = heuristic(start, goal)
root = [0 + h_root, start, 0, h_root, [], [0 + h_root], 0]
frontier = []
hq.heappush(frontier, root)
reached = {}
reached[start] = 0 + h_root
generated = 1
```

while frontier:

```
    f, coord, g, h, path, f_path, d = hq.heappop(frontier)
    if coord == goal:
        return path, f_path, d, generated
```

for a in range(len(ACTIONS)):

```
    action = ACTIONS[a]
    if coord[0] + action[0] < 0 or coord[0] + action[0] > NUM_COL - 1 or coord[1] +
        continue
    new_coord = (coord[0] + action[0], coord[1] + action[1])
    i, j = coord_to_pos(new_coord)
```

```
    if workspace[i][j] == '1':
        continue
```

```
    ca = (k * angle_cost(path[-1], a)) if path else 0
    cd = 1 if a % 2 == 0 else math.sqrt(2)
    new_g = g + ca + cd
    new_h = heuristic(new_coord, goal)
    new_f = new_g + new_h
```

```
    if new_coord in reached and reached[new_coord] <= new_f:
        continue
```

```
    generated += 1
    node = [new_f, new_coord, new_g, new_h, path+[a], f_path+[new_f], d + 1]
    hq.heappush(frontier, node)
    reached[new_coord] = new_f
```

return None

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[illegible][illegible]


```

1 1 1 1 1 1 1 1 0 1 1 1 1 1 1 1 1 1 0 0 0 1 1 0 0 1 1 4 0 1 1 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
1 1 1 1 1 1 1 1 0 0 0 1 1 1 1 1 1 1 1 0 0 0 1 1 0 0 0 4 0 0 0 1 1 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 1 1 0 0 0 1 1 1 1 4 1 1 0 0 1 1 1 1 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 1 0 0 0 0 1 1 1 1 4 0 1 1 0 0 1 1 1 1 0 0 0 0 0 0 0 0 0 0 0 0
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0 0 0 0 0 0 0 0 0 0 1 1 0 0 1 0 0 0 0 1 1 0 0 0 1 0 0 0 4 0 0 0 1 1 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 1 1 0 0 0 0 0 0 0 1 1 0 0 1 1 1 0 4 1 0 0 0 0 1 1 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 1 1 0 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 1 4 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 4 4 4 4 0 0 0 0 1 1 1 1 0 0 0 1 1 1 0 0 0 0 0 0 0 0 0 0
0 0 0 1 1 1 1 1 1 1 0 0 0 1 1 1 0 0 1 1 4 1 1 1 1 1 0 0 0 1 0 1 1 0 0 0 1 1 0 0 0 1 1 0 0 0 0 0 0 0 0 0
0 0 0 1 1 1 1 1 1 1 0 0 0 0 1 1 0 0 1 1 4 1 1 1 1 1 0 0 0 1 0 0 1 1 0 0 0 1 0 0 0 0 1 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 1 0 0 0 0 0 0 1 1 1 0 1 0 4 1 1 1 1 1 0 0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 0 0 0 4 0 0 1 1 1 0 0 0 0 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 1 1 1 0 0 0 0 0 0 1 1 1 0 4 1 1 0 0 1 1 0 0 1 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 1 1 1 0 1 1 0 0 0 0 1 1 4 0 0 0 0 0 0 0 0 0 0 0 0 1 1 1 0 0 1 1 1 0 0 0 0 0 0 0 0 0 0 0
0 0 0 1 1 0 1 1 1 0 1 1 0 0 0 4 4 4 0 0 0 1 0 0 0 0 0 0 0 0 0 0 0 1 1 0 0 0 1 1 1 1 0 0 0 0 0 0 0 0 0
0 0 0 1 1 0 1 1 1 0 1 1 0 0 4 1 1 0 0 0 0 1 1 1 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 0 1 1 0 0 0 0 0
0 0 0 1 1 0 1 1 1 0 0 0 4 0 1 1 0 0 0 0 0 1 0 0 0 0 1 1 1 0 0 0 0 0 1 1 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0
0 0 0 1 1 0 1 1 1 0 0 0 4 0 1 1 0 0 1 1 0 1 1 1 1 0 0 1 1 1 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 1 1 1 0 0 4 0 0 0 1 1 0 0 1 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 4 4 4 4 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0

```

File Input2.txt with k value of 4 output generated at Output2-k=4.txt

37

977

```

0 0 7 0 0 0 1 1 1 1 1 0 0 1 1 1 2 2 2 1 0 0 0 1 1 1 2 2 2 2 1 1 1 1 0 0
37.8021163428716 38.013511046643494 38.235341863986875 40.538997298749976 41.797825588281356
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 1 1 1 1 1 1 1 0 0 0 1 1 1 0 0 1 1 4 1 1 1 1 1 0 0 0 1 0 1 1 0 0 0 1 1 0 0 0 1 1 0 0 0 0 0 0 0 0

```

```

0 0 0 1 1 1 1 1 1 0 0 0 0 1 1 0 0 1 1 4 1 1 1 1 1 0 0 0 1 0 0 1 1 0 0 0 1 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 1 0 0 0 0 0 0 1 1 1 0 1 0 4 1 1 1 1 1 0 0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 0 0 0 4 0 0 1 1 1 0 0 0 0 1 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 1 1 1 0 0 0 0 0 0 1 1 1 0 4 1 1 0 0 1 1 0 0 1 1 1 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 1 1 1 0 1 1 0 0 0 0 1 1 4 0 0 0 0 0 0 0 0 0 0 0 1 1 1 0 0 0 1 1 1 0 0 0 0 0
0 0 0 1 1 0 1 1 1 0 1 1 0 0 0 4 4 4 0 0 0 1 0 0 0 0 0 0 0 0 0 1 1 0 0 0 1 1 1 1 0 0 0 0 0
0 0 0 1 1 0 1 1 1 0 1 1 0 0 4 1 1 0 0 0 0 1 1 1 0 0 1 1 0 0 0 0 0 0 0 1 0 1 1 1 0 0 0 0
0 0 0 1 1 0 1 1 1 0 0 0 0 4 0 1 1 0 0 0 0 0 1 0 0 0 1 1 1 0 0 0 0 0 1 1 0 0 1 1 0 0 0 0
0 0 0 1 1 0 1 1 1 0 0 0 4 0 1 1 0 0 1 1 0 1 1 1 1 0 0 1 1 1 0 0 0 0 1 1 0 0 0 0 0 0 0
0 0 0 0 0 0 1 1 1 0 0 4 0 0 0 1 1 0 0 1 0 0 0 0 0 0 0 0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0
0 0 0 2 4 4 1 1 1 0 4 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 4 4 4 4 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0

```

File Input3.txt with k value of 0 output generated at Output3-k=0.txt

48

461

```

1 1 2 2 2 2 2 1 0 0 1 1 1 1 2 1 0 0 0 0 7 0 0 0 0 0 7 0 0 0 1 1 1 1 0 0 0 0 0 0 1 0 1 0 1 0
46.51881339845203 46.602707673153105 46.69185152366881 47.29105474894765 47.90974558182222 4
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 1 0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0 1 1
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 1 0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0 1 1
0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 0 0 1 0 0 0 0 0 0 0 0 0 0 0 0
1 1 1 1 1 1 1 1 0 1 1 1 1 1 1 1 1 1 0 0 0 1 1 0 0 1 1 0 0 1 1 1 1 0 0 0 0 0 0 0 0 5
1 1 1 1 1 1 1 1 0 0 0 1 1 1 1 1 1 1 1 0 0 0 1 1 0 0 0 0 0 0 0 1 1 1 1 0 0 0 0 4 4 4 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 1 0 0 0 0 1 1 1 1 0 1 1 0 0 1 1 1 1 0 0 0 0 4 4 0
0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1 1 1 0 0 0 0 0 1 1 1 0 0 1 1 0 0 1 1 1 0 4 4 0 0 0 1
0 0 0 0 0 0 0 0 0 0 1 0 0 0 1 1 0 1 1 1 1 0 0 0 0 1 1 0 0 0 0 4 4 4 4 4 0 0 0 0 0 1 1
0 0 0 0 0 0 0 0 0 0 1 1 0 0 1 0 0 0 0 1 1 0 0 0 1 0 0 0 0 0 4 1 1 1 1 0 0 0 0 0 0 0 1 1
0 0 0 0 0 0 0 0 0 0 1 1 0 4 4 4 4 1 1 0 0 1 1 1 0 0 1 0 4 0 0 1 1 1 1 0 0 0 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 1 1 4 1 1 0 0 0 4 4 4 4 4 1 0 1 1 4 0 0 0 0 0 0 0 0 0 1 0 0 0 0 0
0 0 0 0 0 0 0 0 0 0 0 0 4 0 1 0 0 0 0 0 0 0 0 0 4 4 4 4 0 1 1 1 1 0 0 0 1 1 1 0 0 0 1
0 0 0 1 1 1 1 1 1 1 0 4 0 1 1 1 0 0 1 1 0 1 1 1 1 1 0 0 0 1 0 1 1 0 0 0 0 1 1 1 0
0 0 0 1 1 1 1 1 1 1 4 0 0 0 1 1 0 0 1 1 0 1 1 1 1 1 0 0 0 1 0 0 1 1 0 0 0 1 0 0 0
0 0 0 0 0 0 0 1 0 4 0 0 0 0 1 1 1 0 1 0 0 1 1 1 1 0 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0
0 0 0 0 0 0 4 4 4 0 0 0 0 0 0 1 1 0 0 0 0 0 0 1 1 1 0 0 0 0 1 0 0 0 0 0 0 0 0 0 1
0 0 0 0 0 4 1 1 1 0 0 0 0 0 0 1 1 1 0 0 1 1 0 0 1 1 1 0 0 0 1 1 1 0 0 0 0 0 0 0 1
0 0 0 0 4 1 1 1 0 1 1 0 0 0 0 1 1 0 0 0 0 0 0 0 0 0 1 1 1 0 0 1 1 1 0 0 0 0 0 1
0 0 0 1 1 4 1 1 1 0 1 1 0 0 0 0 0 0 0 0 0 1 0 0 0 0 0 0 0 0 1 1 0 0 0 0 0 0 0
0 0 0 1 1 4 1 1 1 0 1 1 0 0 0 0 1 1 0 0 0 0 1 1 1 0 0 1 1 0 0 0 0 0 0 1 0 1 1
0 0 0 1 1 4 1 1 1 0 0 0 0 0 0 1 1 0 0 0 0 0 1 0 0 0 0 0 1 1 0 0 0 0 0 1 1 0 0 0
0 0 0 1 1 4 1 1 1 0 0 0 0 0 0 1 1 0 0 1 1 0 1 1 1 0 0 1 1 1 0 0 0 0 0 1 1 1 1
0 0 0 0 4 0 1 1 1 0 0 0 0 0 0 1 1 0 0 1 0 0 0 0 0 0 0 0 0 0 0 1 1 0 0 0 0 0 1
0 0 0 2 0 0 1 1 1 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 0 1

```


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