```
from collections import deque
import sys
import time
board = []
def ValidMove(board, x, y):
    :param board: NxN board
    :param x: x position
    :param y: y position
    :return: return 2d board
    11 11 11
    return 0 \le x \le len(board) and 0 \le y \le len(board[0])
def ShowBoard(board):
    :param board: NxN board
    :return: Print board on console
    for row in board:
        print("".join(row))
    print()
def Neighbours (board, pos):
    :param board: NxN board
    :param pos: New position of robot
    :return: List of its neighbor
    neighbors = []
    x, y = pos
    for dx, dy in [(1, 0), (-1, 0), (0, 1), (0, -1)]:
        new x, new y = x + dx, y + dy
        if ValidMove(board, new_x, new_y) and board[new_x][new_y] != 'O':
            neighbors.append((new x, new y))
    return neighbors
def Initstate():
    :return: Initial state of the board
   print('Initial Board\n')
    file_obj = open(sys.argv[1])
    rows = file obj.readlines()
    for line in rows:
        if line != "":
            board.append(line.strip())
        else:
            break
    return board
def Successor(board, robot, boxes, storage):
    :param board: NxN board
    :param robot: Location of robot
    :param boxes: Location of boxes
    :param storage: Location of the storage
    :return:Show next board state
```

```
start_state = (robot, boxes)
    visited = set()
    queue = deque([(start_state, [])])
    while queue:
        (robot, boxes), actions = queue.popleft()
        if sorted(boxes) == sorted(storage):
            return actions
        if (robot, boxes) in visited:
            continue
        visited.add((robot, boxes))
        solution board = [list(row) for row in board]
        for box in boxes:
            x, y = box
            solution board[x][y] = 'B'
        solution board[robot[0]][robot[1]] = 'R'
        ShowBoard(solution board)
        for neighbor in Neighbours(board, robot):
            new robot = neighbor
            new boxes = list(boxes)
            for i, box in enumerate(new boxes):
                if box == new robot:
                    new box = (box[0] + (box[0] - robot[0]), box[1] + (box[1] - robot[1]))
                    if ValidMove(board, *new box) and board[new box[0]][new box[1]] != '0':
                        new boxes[i] = new_box
                        break
            new state = (new robot, tuple(new boxes))
            new_actions = actions + [neighbor]
            queue.append((new_state, new_actions))
    return None
def GetStoragePos(board):
    :param board: NxN board
    :return: Positions of the Storages
   return {(x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x][y] ==
'S'}
def GetRobotPos(board):
    :param board: NxN board
    :return: Positions of the Robot
   return [(x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x][y] ==
'R'][0]
def GetBoxPos(board):
    :param board:NxN board
    :return: Positions of the boxes
   return tuple((x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x]
[y] == 'B')
```

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```
# Driver Code
board = Initstate()
storage = GetStoragePos(board)
robot = GetRobotPos(board)
boxes = GetBoxPos(board)
start time = time.time()
actions = Successor(board, robot, boxes, storage)
if actions:
    print("End solution can be found")
    solution board = [list(row) for row in board]
    for action in actions:
        x, y = action
        solution_board[x][y] = 'R'
    ShowBoard(solution board)
else:
   print("End State cannot be found.")
print(f'Total execution time is {time.time() - start_time}')
```

```
import sys
def ValidMove(board, x, y):
   :param board: NxN board
   :param x: x position
   :param y: y position
   :return: return 2d board
   11 11 11
   return 0 \le x \le len(board) and 0 \le y \le len(board[0])
def ShowBoard(board):
    11 11 11
   :param board: NxN board
   :return: Print board on console
   for row in board:
       print("".join(row))
   print()
def Neighbors(board, pos):
   :param board: NxN board
   :param pos: New position of robot
   :return: List of its neighbor
   neighbors = []
   x, y = pos
   for dx, dy in [(1, 0), (-1, 0), (0, 1), (0, -1)]:
       new_x, new_y = x + dx, y + dy
       if ValidMove(board, new_x, new_y) and board[new_x][new_y] != 'O':
           neighbors.append((new x, new y))
   return neighbors
def Successor(board, robot, boxes, storage, depth, actions=[]):
   :param board: NxN board
   :param robot: Robot position
   :param boxes: Boxes Position
   :param storage: Storage Position
   :param depth: Depth
   :param actions: List of actions performed
   :return:Show next board state
   if sorted(boxes) == sorted(storage):
       return actions
   if depth == 0:
       return None
   for neighbor in Neighbors (board, robot):
       new robot = neighbor
       new boxes = list(boxes)
       for i, box in enumerate(new boxes):
           if box == new robot:
               new box = (box[0] + (box[0] - robot[0]), box[1] + (box[1] - robot[1]))
               if ValidMove(board, *new box) and board[new box[0]][new box[1]] != 'O':
                  new boxes[i] = new_box
                  break
       new board = [list(row) for row in board]
```

```
for box in new_boxes:
            x, y = box
            new board[x][y] = 'B'
        new_board[new_robot[0]][new_robot[1]] = 'R'
        ShowBoard (new board)
        result = Successor(new board, new robot, tuple(new boxes), storage, depth - 1, actions
+ [new robot])
        if result:
            return result
    return None
def Initstate():
    11 11 11
    :return: Initial state of the board
   print('Initial Board\n')
    file obj = open(sys.argv[1])
    rows = file obj.readlines()
    for line in rows:
        if line != "":
            board.append(line.strip())
        else:
            break
    return board
def CallSuccessorWithDepth(board, robot, boxes, storage):
    :param board: NxN board
    :param robot: Position of Robot
    :param boxes: Position of box
    :param storage: Position of storage
    :return: Count of the depths
    11 11 11
    depth = 0
    while True:
        print(f"Depth: {depth}")
        result = Successor(board, robot, boxes, storage, depth)
        if result:
           return result
        depth += 1
def GetStoragePos(board):
    :param board: NxN board
    :return: Positions of the Storages
   return {(x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x][y] ==
'S'}
def GetRobotPos(board):
    :param board: NxN board
    :return: Positions of the Robot
   return [(x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x][y] ==
'R'][0]
def GetBoxPos(board):
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```
:param board:NxN board
    :return: Positions of the boxes
   return tuple((x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x]
[y] == 'B')
# Driver Code
board = []
board = Initstate()
storage = GetStoragePos(board)
robot = GetRobotPos(board)
boxes = GetBoxPos(board)
start time = time.time()
actions = CallSuccessorWithDepth(board, robot, boxes, storage)
if actions:
   print("End state can be found")
    solution board = [list(row) for row in board]
    for action in actions:
       x, y = action
        solution board[x][y] = 'R'
    ShowBoard(solution board)
else:
   print("End state cannot be found")
print(f'Total execution time is {time.time() - start time}')
```

```
from heapq import heappop, heappush
import time
import sys
def ValidMove(board, x, y):
   :param board: NxN board
   :param x: x position
   :param y: y position
    :return: return 2d board
    11 11 11
   return 0 \le x \le len(board) and 0 \le y \le len(board[0])
def ManhattanDistance(a, b):
   :param a: Any position
   :param b: Any position
   :return: Absolute distance between 2 co-ordinates
   return abs(a[0] - b[0]) + abs(a[1] - b[1])
def Heuristic(board, robot, boxes, targets):
   :param board: NxN Board
    :param robot: Robot position
   :param boxes: Boxes position
   :param targets: Target locations
   :return: total distance
   total dist = 0
   for box in boxes:
       min dist = min(ManhattanDistance(box, target) for target in targets)
       total dist += min dist
   return total dist
def ShowBoard(board):
   :param board: NxN board
   :return: Print board on console
   for row in board:
       print("".join(row))
   print()
def Successor(board, robot, boxes, targets):
   :param board: NxN board
   :param robot: Location of robot
   :param boxes: Location of boxes
   :param targets: Location of the targets
    :return:Show next board state
   directions = [(1, 0), (-1, 0), (0, 1), (0, -1)]
   def is_goal(boxes):
       return sorted(boxes) == sorted(targets)
   def apply move(entity, direction):
       return (entity[0] + direction[0], entity[1] + direction[1])
   start state = (robot, tuple(sorted(boxes)))
   visited = set()
   priority queue = [(Heuristic(board, robot, boxes, targets), start state)] # (heuristic,
(robot, boxes))
   while priority queue:
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_, (robot, boxes) = heappop(priority_queue)
        if is goal (boxes):
            return boxes
        if (robot, boxes) in visited:
            continue
        visited.add((robot, boxes))
        solution board = [list(row) for row in board]
        for box in boxes:
            x, y = box
            solution board[x][y] = 'B'
        solution board[robot[0]][robot[1]] = 'R'
        ShowBoard(solution board)
        for direction in directions:
            new robot = apply move(robot, direction)
            if not ValidMove(board, *new robot) or board[new robot[0]][new robot[1]] == 'O':
            if (new robot, boxes) not in visited:
                heappush (priority queue, (Heuristic (board, new robot, boxes, targets),
(new robot, boxes)))
    return None
def Initstate():
    :return: Initial state of the board
   print('Initial Board\n')
    file obj = open(sys.argv[1])
    rows = file obj.readlines()
    for line in rows:
        if line != "":
            board.append(line.strip())
        else:
           break
    return board
def GetStoragePos(board):
    :param board: NxN board
    :return: Positions of the Storages
   return {(x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x][y] ==
'S'}
def GetRobotPos(board):
    :param board: NxN board
    :return: Positions of the Robot
   return [(x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x][y] ==
'R'][0]
def GetBoxPos(board):
    :param board:NxN board
    :return: Positions of the boxes
    return tuple((x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x]
```

```
[y] == 'B')
# Driver Code
board = []
board = Initstate()
storage = GetStoragePos(board)
robot = GetRobotPos(board)
boxes = GetBoxPos(board)
start_time = time.time()
result = Successor(board, robot, boxes, storage)
if result:
    print("End state can be found:")
    solution board = [list(row) for row in board]
    for box in result:
       x, y = box
        solution_board[x][y] = 'B'
    print("\n".join(["".join(row) for row in solution_board]))
    print()
else:
   print("End state cannot be found.")
print(f'Total execution time is {time.time() - start_time}')
```

```
import heapq
import time
import sys
def ValidMove(board, x, y):
    :param board: NxN board
    :param x: x position
    :param y: y position
    :return: return 2d board
   return 0 \le x \le len(board) and 0 \le y \le len(board[0])
def ManhattanDistance(pos1, pos2):
   :param a: Any position
   :param b: Any position
    :return: Absolute distance between 2 co-ordinates
   return abs(pos1[0] - pos2[0]) + abs(pos1[1] - pos2[1])
def Heuristic(board, robot, boxes, storagepace):
     :param board: NxN Board
     :param robot: Robot position
     :param boxes: Boxes position
     :param storagepace: storagspace positions
     :return: total distance
     11 11 11
   total dist = 0
   for box in boxes:
       min dist = min(ManhattanDistance(box, target) for target in storagepace)
       total dist += min dist
   return total dist + ManhattanDistance(robot, boxes[0])
def ShowBoard(board):
   :param board: NxN board
   :return: Print board on console
   for row in board:
       print("".join(row))
   print()
def Successor(board, robot, boxes, storage):
    :param board: NxN board
    :param robot: Location of robot
    :param boxes: Location of boxes
    :param storage: Location of the storage
    :return:Show next board state
   print("Pukoban Using A Star Algorithm")
   directions = [(1, 0), (-1, 0), (0, 1), (0, -1)]
   def is goal(boxes):
       return sorted(boxes) == sorted(storage)
   def apply_move(entity, direction):
       return (entity[0] + direction[0], entity[1] + direction[1])
```

```
def valid_move(entity, direction):
        new_entity = apply_move(entity, direction)
        if not ValidMove(board, *new entity) or board[new entity[0]][new entity[1]] == 'O':
            return False
        return True
    start state = (robot, tuple(sorted(boxes)))
    visited = set()
    priority_queue = [(0, start_state)]
    while priority queue:
        f_cost, (robot, boxes) = heapq.heappop(priority_queue)
        if is goal (boxes):
            return boxes
        if (robot, boxes) in visited:
            continue
        visited.add((robot, boxes))
        solution board = [list(row) for row in board]
        for box in boxes:
            x, y = box
            solution board[x][y] = 'B'
        solution board[robot[0]][robot[1]] = 'R'
        ShowBoard(solution board)
        for direction in directions:
            new robot = apply move(robot, direction)
            if not ValidMove(board, *new robot) or board[new robot[0]][new robot[1]] == 'O':
            if (new robot, boxes) not in visited:
                heapq.heappush(priority queue, (f cost + 1 + Heuristic(board, new robot,
boxes, storage),
                                                 (new robot, boxes)))
            for box index, box in enumerate(boxes):
                if box == new robot:
                    new_box = apply_move(box, direction)
                    if valid move (box, direction) and (
                    new_box, boxes[:box_index] + (new_box,) + boxes[box_index + 1:]) not in
visited:
                        heapq.heappush(priority queue, (f cost + 1 + Heuristic(board,
new robot, boxes, storage),
                                                         (new robot,
                                                          boxes[:box_index] + (new_box,) +
boxes[box index + 1:])))
   return None
def Initstate():
    :return: Initial state of the board
    print('Initial Board\n')
    file obj = open(sys.argv[1])
    rows = file obj.readlines()
    for line in rows:
        if line != "":
            board.append(line.strip())
        else:
            break
    return board
```

```
def GetStoragePos(board):
    :param board: NxN board
    :return: Positions of the Storages
   return {(x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x][y] ==
'S'}
def GetRobotPos(board):
    :param board: NxN board
    :return: Positions of the Robot
   return [(x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x][y] ==
'R'][0]
def GetBoxPos(board):
    :param board:NxN board
    :return: Positions of the boxes
   return tuple((x, y) for x in range(len(board)) for y in range(len(board[0])) if board[x]
[y] == 'B')
# Driver Code
board = []
board = Initstate()
storage = GetStoragePos(board)
robot = GetRobotPos(board)
boxes = GetBoxPos(board)
start time = time.time()
result = Successor(board, robot, boxes, storage)
if result:
   print("End state can be found:")
   solution_board = [list(row) for row in board]
    for box in result:
        x, y = box
        solution board[x][y] = 'B'
   print("\n".join(["".join(row) for row in solution_board]))
else:
   print("End state cannot be found:")
```

print(f'Total execution time is {time.time() - start time}')

BFS States

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End State cannot be found. Total execution time is 0.0020017623901367188 secs

GBS States
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End state cannot be found. Total execution time is 0.0 secs.

AStar States

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CS480

Pukoban Assignemt

How to execute the code:

- python3 Driver//PukobanAiGame.py\statefile\board.txt
- Board.ext can always have 1 board from level.txt under boards folder.

In this code, the heuristic function Heuristic calculates the Manhattan distance between each box and its nearest target and then sums these distances for all boxes. The A* search algorithm uses this heuristic to guide the search while printing each state of the game board.

A common heuristic is the Manhattan distance, which calculates the minimum number of moves needed to push all the boxes to their target positions.