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CS_428
Programming Assignment 3

Compiling:
g++ -std=c++14 main.cpp -o main

Execution
./main <source_node>

Part A, B, C
3 sample graphs saved as `GRAPHS` in the `TESTS` object within the main.cpp file.
Ran Djikstra's algorithm on all 3 of these GRAPHS with `u` as the source and had the output saved in the `tables.txt` file. In the `tables.txt` file, Part A is stored under the `TEST1`, Part B under `TEST2`, and Part C under `TEST3`.

Screenshot:

TEST 1

Step	N'	D(v),p(v)	D(w),p(w)	D(x),p(x)	D(y),p(y)	D(z),p(z)
0	u	2,u	5,u	1,u	∞	∞
1	ux	2,u	4,x	---	2,x	∞
2	uxy	2,u	3,y	---	---	4,y
3	uvxy	---	3,y	---	---	4,y
4	uvwxy	---	---	---	---	4,y
5	uvwxyz	---	---	---	---	---

TEST 2

Step	N'	D(t),p(t)	D(v),p(v)	D(w),p(w)	D(x),p(x)	D(y),p(y)	D(z),p(z)
0	u	2,u	3,u	3,u	∞	∞	∞
1	tu	---	3,u	3,u	∞	9,t	∞
2	tuw	---	3,u	---	9,w	9,t	∞
3	tuvw	---	---	---	6,v	9,t	∞
4	tuvwx	---	---	---	---	9,t	14,x
5	tuvwxy	---	---	---	---	---	14,x
6	tuvwxyz	---	---	---	---	---	---

TEST 3

Step	N'	D(v),p(v)	D(w),p(w)	D(x),p(x)	D(y),p(y)	D(z),p(z)
0	u	2,u	5,u	1,u	∞	∞
1	ux	2,u	4,x	---	2,x	∞
2	uxy	2,u	3,y	---	---	4,y
3	uvxy	---	3,y	---	---	4,y
4	uvwxy	---	---	---	---	4,y
5	uvwxyz	---	---	---	---	---

Design Decisions
- *Graph representation:*
    Map from node_name to node's adjancency matrix.
    Considered 2D adjacency matrix; however a map which seemed to make more sense and felt easier to read.
- *Node representation:*

Nodes are simply represented by a char that can be used to index into the Graph which will return that node's adjacency list.
Making another data structure seemed wasteful and unnecessary;

- *Edge representation:*
  Edges were represented as a struct which has a `NODE` destination and length, very standard.
- *N' representation:*
  A C++ set of `NODE`S. This would prevent duplicates which could create edge cases.
- *Distance Tracking:*
  Tracked by a map of `NODE` to current path length to that `NODE`. This distance is updated every time a `NODE` is added to N'.
- *Back Tracking*:
  Utilized a map from `NODE` to `NODE` which kept track of the node used to access the destination node. This map is updated every time the distance data structure is updated.