Consider the search space below, where s is the start mode and 41 and 62 are the goal states. Arcs are labelled with the cost of traversing them and the estimated cost to a goal is reported inside modes.

1 Draw the tree generated by A*

2 List - in order - all the states

popped of the OPEN list

(mark with increasing natural

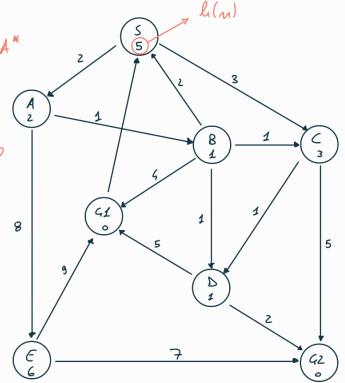
mumber the nodes of the tree

in the order of their expansion;

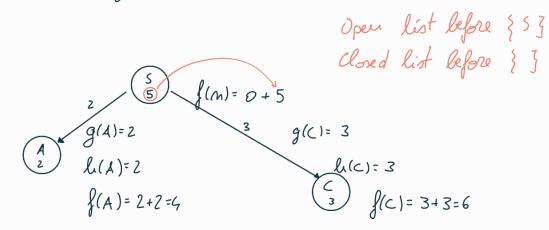
when values are equal, nodes

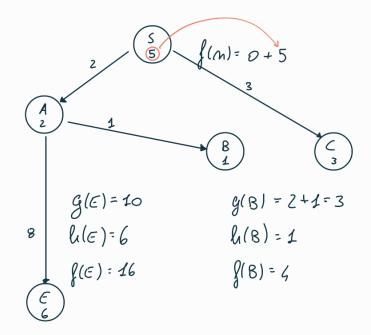
are expanded in alphabetical

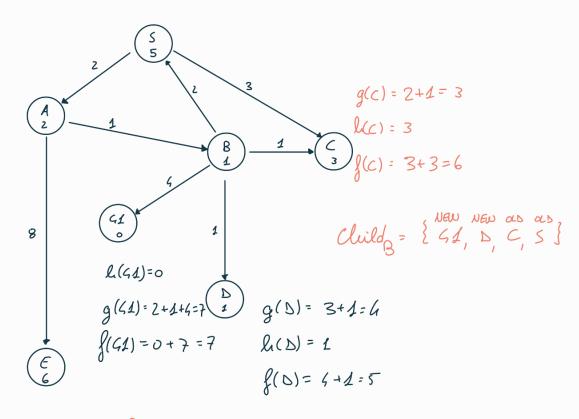
order)



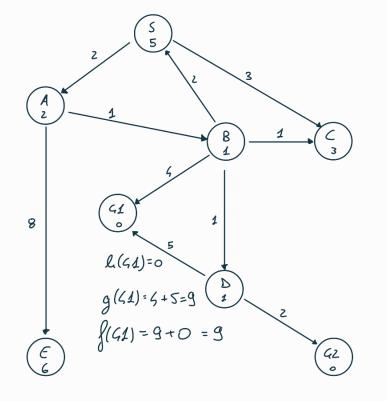
1. Draw the tree generated by A*







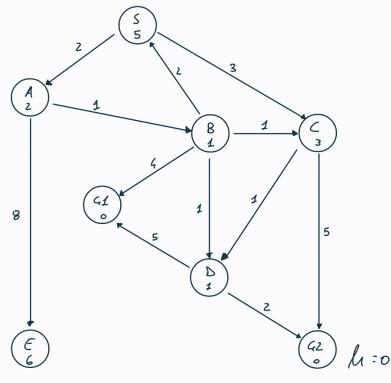
0-1 {
$$S(5)$$
, $C(6)$, $G(4)$ } $\longrightarrow Expand S$
(-1 { $S(5)$, $A^{s}(6)$, $B(6)$ }



41 can now be reached from D
with cost 3, but it is
already in the open list
and can be reached
with cost 7 from B

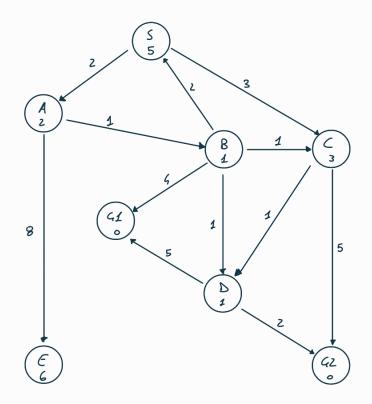
no update

0-1 { c'(6), G2(6), G2(2), E'(16) } - Expand C
(-1 { 3(5), A'(6), B(6), B(5) }



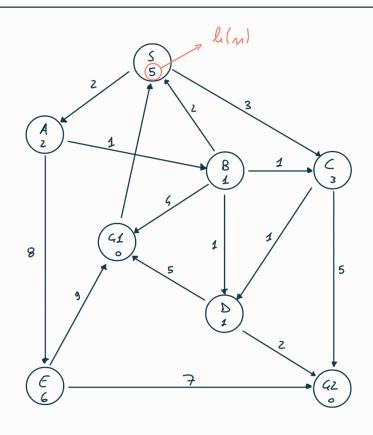
0-1 { G2(6), G2(2), E (16) }
(-1 { 3(5), A'(4), B(6), B(5), C'(6)}

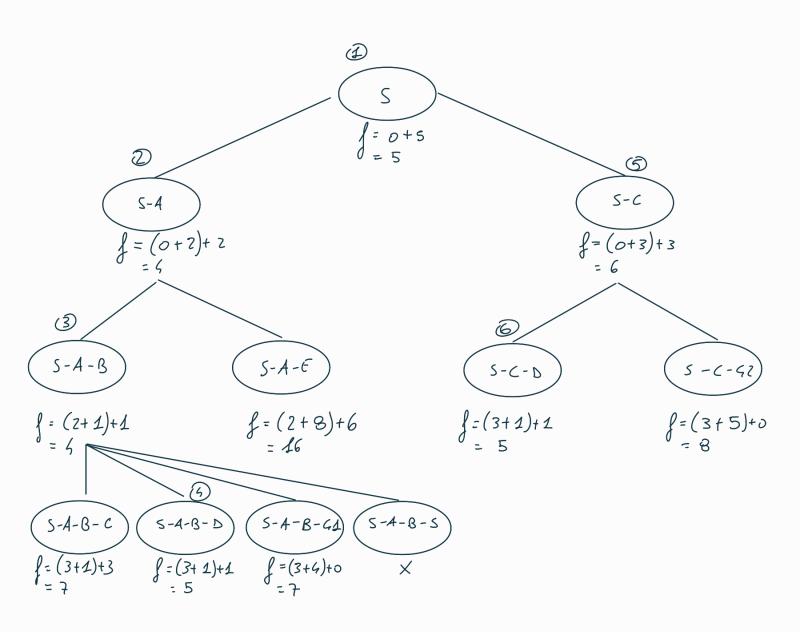
* Expand GZ

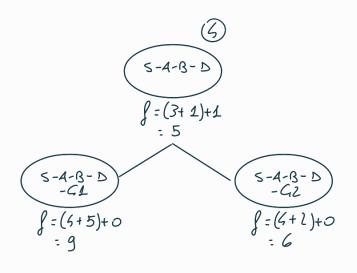


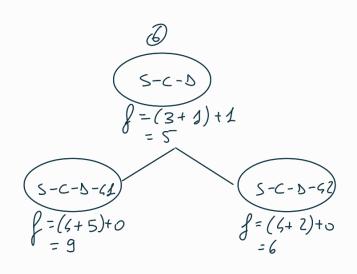
0-1 { G1(2), E(16) } (-1 { 3(5), A'(6), B(6), K(5), C(6), G2(6)}

Algorithm ends









Open set:

contains all the nades

waiting to be expanded

D { S(5)}

D { A(4), C(6)}

S { B(4), C(6), E(16)}

C { S(5), C(6), G1(7), E(16)}

C { C(6), G2(6), G1(7), E(16)}

S { M(5), G2(6), G1(7), E(16)}

0 { 52(6), 51(7), E(16) {

Closed set:

contains all the modes

abready expanded

{}

{S}

{S,A}

{S,A,B}

{S,A,B,D}

{S,A,B,D,C,D}

{S,A,B,D,C,D}

{S,A,B,D,C,D}

2. List - in order - all the states popped of the OPEN list