

Exercise 10: Implementation of Block World Problem

Block World Problem:

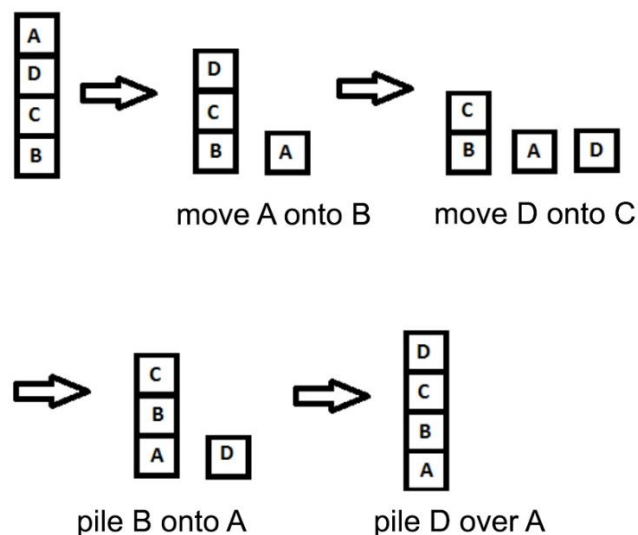
Aim:

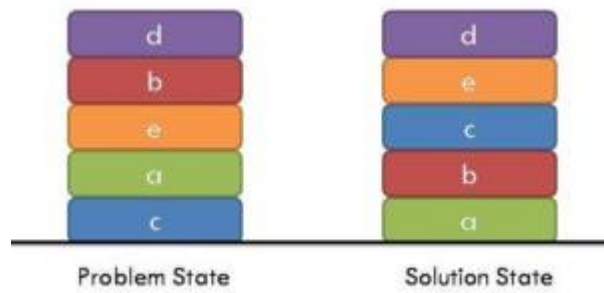
To Solve Block World problem using Goal Stack Algorithm.

Algorithm:

In **Block World** problem we will model a simple block world under certain rules and constraints. That is, we will ``program" a robotic arm to respond to a limited set of commands.

- Push the Goal state in to the Stack
- Push the individual Predicates of the Goal State into the Stack
- Loop till the Stack is empty
 - Pop an element E from the stack
 - IF E is a Predicate
 - IF E is True then
 - Do Nothing
- ELSE
 - Push the relevant action into the Stack
 - Push the individual predicates of the Precondition of the action into the Stack
- Else IF E is an Action
 - Apply the action to the current State.
 - Add the action 'a' to the plan
 -





Program:

```
tab = []
```

```
result = []
```

```
problem = ["c", "a", "e", "d", "b"]
```

```
goalList = ["a", "b", "c", "d", "e"]
```

```
def parSolution(N):
```

```
    for i in range(N):
```

```
        if goalList[i] != result[i]:
```

```
            return False
```

```
    return True
```

```
def Onblock(index, count):
```

```
    if count == len(goalList)+1:
```

```
        return True
```

```
    block = tab[index]
```

```
    result.append(block)
```

```
    print(result)
```

```
    if parSolution(count):
```

```
        print("Valid Step - Pushing Result Soln ")
```

```
        tab.remove(block)
```

```
    Onblock(0, count + 1)
```

```
else:
```

```
    print("Invalid Step - Back To Tab")
```

```
    result.pop()
```

```
    Onblock(index+1, count)
```

```
def Ontab(problem):
```

```
    if len(problem) != 0:
```

```
        tab.append(problem.pop())
```

```
        Ontab(problem)
```

```
    else:
```

```
        return True
```

```
def goal_stack_planing(problem):
```

```
    Ontab(problem)
```

```
    if Onblock(0, 1):
```

```
        print(result)
```

```
if __name__ == "__main__":
```

```
    print("Initial -> Goal")
```

```
    for k, j in zip(goalList, problem):
```

```
        print(j+" "+k)
```

```
    goal_stack_planing(problem)
```

```
    print("\nFinal Result Solution:")
```

```
    print(result)
```

OUTPUT:

```
Initial -> Goal
c      a
a      b
e      c
d      d
b      e
['b']
Invalid Step - Back To Tab
['d']
Invalid Step - Back To Tab
['e']
Invalid Step - Back To Tab
['a']
Valid Step - Pushing Result Soln
['a', 'b']
Valid Step - Pushing Result Soln
['a', 'b', 'd']
Invalid Step - Back To Tab
['a', 'b', 'e']
Invalid Step - Back To Tab
['a', 'b', 'c']
Valid Step - Pushing Result Soln
['a', 'b', 'c', 'd']
Valid Step - Pushing Result Soln
['a', 'b', 'c', 'd', 'e']
Valid Step - Pushing Result Soln

Final Result Solution:
['a', 'b', 'c', 'd', 'e']

...Program finished with exit code 0
Press ENTER to exit console. █
```

Result:

The given program was successfully created and was successfully executed in an Online C++ compiler.