Lowest cost walk using dynamic programming

S=0 t=3 e=10 (edges) 2=5 (vertecès)

	K	i	j	prev	}
init				[-1,-1,-1,-1]	012345678310 00 ~ ~ ~ ~ ~ ~ ~ ~ ~ ~ ~ ~ ~ ~ ~ ~ ~ ~
iteration (1	0	0	[-1,9-1,-1,-1]	4 00 00 00 00 00 00 00 00 00 00 00 00 00
		2		[-1,90,-1,-]	d [2][1] = 0 T17 = 17
		3	0	[-1,0,0,0,7]	d[3][1] =0+10=10

	K	ì	7	prey	a
		4	1 2		d [4][1] = 20
			3		
iteration 2.	2	0	0		d[0][2] = 0 d[1][2] = 2
		2	5	[-1,0,1,0,-1]	d[2][2] = 2r3 = 5
		3	0		d B] [2] = 10
		4	4	[-1,9,1,9,1]	D[4][2] = 2+10 = 12
2	3	0	3		070723]=0
iteration 3)	0	0		\$ [1][3] = 2
		2	3		\$[2][3] = 5
		3	0		1237237=10
		4	014	E-1,0,1,0,23	124J[3]=12 124J[3]=5+2=7

	K	É	j	grev)
it.4	4	0	0 3		d[0][4]=0 d[1][4]=2
		2	0		δ[2][4] = 5
		3	0		d [3][4]=10
		4	4 1 2 2	[-1,0,1,4,2]	d[3][4]=++1=8

Build the path from prex 0 =>13 2 => 4 -1>3

prev[1] prev[2] prev[3]