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AI Lab - 5

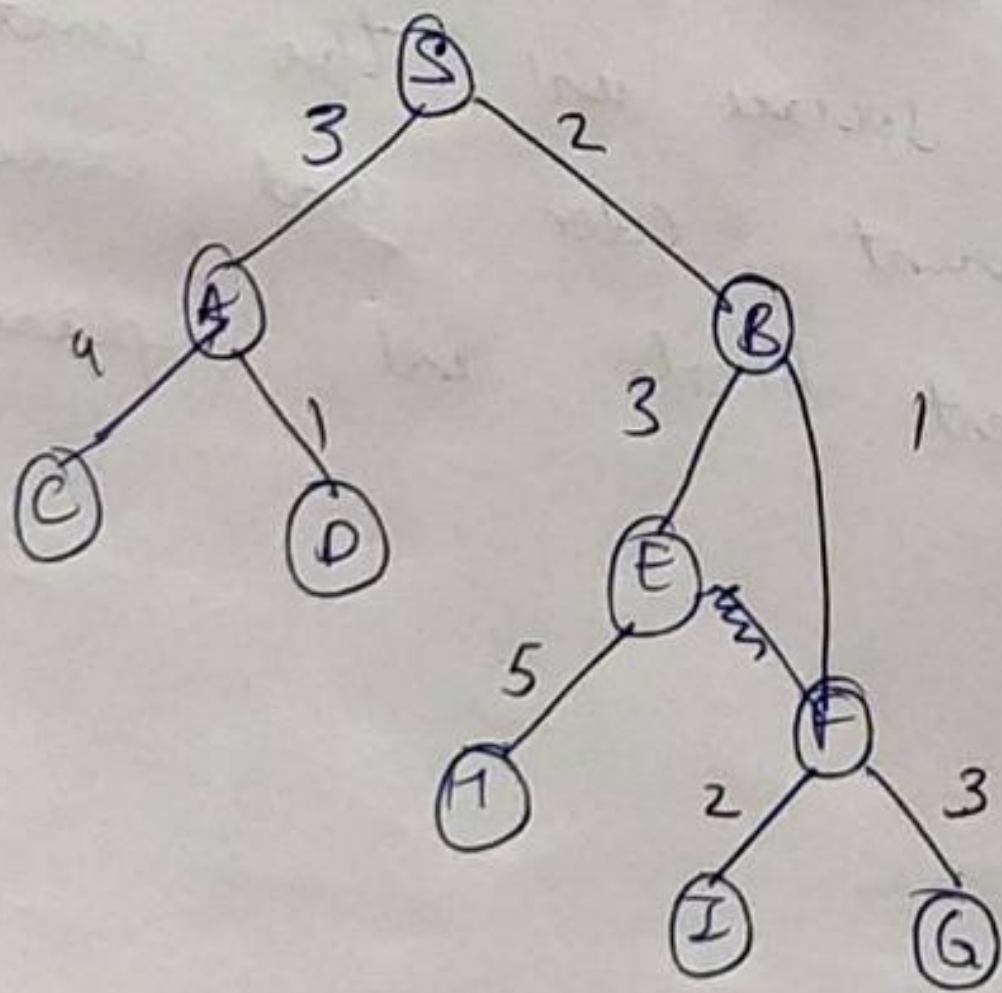
m → Developing Best first search & A^* algorithm for word problems.

i7 Developing Best First Search -

Problem Formulation

Given a graph, starting node and $h(n)$, use the evaluation function to decide which is the most promising node for reaching the destination. Explore it with reach the destination.

Display path & cost function



Node	$h(n)$
A	12
B	4
C	7
D	3
E	8
F	2
G	0
H	4
I	9
S	13

Initial State

Open state: [S]
Closed state: []

Final State

Open state: [I, E, A]
Closed: [S, B, F, G]

Path: $S \rightarrow B \rightarrow F \rightarrow G$
Cost = $2 + 1 + 3 + 0 = 6$

Problem Solving

• open [S]

priority queue $(h(n)) = [13]$

closed : [] $f(S) = h(S) = 13$

• open [B, A]

Priority queue $(h(n)) : [4, 12]$

closed [S]

$f(B) = h(B) = 4$

• open: [F, E, A]

Priority queue $(h(n)) : [2, 3, 12]$

closed : [S, B]

• open: [G, F, I, A]

$(h(n)) = [0, 8, 9, 12]$

closed: [S, B, F]

$f(F) = h(F) = 2$

• open: [E, J, A]

$(h(n)) = [8, 9, 12]$

closed: [S, B, F, G]

$f(G) = h(G) = 0$

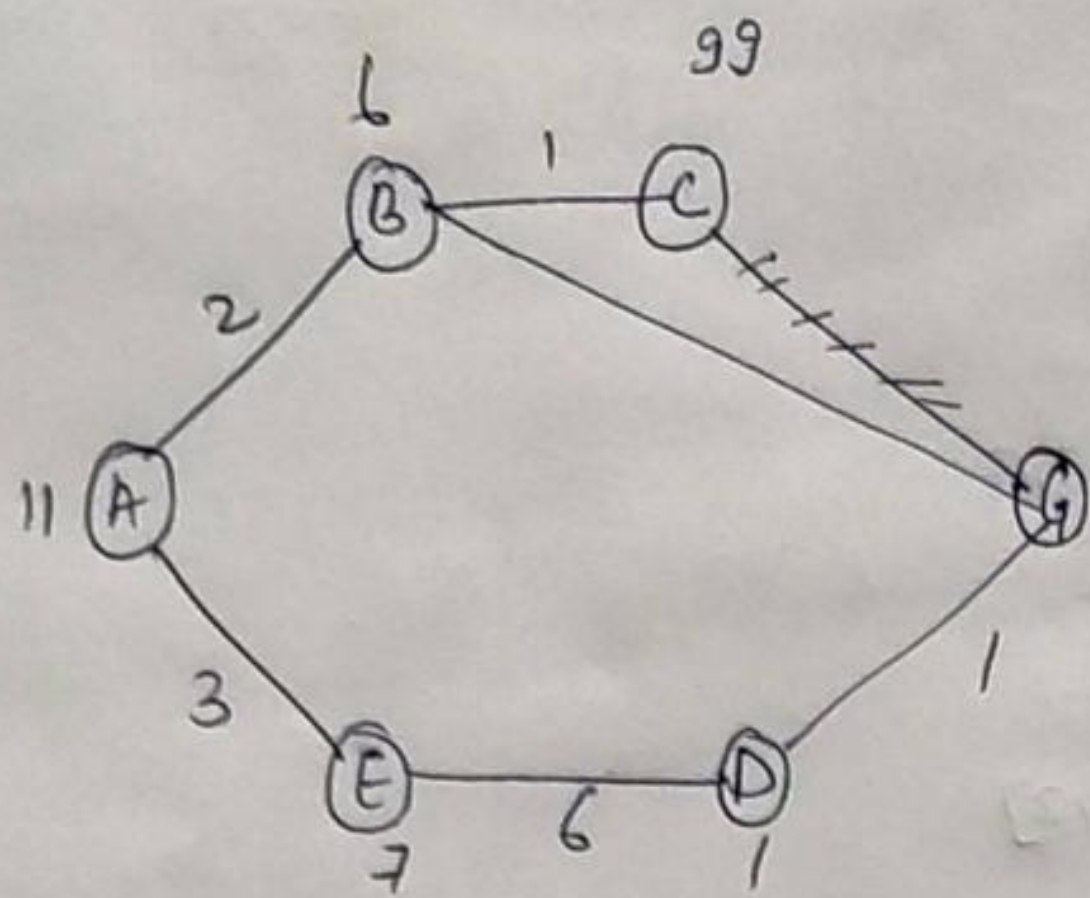
Goal State Reached.

1) Developing A* Algorithm for real world problem.

Problem Formulation

Given a graph with the number written on edges representing the distance between the nodes while the numbers written on nodes representing heuristic values.

2) Find the most cost effective path to reach final state by using A* algorithm.



Initial state

→ A

open = [A]

closed = []

Final state

open: []

closed: [A, E, D, G]

Path: A → E → D → G

Cost: 3 + 6 + 1 to

= 10

Problem Solving

open: [A]

closed: []

$g(A) = 0$

$h(A) = 11$

$f(A) = 11$

• A has two nodes B and E.

$f(B) = 2 + 6 = 8$

$f(E) = 3 + 7 = 10$

$f(B) < f(E)$

, so B is selected

• open: [B, E]

closed: [A]

B has two nodes C and G

$f(C) = 2 + 1 + 99 = 102$

$f(G) = 2 + 9 + 0 = 11$

But $f(G) > f(E)$

∴ we explore path from E.

• open: [E]

closed: [A]

• E has only one node D.

$$f(D) = 3 + 6 + 1 = 10$$

open: [D]

closed: [A, E]

• D has only one node G.

$$f(G) = 3 + 6 + 1 + 0 = 0$$

open: [G]

closed: [A, E, D]

⇒ Since goal state is reached.

Open: []

closed: [A, E, D, G]

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AI LAB 5

(i) Developing Best first search for real world problems

Algorithm:

Step-1: Start

Step-2: Create 2 empty lists: OPEN and CLOSED

Step-3: Start from the initial node (say N) and put it in the 'ordered' OPEN list

Step-4: Repeat the next steps until GOAL node is reached

a. If OPEN list is empty, then EXIT the loop returning 'False'

b. Select the first/top node (say N) in the OPEN list and move it to the CLOSED list. Also capture the information of the parent node

c. If N is a GOAL node, then move the node to the Closed list and exit the loop returning 'True'. The solution can be found by backtracking the path

d. If N is not the GOAL node, expand node N to generate the 'immediate' next nodes linked to node N and add all those to the OPEN list

e. Reorder the nodes in the OPEN list in ascending order according to an evaluation function $f(n)$

Step-5: Stop

Source Code

```
class Graph:
```

```
# Initialize the class
```

```
def __init__(self, graph_dict=None, directed=True):
```

```

self.graph_dict = graph_dict or {}

self.directed = directed

if not directed:

    self.make_undirected()

# Create an undirected graph by adding symmetric edges

def make_undirected(self):

    for a in list(self.graph_dict.keys()):

        for (b, dist) in self.graph_dict[a].items():

            self.graph_dict.setdefault(b, {})[a] = dist

# Add a link from A and B of given distance, and also add the inverse link if the graph is undirected

def connect(self, A, B, distance=1):

    self.graph_dict.setdefault(A, {})[B] = distance

    if not self.directed:

        self.graph_dict.setdefault(B, {})[A] = distance

# Get neighbors or a neighbor

def get(self, a, b=None):

    links = self.graph_dict.setdefault(a, {})

    if b is None:

        return links

    else:

        return links.get(b)

# Return a list of nodes in the graph

def nodes(self):

    s1 = set([k for k in self.graph_dict.keys()])

    s2 = set([k2 for v in self.graph_dict.values() for k2, v2 in v.items()])

    nodes = s1.union(s2)

    return list(nodes)

# This class represent a node

class Node:

    # Initialize the class

```

```

def __init__(self, name:str, parent:str):
    self.name = name
    self.parent = parent
    self.g = 0 # Distance to start node
    self.h = 0 # Distance to goal node
    self.f = 0 # Total cost

    # Compare nodes
    def __eq__(self, other):
        return self.name == other.name

    # Sort nodes
    def __lt__(self, other):
        return self.f < other.f

    # Print node
    def __repr__(self):
        return ('({0},{1}').format(self.position, self.f))

    # Best-first search
    def best_first_search(graph, heuristics, start, end):

        # Create lists for open nodes and closed nodes
        open = []
        closed = []

        # Create a start node and an goal node
        start_node = Node(start, None)
        goal_node = Node(end, None)

        # Add the start node
        open.append(start_node)

        # Loop until the open list is empty
        while len(open) > 0:

            # Sort the open list to get the node with the lowest cost first
            open.sort()

```

```

# Get the node with the lowest cost
current_node = open.pop(0)

# Add the current node to the closed list
closed.append(current_node)

# Check if we have reached the goal, return the path
if current_node == goal_node:
    path = []
    while current_node != start_node:
        path.append(current_node.name + ':' + str(current_node.g))
        current_node = current_node.parent
    path.append(start_node.name + ':' + str(start_node.g))
    # Return reversed path
    return path[::-1]

# Get neighbours
neighbors = graph.get(current_node.name)

# Loop neighbors
for key, value in neighbors.items():
    # Create a neighbor node
    neighbor = Node(key, current_node)

    # Check if the neighbor is in the closed list
    if(neighbor in closed):
        continue

    # Calculate cost to goal
    neighbor.g = current_node.g + graph.get(current_node.name, neighbor.name)
    neighbor.h = heuristics.get(neighbor.name)
    neighbor.f = neighbor.h

    # Check if neighbor is in open list and if it has a lower f value
    if(add_to_open(open, neighbor) == True):
        # Everything is green, add neighbor to open list

```



```

open.append(neighbor)

# Return None, no path is found
return None

# Check if a neighbor should be added to open list
def add_to_open(open, neighbor):
    for node in open:
        if (neighbor == node and neighbor.f >= node.f):
            return False
    return True

# The main entry point for this module
def main():
    # Create a graph
    graph = Graph()

    # Create graph connections (Actual distance)
    graph.connect('Frankfurt', 'Wurzburg', 111)
    graph.connect('Frankfurt', 'Mannheim', 85)
    graph.connect('Wurzburg', 'Nurnberg', 104)
    graph.connect('Wurzburg', 'Stuttgart', 140)
    graph.connect('Wurzburg', 'Ulm', 183)
    graph.connect('Mannheim', 'Nurnberg', 230)
    graph.connect('Mannheim', 'Karlsruhe', 67)
    graph.connect('Karlsruhe', 'Basel', 191)
    graph.connect('Karlsruhe', 'Stuttgart', 64)
    graph.connect('Nurnberg', 'Ulm', 171)
    graph.connect('Nurnberg', 'Munchen', 170)
    graph.connect('Nurnberg', 'Passau', 220)
    graph.connect('Stuttgart', 'Ulm', 107)
    graph.connect('Basel', 'Bern', 91)
    graph.connect('Basel', 'Zurich', 85)
    graph.connect('Bern', 'Zurich', 120)

```



```
graph.connect('Zurich', 'Memmingen', 184)
graph.connect('Memmingen', 'Ulm', 55)

graph.connect('Memmingen', 'Munchen', 115)
graph.connect('Munchen', 'Ulm', 123)
graph.connect('Munchen', 'Passau', 189)
graph.connect('Munchen', 'Rosenheim', 59)
graph.connect('Rosenheim', 'Salzburg', 81)
graph.connect('Passau', 'Linz', 102)
graph.connect('Salzburg', 'Linz', 126)

# Make graph undirected, create symmetric connections
graph.make_undirected()

# Create heuristics (straight-line distance, air-travel distance)
heuristics = {}
heuristics['Basel'] = 204
heuristics['Bern'] = 247
heuristics['Frankfurt'] = 215
heuristics['Karlsruhe'] = 137
heuristics['Linz'] = 318
heuristics['Mannheim'] = 164
heuristics['Munchen'] = 120
heuristics['Memmingen'] = 47
heuristics['Nurnberg'] = 132
heuristics['Passau'] = 257
heuristics['Rosenheim'] = 168
heuristics['Stuttgart'] = 75
heuristics['Salzburg'] = 236
heuristics['Wurzburg'] = 153
heuristics['Zurich'] = 157
heuristics['Ulm'] = 0

# Run search algorithm
```

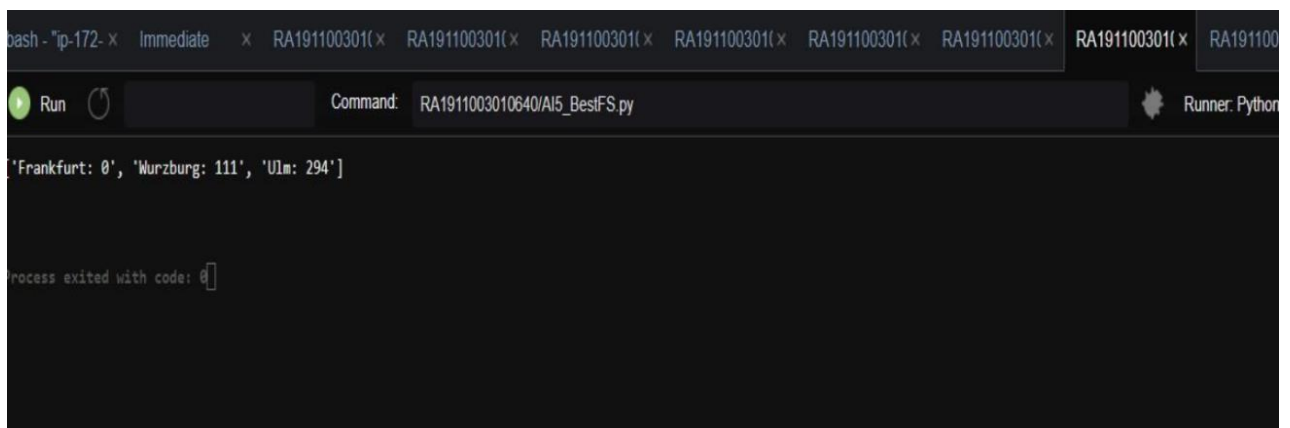


```
path = best_first_search(graph, heuristics, 'Frankfurt', 'Ulm')
print(path)
print()
```

Tell python to run main method

```
if __name__ == "__main__": main()
```

OUTPUT-

A screenshot of a Python IDE window. The title bar shows multiple tabs, with the active one being 'RA191100301(x)'. The command line shows 'Command: RA1911003010640/AI5_BestFS.py' and 'Runner: Python'. The output console displays the result of the search: 'Frankfurt: 0', 'Munich: 111', 'Ulm: 294'. Below the output, it says 'Process exited with code: 0'.

(ii) Developing A* Algorithm for real world problems

Algorithm:

Step-1: Start.

Step-2: Firstly, add the beginning node to the open list

Step-3: Then repeat the following step

– In the open list, find the square with the lowest F cost – and this denotes the current square.

– Now we move to the closed square.

– Consider 8 squares adjacent to the current square and

- Ignore it if it is on the closed list, or if it is not workable. Do the following if it is workable

- Check if it is on the open list; if not, add it. You need to make the current square as this square's a parent. You will now record the

different costs of the square like the F, G and H costs.

- If it is on the open list, use G cost to measure the better path.

Lower the G cost, the better the path. If this path is better, make

the current square as the parent square. Now you need to recalculate the other scores – the G and F scores of this square.

– You'll stop:

- If you find the path, you need to check the closed list and add the target square to it.
- There is no path if the open list is empty and you could not find the target square.

Step-4: Now you can save the path and work backwards starting from the target square, going to the parent square from each square you go, till it takes you to the starting square. You've found your path now.

Step-5 Stop.

Source Code

```
def aStarAlgo(start_node, stop_node):
```

```
    open_set = set(start_node)
```

```
    closed_set = set()
```

```
    g = {} #store distance from starting node
```

```
    parents = {}# parents contains an adjacency map of all nodes
```

```
    #distance of starting node from itself is zero
```

```
    g[start_node] = 0
```

```
    #start_node is root node i.e it has no parent nodes
```

```
    #so start_node is set to its own parent node
```

```
    parents[start_node] = start_node
```

```

while len(open_set) > 0:
    n = None

    #node with lowest f() is found
    for v in open_set:
        if n == None or g[v] + heuristic(v) < g[n] + heuristic(n):
            n = v

    if n == stop_node or Graph_nodes[n] == None:
        pass
    else:
        for (m, weight) in get_neighbors(n):
            #nodes 'm' not in first and last set are added to first
            #n is set its parent
            if m not in open_set and m not in closed_set:
                open_set.add(m)
                parents[m] = n
                g[m] = g[n] + weight

            #for each node m,compare its distance from start i.e g(m) to the
            #from start through n node
            else:
                if g[m] > g[n] + weight:
                    #update g(m)
                    g[m] = g[n] + weight
                    #change parent of m to n
                    parents[m] = n

            #if m in closed set,remove and add to open
            if m in closed_set:

```



```
closed_set.remove(m)
```

```
open_set.add(m)
```

```
if n == None:
```

```
    print('Path does not exist!')
```

```
    return None
```

```
# if the current node is the stop_node
```

```
# then we begin reconstructin the path from it to the start_node
```

```
if n == stop_node:
```

```
    path = []
```

```
while parents[n] != n:
```

```
    path.append(n)
```

```
    n = parents[n]
```

```
path.append(start_node)
```

```
path.reverse()
```

```
print('Path found: {}'.format(path))
```

```
return path
```

```
# remove n from the open_list, and add it to closed_list
```

```
# because all of his neighbors were inspected
```

```
open_set.remove(n)
```

```
closed_set.add(n)
```

```
print('Path does not exist!')
```

```
return None
```

```

#define fuction to return neighbor and its distance

#from the passed node
def get_neighbors(v):
    if v in Graph_nodes:
        return Graph_nodes[v]
    else:
        return None

#for simplicity we ll consider heuristic distances given
#and this function returns heuristic distance for all nodes
def heuristic(n):
    H_dist = {
        'A': 11,
        'B': 6,
        'C': 99,
        'D': 1,
        'E': 7,
        'G': 0,

    }

    return H_dist[n]

#Describe your graph here
Graph_nodes = {
    'A': [('B', 2), ('E', 3)],
    'B': [('C', 1), ('G', 9)],
    'C': None,
    'E': [('D', 6)],
    'D': [('G', 1)],

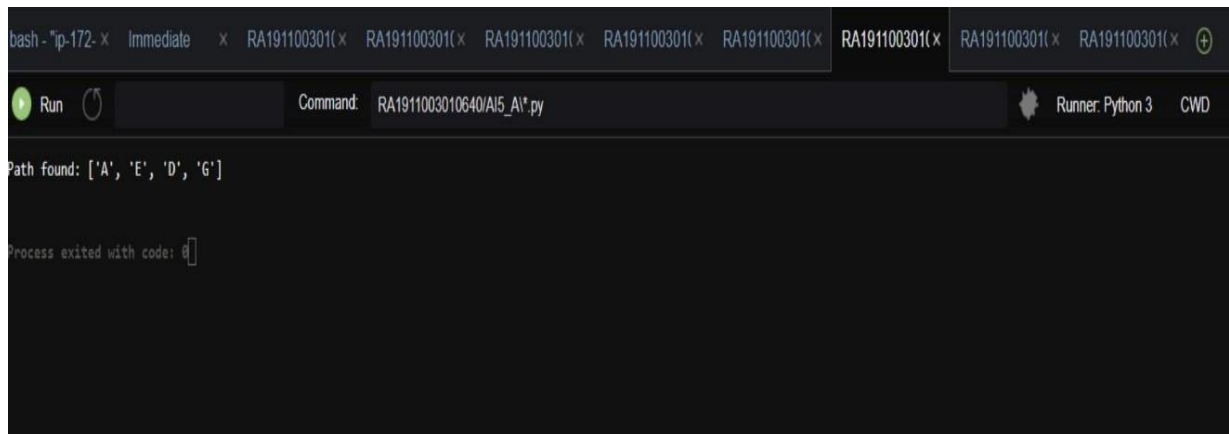
```



```
}
```



```
aStarAlgo('A', 'G')
```

Output –



The screenshot shows a code editor interface with a dark theme. At the top, there is a tab bar with several tabs, including 'bash - Tip-172', 'Immediate', and multiple tabs labeled 'RA191100301'. The active tab is 'RA191100301'. Below the tab bar, there is a toolbar with a green play button labeled 'Run', a circular arrow icon, and a text field containing the command 'RA1911003010640/AI5_AI.py'. To the right of the text field, there is a gear icon, the text 'Runner: Python 3', and 'CWD'. The main area of the editor displays the output of the script: 'Path found: ['A', 'E', 'D', 'G']' and 'Process exited with code: 0'.

```
bash - Tip-172 x Immediate x RA191100301(x) RA191100301(x) RA191100301(x) RA191100301(x) RA191100301(x) RA191100301(x) RA191100301(x) RA191100301(x) RA191100301(x) (+)
```

Run  Command: RA1911003010640/AI5_AI.py  Runner: Python 3 CWD

Path found: ['A', 'E', 'D', 'G']

Process exited with code: 0