1. We set up distance, visited tracker and a priority queue to store necessary info. Then we iterate and extract the closest unvisited node and check the neighbours. If a shorter path is found it updates the neighbours distance and add it to the queue. After processing all node it converts unreachable node to -1 and returns the array of the shortest distance from the source.

2. It runs dijkstras algorithm from both Alice and Bob to find shortest time. It checks nodes that are reachable by both parties. Then the node where they can meet in the shortest time is selected. Prints impossible if no such nodes exists.

3. We modify the dijkstra's algorithm where we track maximum danger level instead of edge weight. We do this by prioritizing paths with lowest maximum danger levels. Then we find the safest path with minimum danger level and prints "impossible" if no such path exists.