```
function TREE_SEARCH(problem) returns a solution, or failure

    initialize the frontier as a specific work list (stack, queue, priority queue)
    add initial state of problem to frontier
    loop do
        if the frontier is empty then
            return failure
        choose a node and remove it from the frontier
        if the node contains a goal state then
            return the corresponding solution

        for each resulting child from node
            add child to the frontier
```

```
function GRAPH_SEARCH(problem) returns a solution, or failure
    initialize the explored set to be empty
    initialize the frontier as a specific work list (stack, queue, priority queue)
    add initial state of problem to frontier
    loop do
        if the frontier is empty then
            return failure
        choose a node and remove it from the frontier
        if the node contains a goal state then
            return the corresponding solution
        add the node state to the explored set
        for each resulting child from node
            if the child state is not already in the frontier or explored set then
                add child to the frontier
```

```
function UNIFORM-COST-SEARCH(problem) returns a solution, or failure
    initialize the explored set to be empty
    initialize the frontier as a priority queue using node path_cost as the priority
    add initial state of problem to frontier with path_cost = 0
    loop do
        if the frontier is empty then
            return failure
        choose a node and remove it from the frontier
        if the node contains a goal state then
            return the corresponding solution
        add the node state to the explored set
        for each resulting child from node
            if the child state is not already in the frontier or explored set then
                add child to the frontier
            else if the child is already in the frontier with higher path_cost then
                replace that frontier node with child
```