

# Path planning

- Dijkstra
- $A^*$
- "car" planner

## Dijkstra

front = start node

while front not empty:

    get node  $n$  with minimum cost

    mark  $n$  as visited

    for any direct neighbor  $m$  of  $n$ , not visited:

        add  $m$  to front

        -or-

        adjust cost if  $m$  is already in front and  
        its new cost is lower