From “<https://dzone.com/articles/how-does-path-planning-for-autonomous-vehicles-wor>”

* A **path** is a continuous sequence of configurations beginning and ending with boundary configurations. These configurations are also referred to as initial and terminating.
* **Path planning** involves finding a geometric path from an initial configuration to a given configuration so that each configuration and state on the path is feasible (if time is taken into account).
* A **maneuver** is a high-level characteristic of a vehicle’s motion, encompassing the position and speed of the vehicle on the road. Examples of maneuvers include going straight, changing lanes, turning, and overtaking.
* **Maneuver planning** aims at taking the best high-level decision for a vehicle while taking into account the path specified by path planning mechanisms.
* A **trajectory** is a sequence of states visited by the vehicle, parameterized by time and, most probably, velocity.
* **Trajectory planning** or trajectory generation is the real-time planning of a vehicle’s move from one feasible state to the next, satisfying the car’s kinematic limits based on its dynamics and as constrained by the navigation mode.