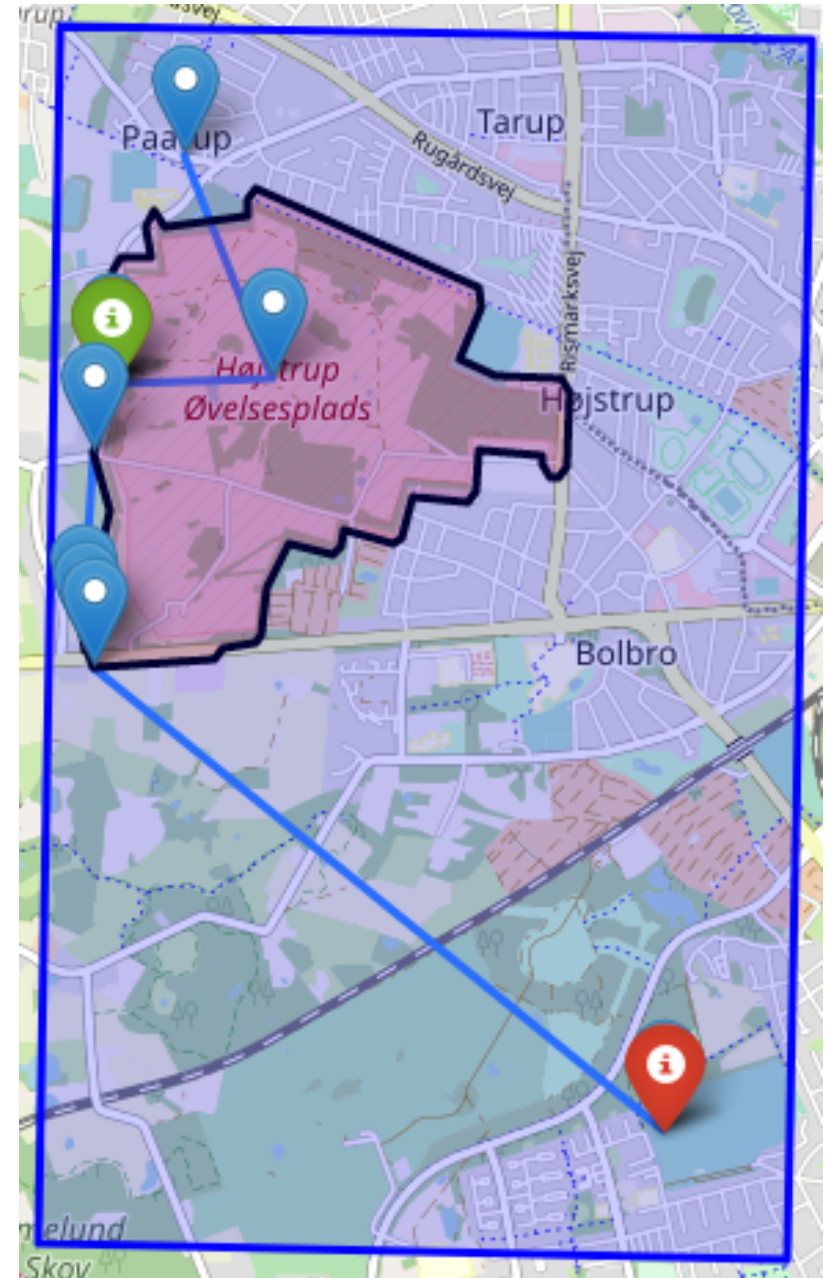


What & Why?

- Visibility Graph
- Bounding box
- Buffer
- Special cases



Pros & Cons (Visibility graph)

- Few vertices
- Fast search time
- Shortest path (Avoid "sawtooth" pattern)
- Flying close to NFZ
- Time to construct Graph
- "Unknown" construction time
- Continues planning

Reflections

- Route outside Boundingbox
- Dijkstra's vs A*
- Local planner
- Rebuild Graph when new polygon is injected
- Only plans in 2D
- Consider SoC
- Preemptive planning
- (Close neighbours)
- (DNFZ over drones/Deconflict)

