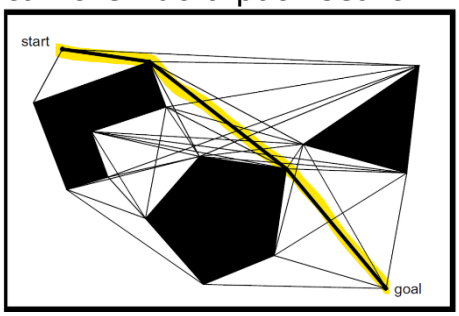
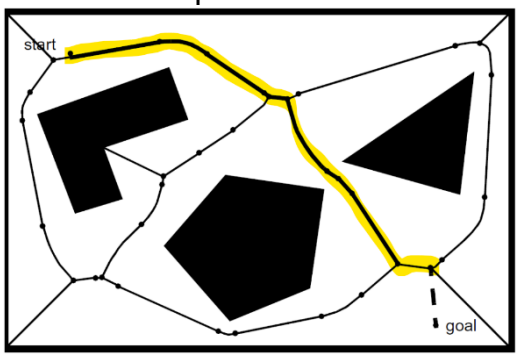
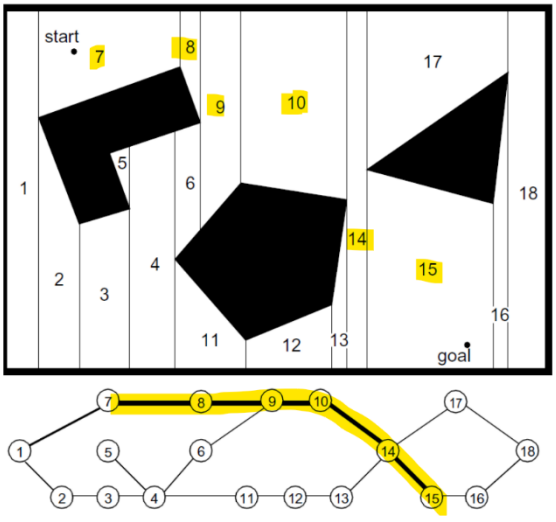
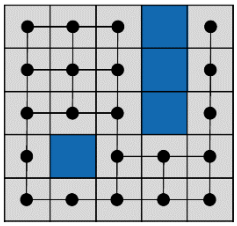
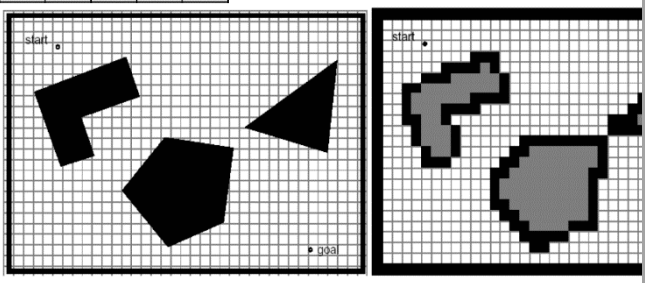
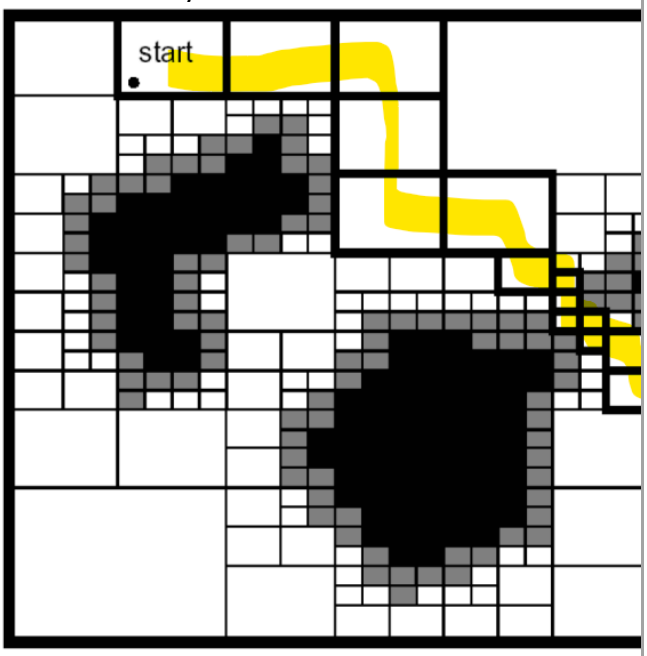
	Explanation	Pros	Cons
Visibility Graph	Connect vertices which are visible to each other can then do a path search 	gives the shortest path	not safe (can hit edges)
Voroni Diagram	- construct vertices at points with equal distance to the nearest two edges - connect vertices - then do a path search 	safe (doesn't hit edges)	not always the shortest path
Exact cell decomposition	- split map into "zones" based on polygon vertices of obstacles - connect adjacent zones 	Efficient for large, sparse environments	complex implementation

Fixed cell decomposition (occupancy grid	- split map into cells of a grid - connect adjacent cells which don't contain obstacles  	Easy to implement	High memory requirements may lose narrow passages if resolution isn't high enough
Adaptive cell decomposition	- similar to fixed cell decomposition (occupancy grid) - fewer cells/nodes for large areas - more cells/nodes close to obstacles 	solves memory issue	complex implementation