CREATE A GRAPH: \((V, E)\)

**Goal:** Find a feasible path from start to goal

**Node:** A node is \(D\)-dimensional state of the robot.
\[
\begin{bmatrix}
\theta_1 \\
\theta_2 \\
\vdots \\
\theta_D
\end{bmatrix}
\]

**Edge Evaluation:** 
"is the motion between \(v_0\) & \(v_1\) feasible?"