Preparation of Papers for IEEE Sponsored Conferences & Symposia

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TABLE I
AN EXAMPLE OF A TABLE

One	Two
Three	Four

***Abstract*—**

I. INTRODUCTION

The goal of this project is to implement a braitenberg-type controller for movement in formation on epucks. For this, a PSO algorithm was implemented, using the braitenberg weights as a search space. The formation consists of 3 follower robots and one leader that moves with a predefined trajectory.

A. Design of PSO

Individual Performance Group Solution Heterogeneous Approach

B. Fitness Function

minimize relative range minimize relative bearing minimize relative orientation

II. METHODOLOGY

heterogeneous, public individual performance

A. Implementation Webots

1) Environment:
2) Leader:
3) Supervisor:
4) Follower:

B. Optimization

optiomize the fitness etc noise resistant no penalty fo rmax speed etc bearing more important... ABCD

Fig. 1. Inductance of oscillation winding on amorphous magnetic core versus DC bias magnetic field

This work is a project of the course Distributed intelligent systems by Prof. Alcherio Martinoli

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III. RESULTS

IV. CONCLUSIONS

V. ACKNOWLEDGMENTS

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