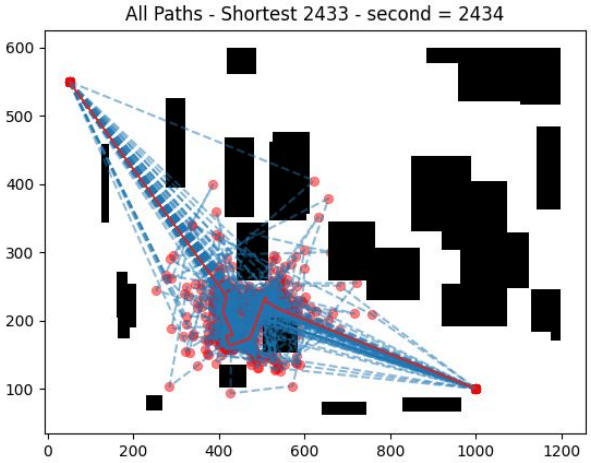
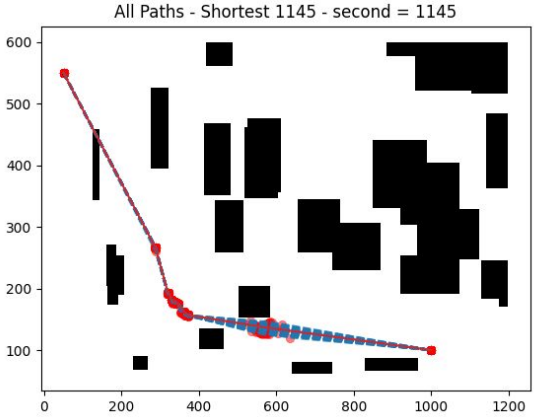
# PSO

versions results

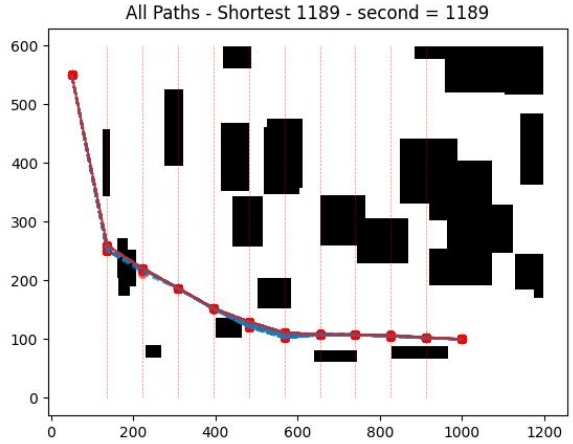
**v2** rect collision - 12 points



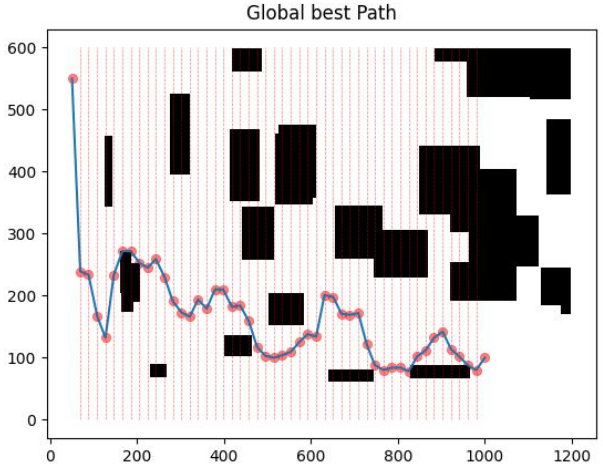

**v2** inside collision - 12 points



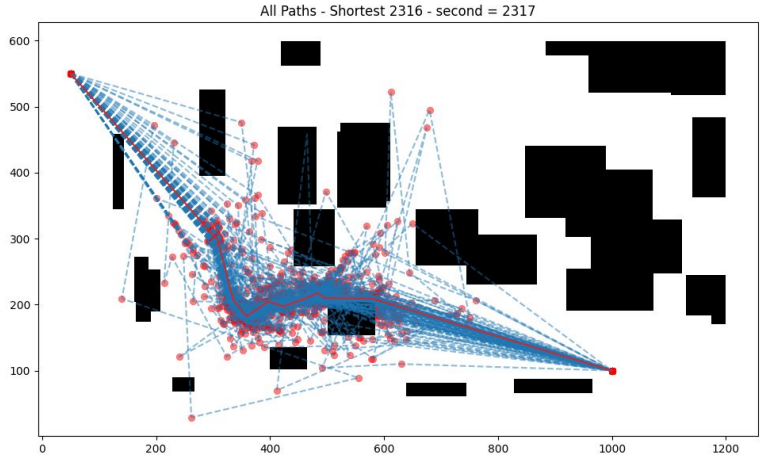

**v1** inside collision - 12 points

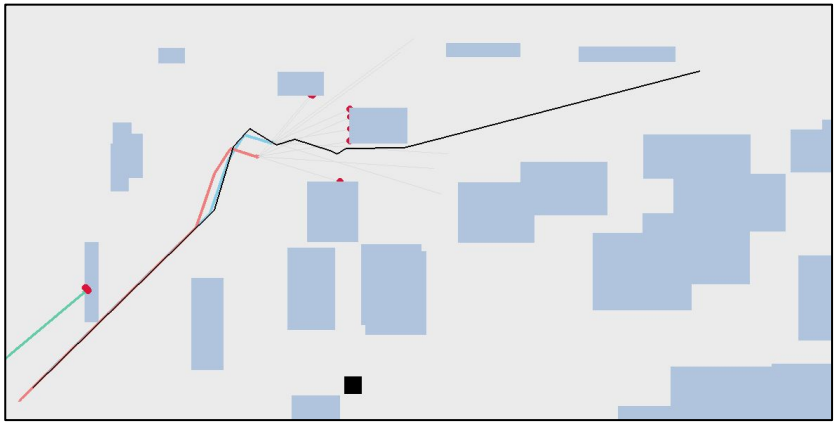


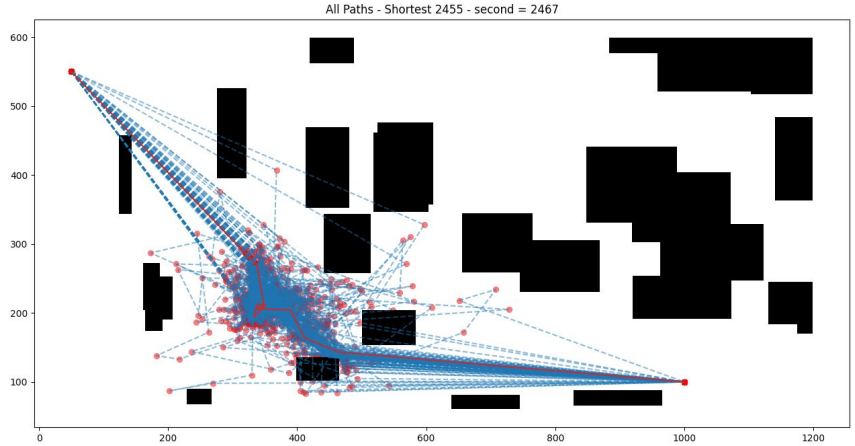

**v1** inside collision - 50 points

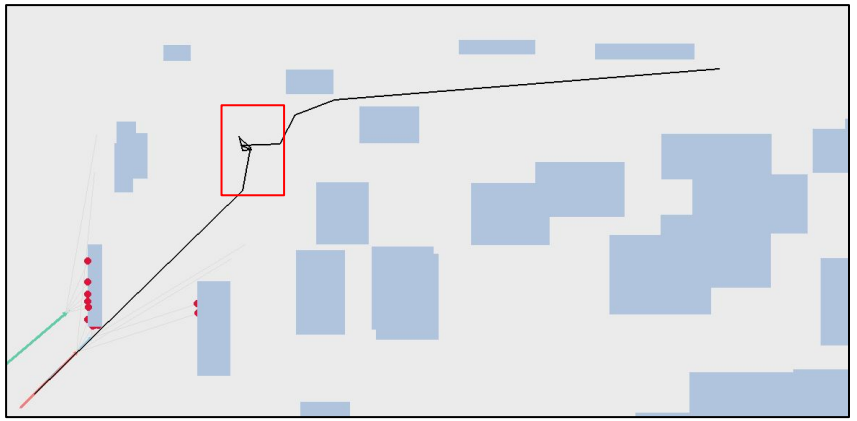


# PSO v2 Cost: rectangle collision and inside point

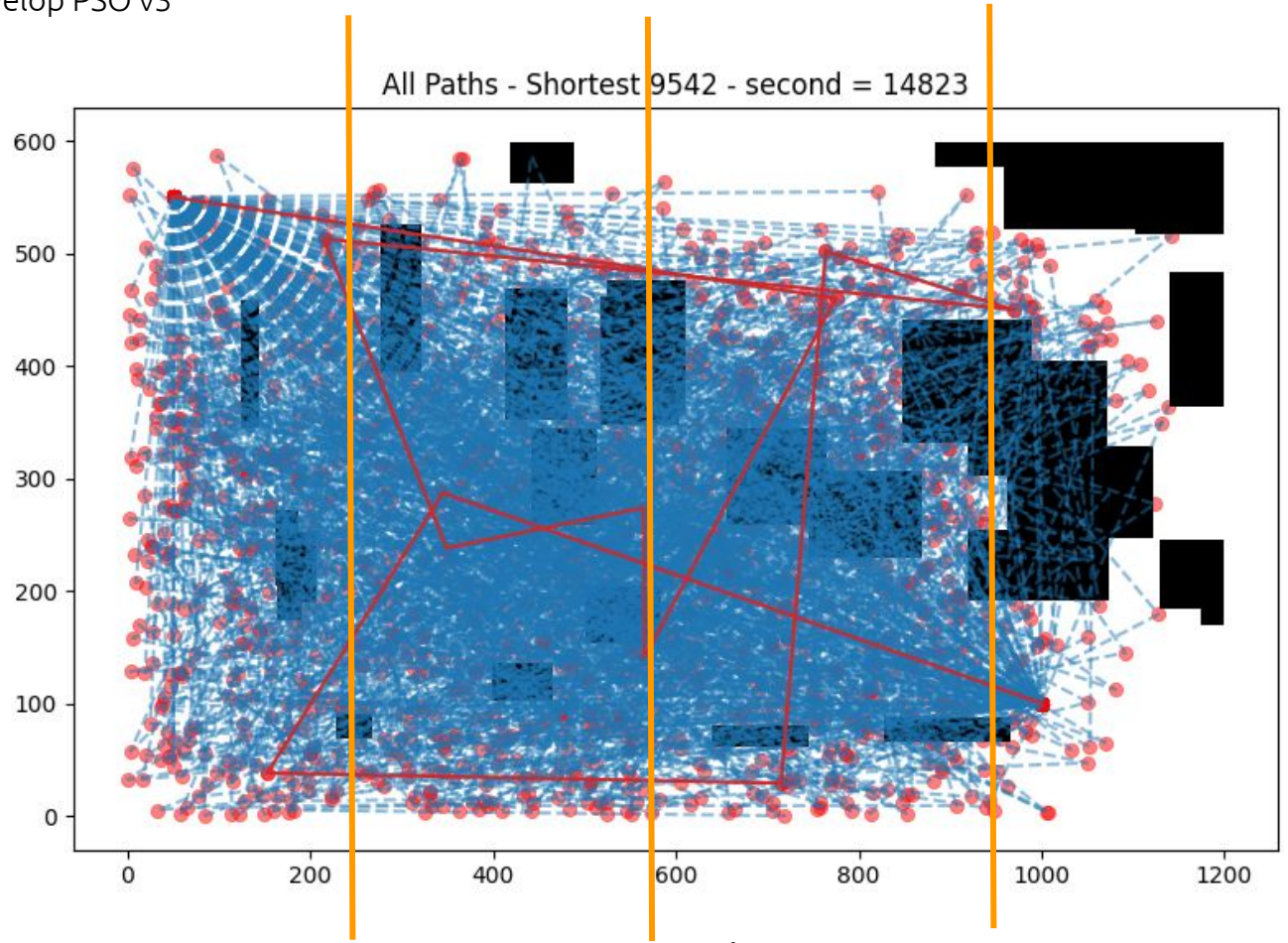




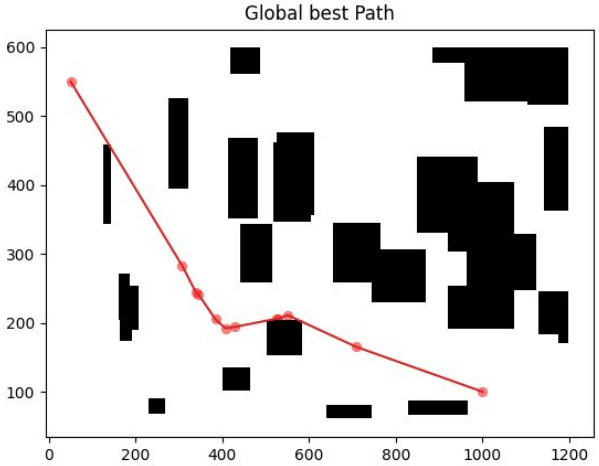



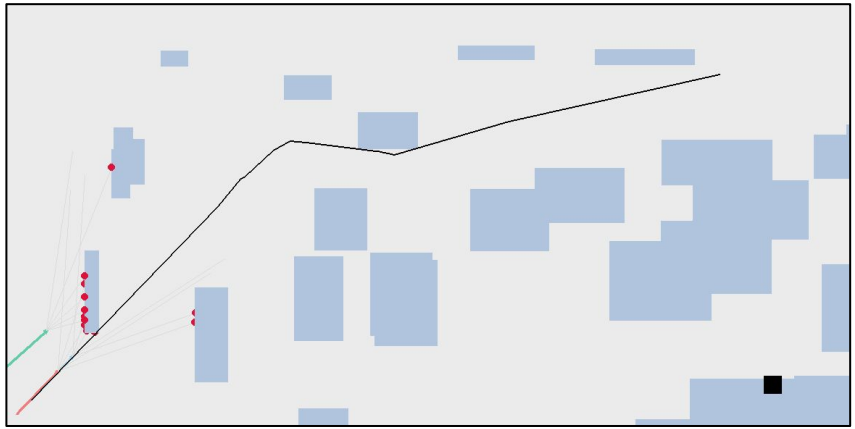
Scenario to develop PSO v3

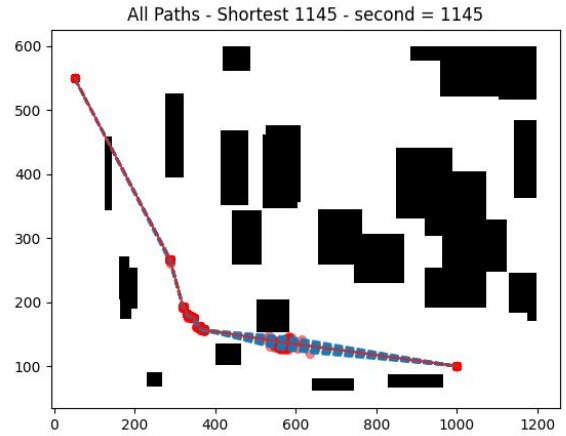


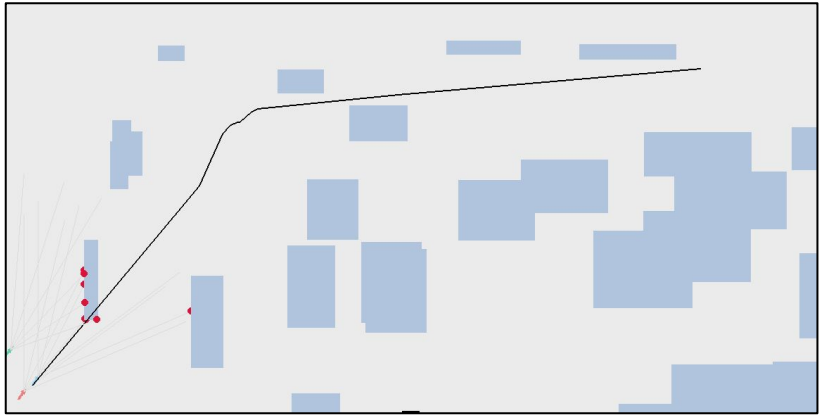

**One Iteration**

PSO v2 Cost: Inside point

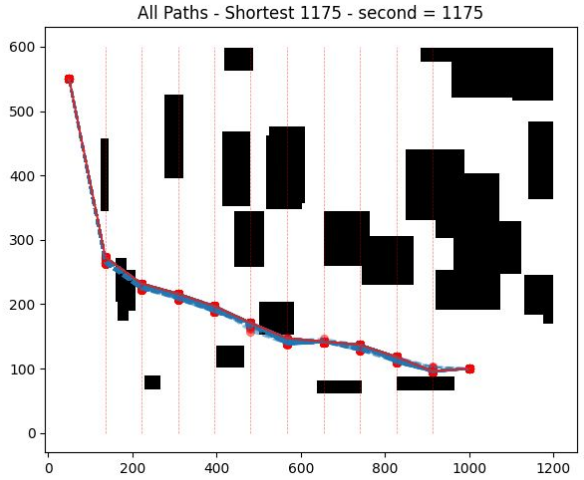


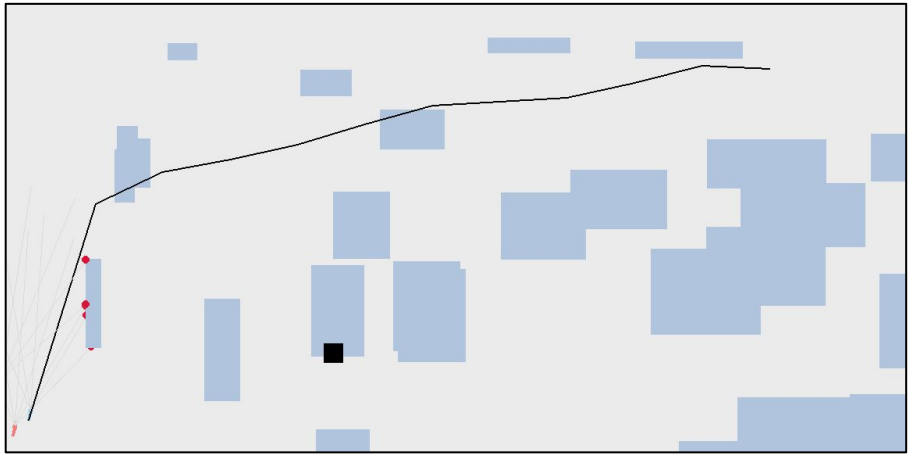



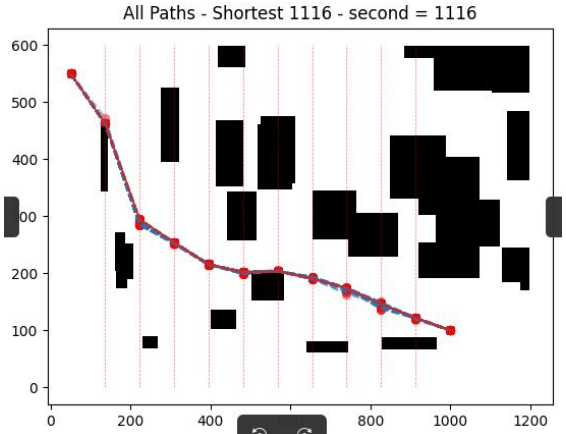


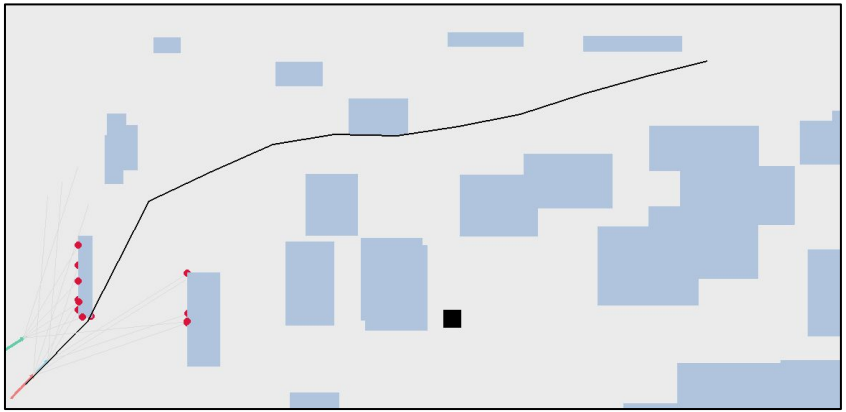



PSO v1 Cost: Inside point Unitree





Unitree, 4 legged robot

https://github.com/unitreerobotics/unitree_ros

https://www.unitree.com/opensource/

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