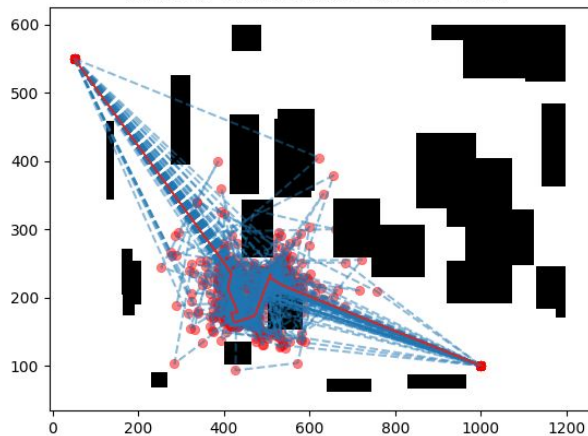


# PSO

versions results

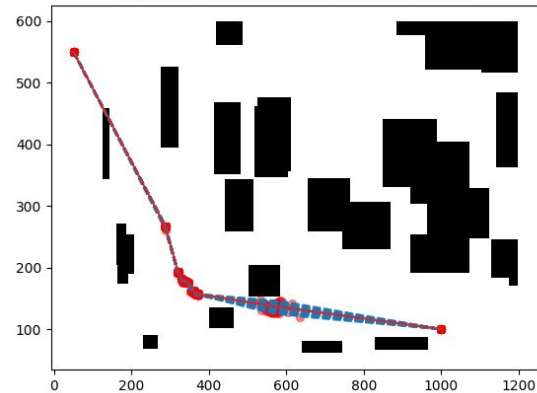
**v2** rect collision - 12 points

All Paths - Shortest 2433 - second = 2434



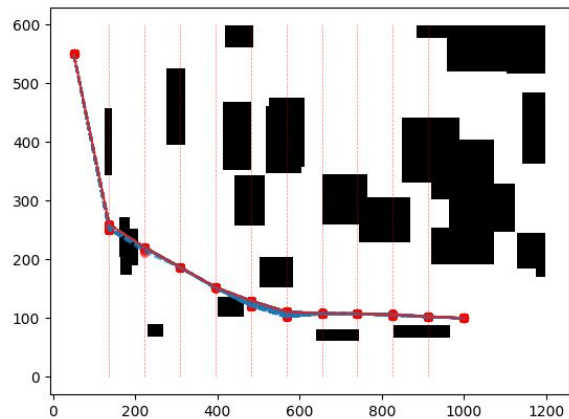
**v2** inside collision - 12 points

All Paths - Shortest 1145 - second = 1145



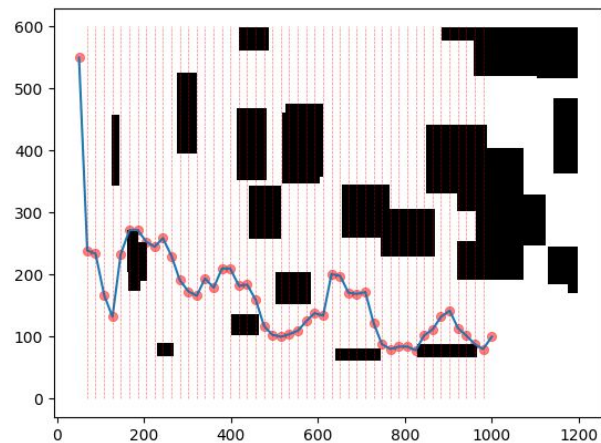
**v1** inside collision - 12 points

All Paths - Shortest 1189 - second = 1189

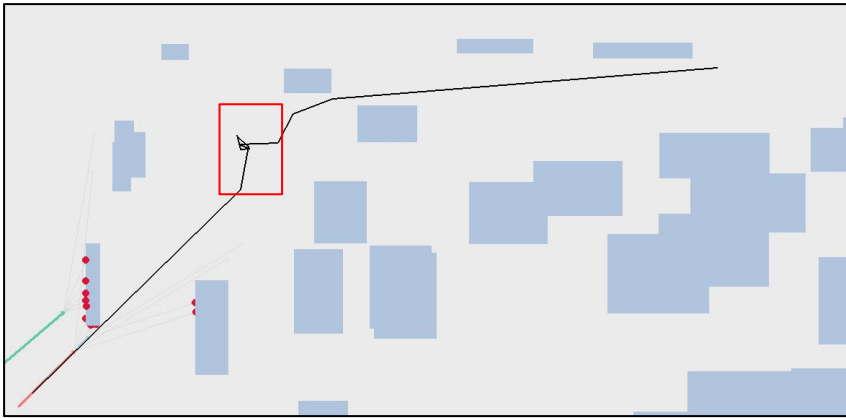
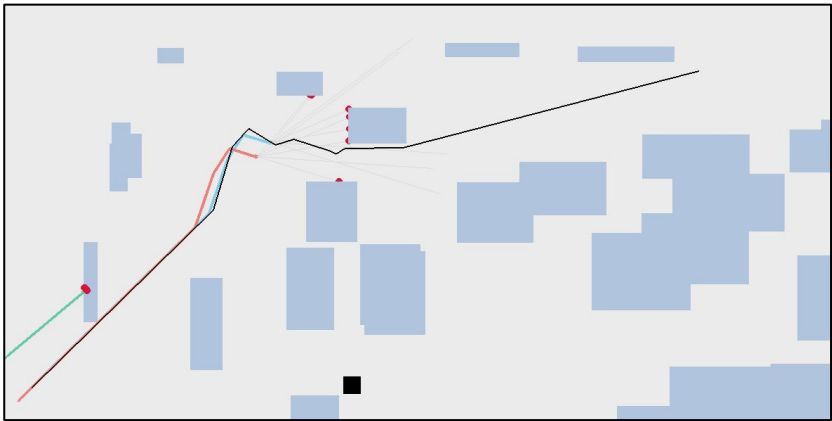
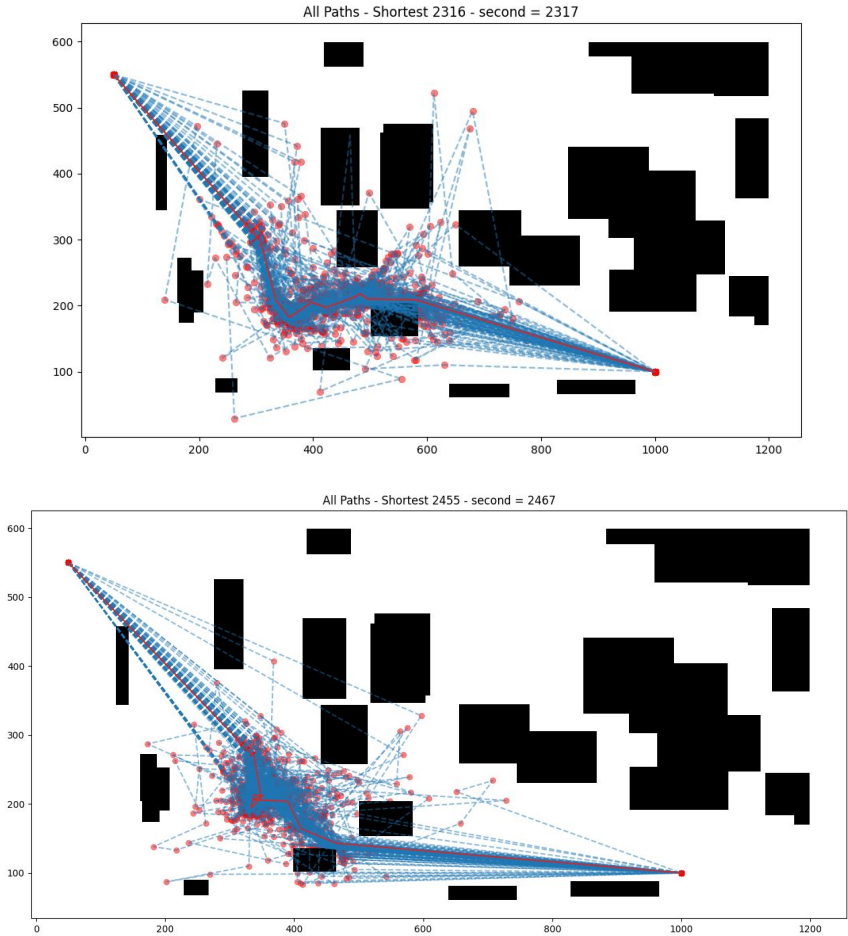


**v1** inside collision - 50 points

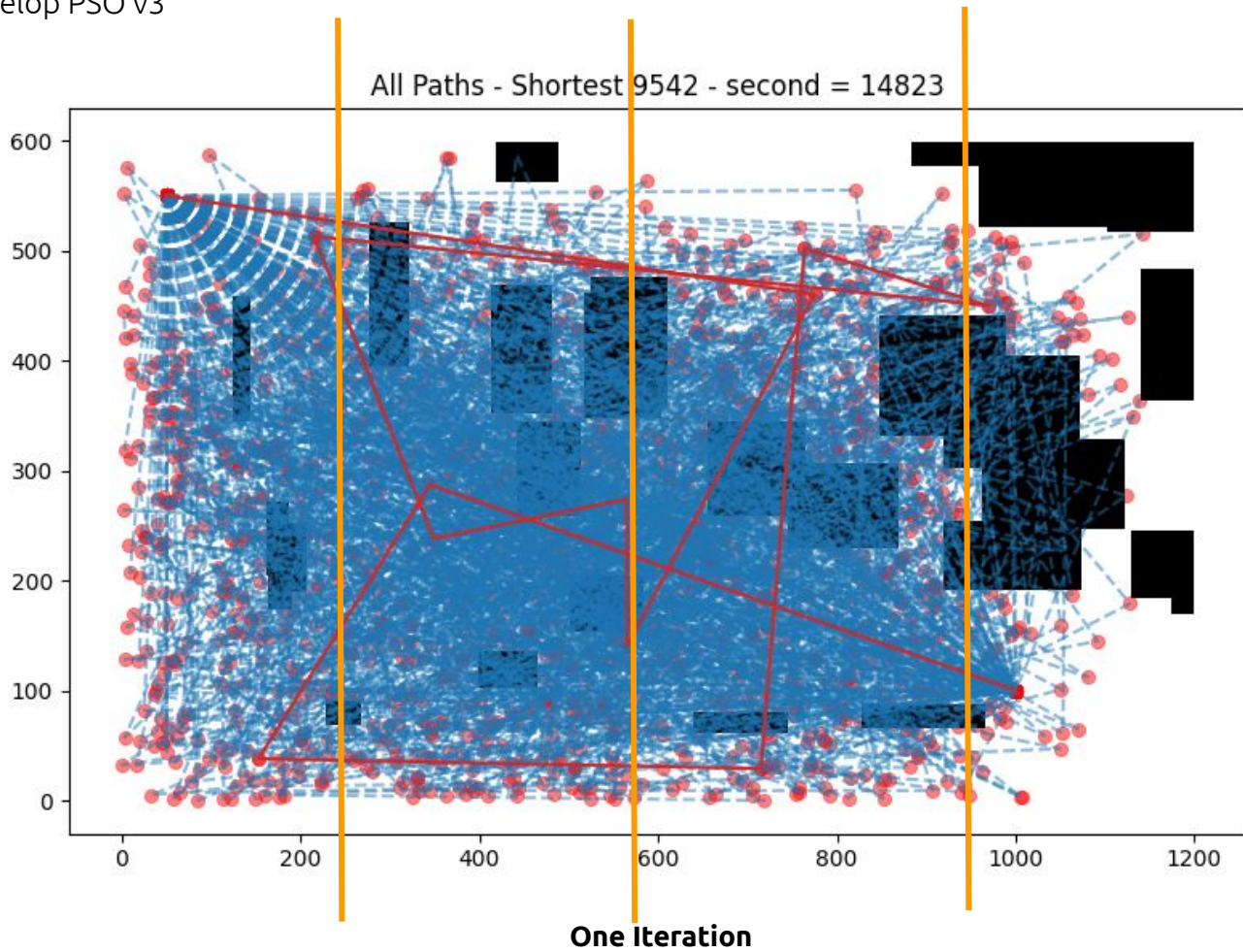
Global best Path



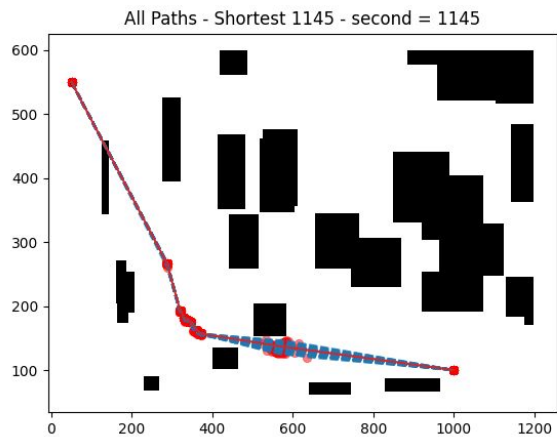
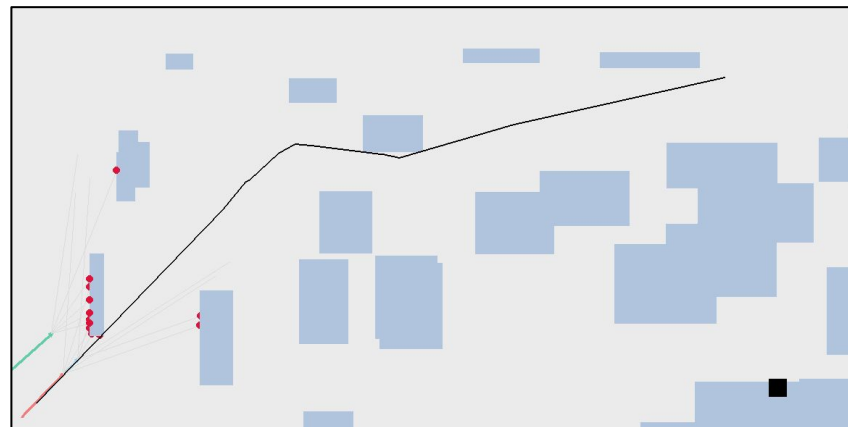
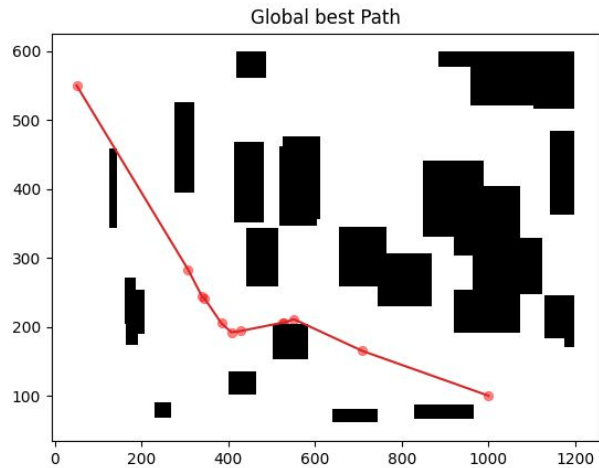
PSO v2 Cost: rectangle collision and inside point



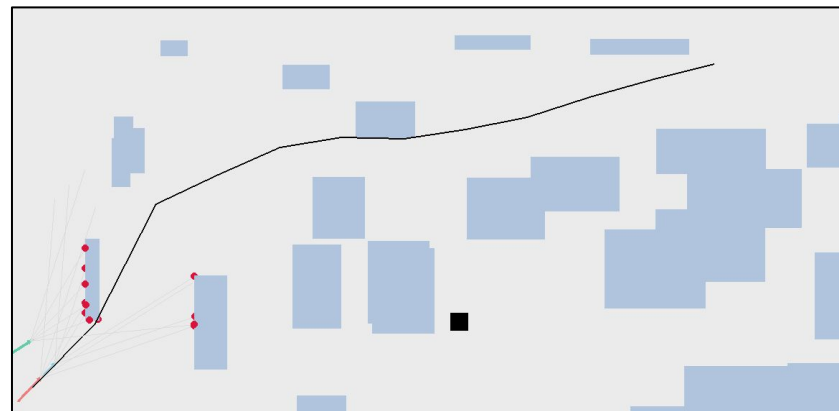
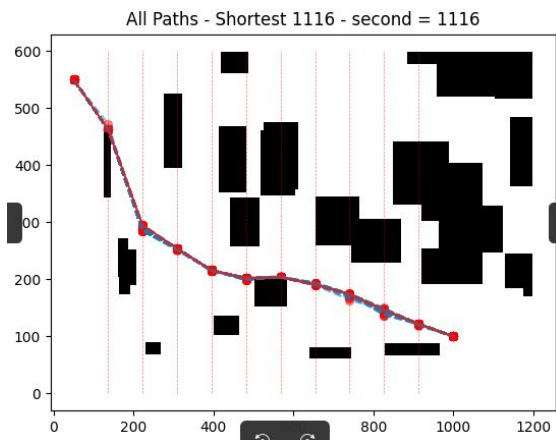
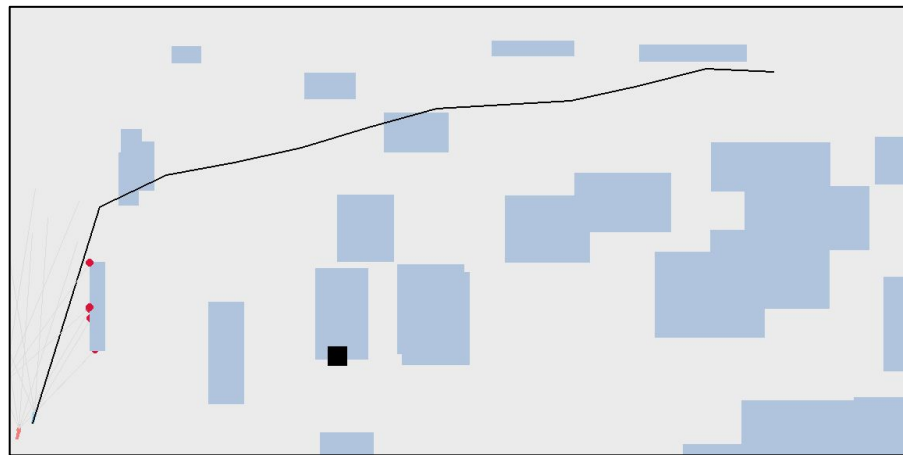
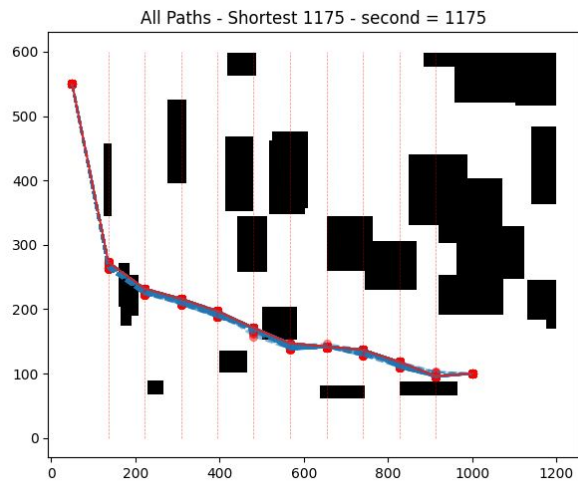
## Scenario to develop PSO v3



## PSO v2 Cost: Inside point



## PSO v1 Cost: Inside point Unitree



Unitree, 4 legged robot

[https://github.com/unitreerobotics/unitree\\_ros](https://github.com/unitreerobotics/unitree_ros)

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

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