# Self-aware drone swarm for transportation

## Mohammad Rahmani

# 1  Homeostatic

Keep maximum stability which is

# 2  Generative models

## 2.1  Initial model - constant movement between two points

## 2.2  Vertical frame maneuver

## 2.3  Horizontal frame maneuver

# 3  Leader-follower

**Ranking**  The one which is closer to the destination will be ranked lower and the ranking starts from 1. The leader is rank 1

# 4  Neighboring interaction

Interaction fellow is only possible between the neighboring agents. the two agents are neighbors only if they rank in row according to their distance until the destination.

# References