Title

A thesis submitted to the University of Manchester for the degree of Doctor of Something in the Faculty of Something.

2023

My name
My department

LIST OF CONTENTS

WORD COUNT: 0

LIST OF FIGURES

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List of Abbreviations

HRI	Human Robot Interaction

LIST OF SYMBOLS AND NOTATIONS

$P(A)$	Probability of event A
$\boldsymbol{h}$	Quaternion

ABSTRACT

Abstract limited to one page.

Lay Abstract

Optional lay abstract limited to one page.

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ACKNOWLEDGMENTS

Optional acknowledgments

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INTRODUCTION

Example of citation: Adorno (2017).

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Table 1.1: Example of table with a long long long long long long long long long long long long long caption.

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Appendix

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PUBLICATIONS

List of publications related to the work.

REFERENCES

Adorno, B. V. (2017). "Robot Kinematic Modeling and Control Based on Dual Quaternion Algebra - Part I: Fundamentals". In: URL: https://hal.archives-ouvertes.fr/hal-01478225.