



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

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LIST OF ABBREVIATIONS

HRI	Human Robot Interaction
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LIST OF SYMBOLS AND NOTATIONS

$p(A)$ Probability of event A

h Quaternion

ABSTRACT

Abstract limited to one page.

LAY ABSTRACT

Optional lay abstract limited to one page.

DECLARATION

A declaration stating:

- EITHER: that no portion of the work referred to in the thesis has been submitted in support of an application for another degree or qualification of this or any other university or other institute of learning;
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THE AUTHOR

It is advisable to include a brief statement for External Examiners, giving the candidate's degree(s) and research experience, even if the latter consists only of the work done for this thesis. This may be untitled or it may be headed 'Preface' or 'The Author' or similar.

ACKNOWLEDGMENTS

Optional acknowledgments

Optional dedication

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INTRODUCTION

Example of citation: Adorno (2017).

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1.1 Examples of figure and table

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Figure 1.1: Example of figure.

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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 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>.