Microcontroller-based Fire Sensing and Extinguishing Mobile Robot

A Thesis
Presented to the Faculty of the
Department of Electronics and Communications Engineering
Gokongwei College of Engineering
De La Salle University

In Partial Fulfillment of the
Requirements for the Degree of
Bachelor of Science in Computer Engineering

by

CHUA, Sean Herbie P.
LIMQUECO, Jerald Steven G.
LU, Ervin Lester G.
QUE, Sean Wyndell T.

July, 2016

De La Salle University

ORAL DEFENSE RECOMMENDATION SHEET

This thesis, entitled **Microcontroller-based Fire Sensing and Extinguishing Mobile Robot**, prepared and submitted by thesis group, HERBS, composed of:

CHUA, Sean Herbie P.
LIMQUECO, Jerald Steven G.
LU, Ervin Lester G.
QUE, Sean Wyndell T.

in partial fulfillment of the requirements for the degree of **Bachelor of Science in Computer Engineering** (**BS-CPE**) has been examined and is recommended for acceptance and approval for **ORAL DEFENSE**.

Engr. Melvin K. Cabatuan
Adviser

July 24, 2016

De La Salle University

THESIS APPROVAL SHEET

This thesis entitled **Microcontroller-based Fire Sensing and Extinguishing Mobile Robot**, prepared and submitted by:

CHUA, Sean Herbie P.
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QUE, Sean Wyndell T.

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PANEL OF EXAMINERS

Engr. Maria Antonette C. Roque
Chair

Engr. Donabel D. Abuan
Member

Engr. Argel A. Bandala
Member

Engr. Melvin K. Cabatuan
Adviser

Date: July 24, 2016

De La Salle University

ACKNOWLEDGMENT

Write this prior to hard binding if you have submitted all requirements and are told by your adviser that you have passed.

ABSTRACT

Keep your abstract short by giving the gist/nutshell of your thesis.

Index Terms—microcontroller, fire, sensing, extinguishing, mobile, robot.

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ABBREVIATIONS

AC	Alternating Current	56
HTML	Hyper-text Markup Language	56
CSS	Cascading Style Sheet	56
XML	eXtensible Markup Language	56

NOTATION

$\mathcal{S}$	a collection of distinct objects	58
$\mathcal{U}$	the set containing everything	58
$\emptyset$	the set with no elements	58
$\lvert\mathcal{S}\rvert$	the number of elements in the set $\mathcal{S}$	58
$h\left(t\right)$	impulse response	48
$x\left(t\right)$	input signal represented in the time domain	48
$y\left(t\right)$	output signal represented in the time domain	48

Throughout this thesis, mathematical notations conform to ISO 80000-2 standard, e.g. variable names are printed in italics, the only exception being acronyms like e.g. SNR, which are printed in regular font. Constants are also set in regular font like j. Functions are also set in regular font, e.g. in $\sin\left(\cdot\right)$. Commonly used notations are t, f, $\mathrm{j} = \sqrt{-1}$, n and $\exp\left(\cdot\right)$, which refer to the time variable, frequency variable, imaginary unit, nth variable, and exponential function, respectively.

GLOSSARY

matrix a concise and useful way of uniquely representing and working with linear transformations; a rectangular table of elements 58

LISTINGS

Chapter 1

INTRODUCTION

Contents

1.1 Background of the Study

A mobile robot is an automatic machine that is fast evolving and has a significant role in the industry. It is capable of moving from one place to another or to execute the program it was given. Some mobile robots have the capability to navigate without the user controlling it, while there are also mobile robots that can be controlled through controllers. Some of its application in the industry includes, manufacturing, agriculture, medical, aerospace and etc. Mobile robots are made up of software, controller, actuators and sensor. Its controller can be made using embedded microcontroller, microprocessor or a computer. Its controller is programmed using assembly language, C, C++ and etc. The kind of sensor that will be equipped in the mobile robot depends on the application. Some application can be for proximity sensing, collision avoidance, positioning, distance calculator and etc.

The plan is to create a firefighting robot that will be able to extinguish fire and draw the smoke in. It is capable of detecting fire and smoke using a flame sensor and smoke sensor. It can also extinguish the flames by using the small fire extinguisher equipped on it. The mobile robot will be Arduino-based. It will consist of several DC motors.

The constants will be the battery, the fan, and the room to be used. The goal is to design a system that will allow all components of the robot to function harmoniously. The flame sensor will be integrated with the Arduino to be able to sense the flame and alarm the vehicle. It will approach it and extinguish it using the canister equipped with it.

1.2 Prior Studies

There are many ways to detect fire. As technology improves, ways to detect fire became more and more reliable and accurate. The most reliable fire detectors are still humans

because they can see the fire and smell the smoke the moment they appear, which allows them to respond quickly. However, at times when people are not home, electronic fire detectors are needed to keep a house or building safe. One such sensor is the heat detector. According to Science Learning Hub, most heat-detecting sprinklers used these days utilize a fragile glass bulb containing fluid that expands with heat. The glass breaks, spraying water down from the sprinkler. Heat detectors do not cost much and are relatively reliable. They operate completely without electricity as well, which makes them very popular in large establishments. They are, however, slow to respond as the heat needs to reach the ceiling to activate the sprinklers.

Another way to detect fire is through the use of smoke detectors. Smoke detectors respond faster than heat detectors. They are more sensitive and can respond the moment it detects the smoke from the fire. One drawback of the smoke detector is its complex design and its price. Another drawback is its sensitivity. Sometimes the smoke detector cannot differentiate fire smoke from normal steam or dust.

Other ways to sense fire include optical flame detectors. These detectors work using ultraviolet or infrared light. Infrared flame detectors sense fire through the infrared spectral band for unique patterns emitted by the hot gas of the flame. However, accuracy of the infrared flame detectors is largely affected when exposed to direct sunlight. Ultraviolet detectors, on the other hand, operate by sensing the UV radiation given off by the flame. These sensors are capable of detecting flames in three to four milliseconds. Between these two optical flame detectors, the UV detector is much more accurate and reliable.

1.3 Problem Statement

According to the Philippine Statistics Authority, at least 2,000 fire incidents happen on the months of April to May each year. Fire incidents is one of the major setbacks to the growth of the Philippines economy because it does not only do damage to properties, but also result to a sizable number of casualties. With the joint efforts of the Bureau of Fire Prevention (BFP), Red Cross, and other Non-Government Organizations (NGOs), the amount of destruction caused by fires decreased.

However, due to the recent incidents of heavy traffic in Metro Manila, fire and medical volunteers are having a hard time arriving at their destinations. Because of the delayed response of the volunteers, about 2.5 billion pesos worth of property are destroyed, 5,000 civilians left homeless, and 90 persons killed (58 civilians and 32 firefighters) in Metro Manila only. Lack of proper fire response equipment in local barangays also play a part in the destruction caused by the fire.

In response to this problem, The researchers study proposes to create a microcontroller-based mobile robot that can sense and extinguish fire. The said robot can be deployed manually (by a technician) or automatically (by using its flame sensor) to the concerned location. Because the robot will already be placed in the building, the immediate response time to treat the fire will be fairly shorter as compared as to calling the fire department.

1.4 Objectives

1.4.1 General Objective(s)

To design and to develop a wheeled mobile robot that is capable of detecting fire using an

infrared-based flame sensor, and extinguish fire with the use of a small fire extinguisher mounted onto the robot.

1.4.2 Specific Objectives

To design and to develop a voltage booster circuit that is capable of powering up a mobile robot carrying a small exhaust fan.;

To design and to develop a mobile robot that can detect and locate a flame source.;

To develop a mobile robot that is capable of detecting the face of a human within a room with smoke.;

1.5 Significance of the Study

People working or living in a building

People working or living in buildings that have no complete fire precautions (protection) can use this robot in their daily lives. While the firefighters are still on their way to the rescue, this firefighting robots can clear the smoke from the persons pathway so he or she wont suffocate on his or her way out of the vicinity. It can also help people who are trapped in their rooms by extinguishing the flame on small areas using the fire extinguisher equipped on the mobile robot.

Fire Fighters

This robot can be a great help for firefighters because it can start killing some fires to evacuate the people in a room while the firefighters are on their way to the site or when they

are stuck in traffic. It can also lessen the number of deaths among firefighters by letting this robot go into the building to check if there are still small fires or if there are things that are on fire. Furthermore, unmanned vehicles are more suitable for dangerous task to reduce the injuries or even deaths of people.

School/University

This can also give aid in the universities especially in the laboratories where it is possible to have a fire outbreak like chemistry laboratories, electronic laboratories and etc.

Selling Point

The slightest amount of time during a fire outbreak is very crucial which may decide whether the person will live or die. This mobile robot is designed to help the people in case of a fire in buildings, houses or any closed vicinity, while the firefighters get to the burning site. This mobile robot will not only help the people create a smokeless pathway but will also kill small fires with a mini fire extinguisher equipped. It also lessens injuries and deaths to firefighters since it is an unmanned vehicle.

1.6 Assumptions, Scope and Delimitations

This study will focus on using flame sensors in locating the fire approximately 1 foot away.;

The study will also use an ultrasonic sensors to avoid obstacle and navigate through the room.;

The researchers will use a camera to implement face detection in order to locate victims.;

This study will only cover extinguishing of small scale of fire that have started from non-electrical things.;

The researchers will use an Arduino board as means of communication between the sensors and the motors.;

The researchers will design a battery management module for the robot so the input power will be distributed among the components without making one part of the robot fail or breakdown.;

The mobile robot will not cover fire proofing.;

1.7 Description and Methodology

The project aims to extinguish fire using a wheeled mobile robot equipped with an Arduino, a fire extinguisher, fans, flame sensors, and ultrasonic sensors. The Arduino board acts as the controller of the mobile robot that loads the program that controls the movement of the robot, fans, and sensors which control the fire extinguisher. The board interprets the data sent by the sensors to the microcontroller and loads a specific program which triggers the movement of the robot, the fans, and the fire extinguisher. Since the robot is controlled by sensors, a camera will be mounted in front of the robot to allow the user to see the surroundings and objects in front of it, and detect a human face inside a smokey room.

The research project allows the use of different devices such as fans, camera, sensors, fire extinguisher and a wheeled mobile robot. The researchers would use an algorithm that would allow the mobile robot to navigate through an area and search for fire which it will extinguish while its fans are absorbing the smoke. The research project will then take

inputs from the sensor whether the robot should move or not and whether the fan should rotate or not. The camera equipped on the mobile robot will also detect victims of the fire.

The mobile robot will consist of an Arduino board connected to a motor driver which controls the DC motors. The sensors connected on the mobile robot will consist of the following: ultrasonic sensors, flame sensors, and smoke sensor. The ultrasonic sensor is used by the mobile robot to navigate through the room. The flame sensor is used to locate the flame about a foot apart. The smoke sensor will dictate when the fans will operate in sucking the smoke. The mobile robot will also be equipped with a fire extinguisher which the mobile robot will use in killing the fire. Lastly, the camera will be used in detecting victims of the fire.

The accuracy of the flame sensor can be verified by testing the sensor on set distances from the flame. The flame sensor will first be tested 10 times while placed 3 feet away from the flame; followed by another 10 times, 2 feet away; and finally another 10 times, 1 foot away.

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1.8 Estimated Work Schedule and Budget

Item	Quantity	Price (PHP)
Arduino UNO (GizDuino Board)	1	400
Bluetooth Camera	1	430
Flame Sensor	3	135
Ultrasonic Sensor	3	750
Smoke Sensor	1	500
Used Exhaust Fan	2	400
Battery	2	300
Buzzer	1	15
Used RC Car	1	500
Fire Extinguisher	1	195
DC to DC Booster	1	140
Battery Management System Board	1	500
Total	4265	

Figure 1. Estimated Budget

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	May	June					July				August			
	W1	W2	W3	W4	W5	W6	W7	W8	W9	W10	W11	W12	W13	
Research for a topic														
Submission of proposed topic														
Background of the Study														
Statement of the Problem														
Objectives														
Abstract														
Scope and Delimitations														
Methodology														
Review of Related Literature														
Individual research														
Schematic Diagram														
Battery System														
Sensors														
Arduino Programming														
Android Programming														
Android Layout														
Board Design														
Board Layout														
Fabrication														
Mounting														
Proofreading and Revisions														
Final Documentation														
Defense														

Figure 2. Gantt Chart

MORFCPE : MICROCONTROLLER BASED FIRE SENSING AND EXTINGUISHING MOBILE ROBOT

Prepared by: S.H. CHUA, J.S. LIMQUECO, E.L. LU, S.W. QUE

Approved by: Engr. MELVIN CABATUAN

PLAN OF ACTIVITIES

Activities	P.I.C.		Wk-1 (May23-May29)	Wk-2 (May30-Jun05)	Wk-3 (Jun06-Jun12)	Wk-4 (Jun13-Jun19)	Wk-5 (Jun20-Jun26)	Wk-6 (Jun27-Jul03)	Wk-7 (Jul04-Jul10)	REMARKS
1.) Documentation	Herbie, Jerald, Ervin, Wyndell	plan								
		actual								
2.) BMS	Ervin, Jerald, Wyndell	plan			Researched about BMS					
		actual								
3.) Mobile Robot	Ervin, Jerald, Herbie	plan			Tested the motors and fans					
		actual								
4.) Sensors Testing	Herbie, Wyndell	plan			Tested the flame sensor					
		actual								
5.) Face Detection	Herbie, Jerald, Ervin, Wyndell	plan								
		actual								
6.) Debugging of Program	Herbie, Jerald, Ervin, Wyndell	plan								
		actual								
7.) System Integration	Herbie, Jerald, Ervin, Wyndell	plan								
		actual								
8.) Weekly Progress Repor	Herbie, Jerald, Ervin, Wyndell	plan	Generated topic idea	Completed Chapter 1	Completed Chapter 1 and 2					
		actual								
9.) Final Report Preparation	Herbie, Jerald, Ervin, Wyndell	plan								
		actual								
10.) Defense	Herbie, Jerald, Ervin, Wyndell	plan								
		actual								

Figure 3. Workplan

1.9 Overview

This paper shows how the researchers designed a firefighting mobile robot. It contains all the necessary informations needed to build the robot. The first chapter includes a description of the specifications and functions of the mobile robot. It also has prior studies about the topic that the researchers used to design the robot. The following chapters will cover the research undergone by the researchers to explore the possibilities attainable by the robot through academic articles.

Chapter 2

LITERATURE REVIEW

Contents

2.1 Mobile Robots

2.1.1 Operation of Mobile Robot

According to Pandey, Kumar, Pandey, and Parhi (2016), navigation and obstacle avoidance are the most important task for any mobile robot. Using the Adaptive Neuro-Fuzzy Interference System (ANFIS) controller, it uses several transducers to detects obstacles in an unknown environment. The ANFIS is product of by Takagi-Sugeno fuzzy interference system and Artificial Neural Networks (ANN). Similarly, the objective of this thesis is to create a firefighting wheeled mobile robot that will be able to navigate through foggy places.

2.1.2 Mobile Robot Controlled with Android Device

Basing from an article by Pahuja and Kumar (2014), controlling the mobile robot was done using the HC serial bluetooth. In this article, the HC-06 bluetooth module was used together with the 8051 microcontroller. The flow of the data is from the bluetooth module, which will be sent to the decoder. Then, it goes straight to the microcontroller, which dictates a different data depending on the buttons pressed by the master module. It will dictate how the motors should operate based on the data received by the bluetooth module.

2.1.3 Mobile Robot Navigation

The mobile robot can be implemented using a microcontroller, the Programmable Interface Controller (PIC). According to Kendre, Mulmule, and Shinde (2010), the PIC is economical and has a high computational performance. Based from the article, the mobile robot was

able to navigate through a simple lined map using a heuristic search algorithm. The mobile robot is capable of mapping the layout of the area and can store the information. It also has the capability of sharing the information with other mobile robots using an ASK transmitter and ASK receiver. In its first run, it maps out the area and during its succeeding run, the mobile robot knows the right path. This will be of significant help when creating a robot that has the capability of traversing the room. According to Thrun (1997), there are two types of indoor mapping: the grid-based and topological. The grid-based map is the layout of the room. The topological map is the pathway map. The grid-based produces more accurate metric maps but are complex and iefficient, especially in large rooms. The topological is more efficient but is less accurate compared to the output of a grid-based mapping.

2.2 Battery Management System

Modern battery operated robots performs very complicated tasks because more and more applications are added unto its system which demands more power from its input. Some of the new applications are cameras, navigation, bluetooth, mapping and etc. These robots cannot tell if the battery used is enough or not when an additional component is added onto it which may cause its operation to breakdown. Even worse, batteries may be used incorrectly due to lack of knowledge which may reduce or damage its performance. According to Cai, Du, and Liu, power supply is the basic problem when it comes to adding applications to a robot. With these kind of problems, robots are being unacceptable to security or critical applications. According to Lucas, Codrea, Hirth, Gutierrez, and Dressler, these problems can be avoided with proper knowledge and proper battery management system. A robot

battery management and monitoring system is an improved interface between the battery and the robot. It monitors the battery state and controls the charging process of the battery.

According to Lucas, Codrea, Hirth, Gutierrez, and Dressler, It is common for robots to have lead-acid batteries as their supply. These batteries are accepted by the users even though these cells have a low power-density because it is cheap and powerful. The RoBM2 board is an adaptable platform for implementing battery supervision policies, even without the smart power supplies. Smart power system is a complete power system that has a multiple specification for portable devices. Smart battery, smart battery charger and a SMBus Host should always be present in a smart power system. The system management bus or SMBus is a two-wire bus transporting data between devices.

2.3 Sensor

2.3.1 Ultrasonic Sensor

In order for the mobile robot to move autonomously, it needs distance measuring sensors to determine the presence of an obstacle in front of it. Ultrasonic sensors are largely used for this application due to its relatively high reliance and low cost. According to Vaduva (2013), through the use of the triangulation method, the ability of the sensors to detect an object would increase in efficiency. Using a single ultrasonic sensor would only detect the presence of an object. However, using two ultrasonic sensors would allow a two dimensional detection of an object. It will not only calculate the distance, but the angle at which the obstacle is facing the sensor as well. There are some disadvantages in using the ultrasonic sensor. Errors usually happen with transparent or shiny objects.

2.3.2 Flame Sensor

In a study made by Punuganti, Srinivas, Savanoor, and Shree (2014) in designing a fire-fighting robot, they used a generic infrared fire sensor to detect flames. In the occurrence of a fire, distinct changes in the IR region are exhibited by the flame. The fire sensor module used weighs a total of five grams and has a maximum range of one meter. An LED is attached to the module to indicate whether the sensor detected a fire or not. To cover a wider field of view, the researchers used four IR fire sensors, one on each side of robot.

Another type of fire sensor is the ultraviolet fire sensor. According to Bharathi and Prasad (2013), a flame from a tiny candle can be detected by the UV fire sensor five meters away. The UV sensor in particular is called the Hamamatsu UV TRON Flame Detector. It is more reliable and accurate than the IR sensor, but the price is much more expensive.

2.3.3 Smoke Sensor

According to Luis, Galan, and Espigado (2015), the use of smoke sensors is the most popular method in detecting fires due to its quick response and low cost. However, they stated that using only one sensor to detect fire can be unreliable. To improve the accuracy of the smoke alarm, they added a few more relevant sensors. The smoke sensor triggers when smoke particles enter into the chamber of the component and activates a photosensitive device when light bounces off from the smoke particles. A carbon monoxide sensor is added to the device to measure the level of carbon monoxide in the air. The main function of this sensor is differentiating actual fire smoke from steam or dust. This added component increased the reliability of the smoke detector significantly.

Another way to detect smoke is through image processing. According to Luo, Yan,

Wu, and Zheng (2015), condensing a video can significantly increase the efficiency in detecting the smoke through special characteristics exhibited by the smoke trajectories. There are many advantages to using a video camera over a sensor. Not only is it cheaper, it can be applied to a wider angle and longer range. This is especially effective for forest fires. There are five unique smoke trajectory characteristics that can help in detecting the smoke and these are the right-leaning line of the velocity-to-time trajectory, the smooth streamline, the low frequency of the smoke clique, the fixed source of the smoke, and the vertical-horizontal ratio. Since smoke always appear when there is fire, using this method can make for an excellent early warning system.

Chapter 3

THEORETICAL CONSIDERATIONS

Contents

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3.1 Summary

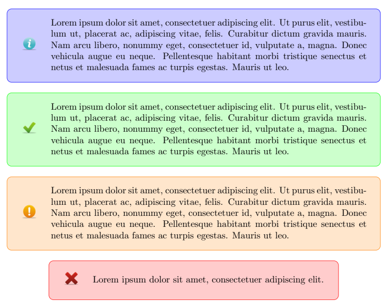

Fig. 3.1 A quadrilateral image example.

Chapter 4

DESIGN CONSIDERATIONS

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4.1 Summary

Chapter 5

METHODOLOGY

Contents

The proposed study work is is mainly focused to find out whether the proposed mobile robot can detect and locate a fire, suck smoke away from the human face, and detect a human face in a smokey room effectively and efficiently. The main hypothesis of the proposed system is the effective and efficient fire detection, smoke redirection, and human face detection. The proposed mobile robot will be using two Arduino UNO boards that will serve as the main controllers, three HC-SR04 ultrasonic sensors that will aid the robot to navigate through a room, two infrared flame sensors that will detect and guide the robot to the flame source, one L298N dual bridge motor controller module that will drive the main motors of the mobile robot, one toy tank chassis, which includes the rubber tracks and the motors, that will serve as the mobile robot itself, one MQ2 smoke sensor that will detect the presence of smoke, one exhaust fan, which is composed of four 12V computer fans, that will suck the air away, one buzzer that will serve as an alarm when fire and smoke are detected, rechargeable batteries that will serve as the main power supply for the robot, one fire extinguisher that will be used to extinguish the fire, and a laptop that will be our workstation in implementing, coding, and interfacing everything all together.

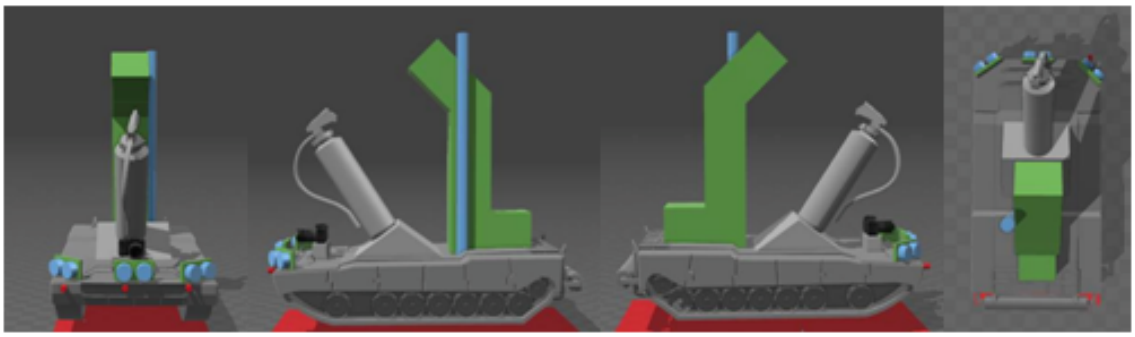

Fig. 5.1 Target Mobile Robot Design

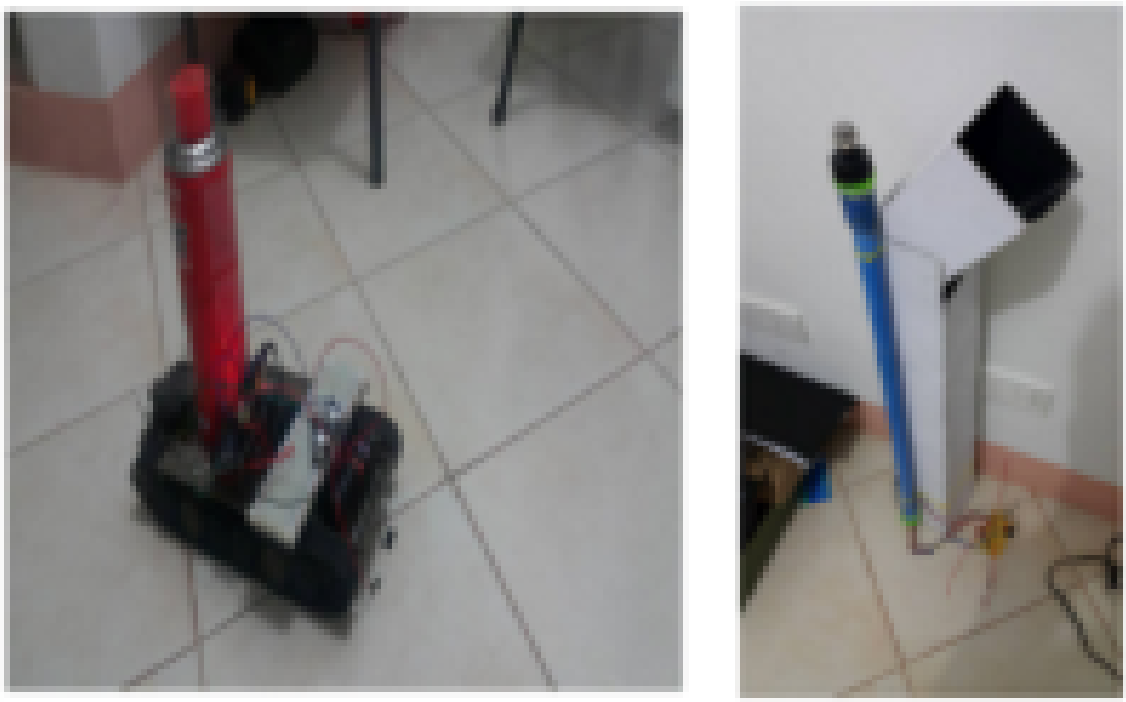

Fig. 5.2 Current Mobile Robot Design

5.1 Implementation

The proposed mobile robot will be connected as shown in Figure 5.1 with the actual set up (as of the moment) and the exhaust fan shown in Figure 5.2.

The implementation phase of the proposed system was broken into two sub phases, the individual tests where each component of the proposed mobile robot are put into rigorous testing to their maximum capacity without breaking down, and the actual testing where everything is assembled together and the actual performance of the system can be tested. The researchers are currently in the individual tests interfacing the two Arduino UNO boards. The proposed algorithm for the system will be composed of two parts, the Room Handling Algorithm, and the Navigation Algorithm. The flowchart on the program flow is shown in Figures 5.3 and 5.4 respectively.

5.2 Evaluation

5.3 Summary


START
Enter room
Navigate through room
Does it have fire?
NO
YES
Navigate through room and locate exit
Exit room and proceed to next room
Navigate through room
Search for candle
Exit room and proceed to next room
Navigate through room and locate exit
Navigate through room
NO
Fire located?
YES
Move close to candle
Turn on fan and extinguish fire (10 seconds)
NO
YES

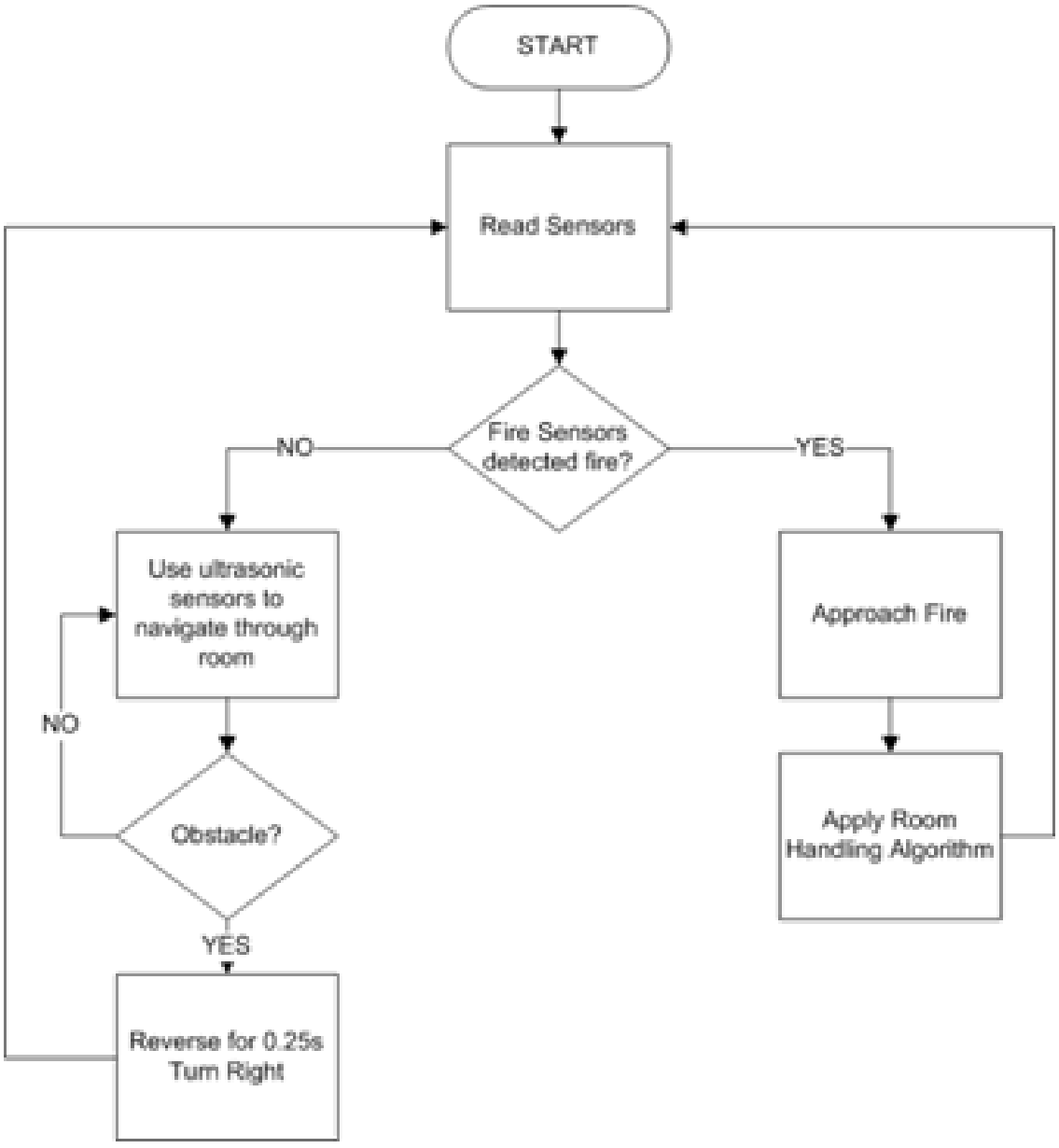

Fig. 5.4 Navigation Algorithm

Chapter 6

RESULTS AND DISCUSSION

Contents

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6.1 Summary

Chapter 7

CONCLUSIONS, RECOMMENDATIONS, AND FUTURE DIRECTIVES

Contents

7.1 Concluding Remarks

In this Thesis, . . .

7.2 Contributions

The interrelated contributions and supplements that have been developed in this Thesisare listed as follows.

- the ;
- the ;
- the ;

7.3 Recommendations

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De La Salle University

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7.4 Future Prospects

There are several prospect related in this research that may be extended for further studies. . . . So the suggested topics are listed in the following.

1. the . . . .
2. the . . . .
3. the . . . .

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[Oetiker et al., 2014] Oetiker, T., Partl, H., Hyna, I., and Schlegl, E. (2014). *The Not So Short Introduction to LaTeX 2ε Or LaTeX 2ε in 157 minutes*. n.a.

Produced: July 24, 2016, 21:14

Appendix A
ANSWERS TO QUESTIONS TO THIS THESIS

Contents

De La Salle University

A1 How important is the problem to practice?

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A2 How will you know if the solution/s that you will achieve would be better than existing ones?

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A2.1 How will you measure the improvement/s?

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A2.1.1 What is/are your basis/bases for the improvement/s?

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A2.1.2 Why did you choose that/those basis/bases?

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A2.1.3 How significant are your measure/s of the improvement/s?

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A3 What is the difference of the solution/s from existing ones?

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A3.1 How is it different from previous and existing ones?

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A4 What are the assumptions made (that are behind for your proposed solution to work)?

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A4.1 Will your proposed solution/s be sensitive to these assumptions?

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A4.2 Can your proposed solution/s be applied to more general cases when some of the assumptions are eliminated? If so, how?

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A5 What is the necessity of your approach / proposed solution/s?

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris.

Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

A5.1 What will be the limits of applicability of your proposed solution/s?

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

A5.2 What will be the message of the proposed solution to technical people? How about to non-technical managers and business men?

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

A6 How will you know if your proposed solution/s is/are correct?

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla

tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

A6.1 Will your results warrant the level of mathematics used (i.e., will the end justify the means)?

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

A7 Is/are there an/_ alternative way/s to get to the same solution/s?

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

A7.1 Can you come up with illustrating examples, or even better, counter examples to your proposed solution/s?

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor.

Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

A7.2 Is there an approximation that can arrive at the essentially the same proposed solution/s more easily?

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

A8 If you were the examiner of your proposal, how would you present the proposal in another way?

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

A8.1 What are the weaknesses of your proposal?

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor.

Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

Appendix B
USAGE EXAMPLES

The user is expected to have a working knowledge of LaTeX. A good introduction is in [Oetiker et al., 2014]. Its latest version can be accessed at http://www.ctan.org/tex-archive/info/lshort.

B1 Equations

The following examples show how to typeset equations in LaTeX. This section also shows examples of the use of `\gls{ }` commands in conjunction with the items that are in the `notation.tex` file. **Please make sure that the entries in `notation.tex` are those that are referenced in the LaTeX document files used by this Thesis. Please comment out unused notations and be careful with the commas and brackets in `notation.tex` .**

In (B.1), the output signal $y\left(t\right)$ is the result of the convolution of the input signal $x\left(t\right)$ and the impulse response $h\left(t\right)$.

$$y\left(t\right)=h\left(t\right)*x\left(t\right)=\int_{-\infty}^{+\infty}h\left(t-\tau\right)x\left(\tau\right)\mathrm{d}\tau \tag{B.1}$$

Other example equations are as follows.

$$\begin{bmatrix}\frac{V_1}{I_1}\end{bmatrix}=\begin{bmatrix}A & B\\ C & D\end{bmatrix}\begin{bmatrix}\frac{V_2}{I_2}\end{bmatrix} \tag{B.2}$$

$$\frac{1}{2}<\left|\mathrm{mod}\left(\left\lfloor\frac{y}{17}\right\rfloor 2^{-17\lfloor x\rfloor-\mathrm{mod}(\lfloor y\rfloor,17)},2\right)\right|, \tag{B.3}$$

$$|\zeta(x)^3\zeta(x+iy)^4\zeta(x+2iy)|=\exp\sum_{n,p}\frac{3+4\cos(ny\log p)+\cos(2ny\log p)}{np^{nx}}\geq 1 \tag{B.4}$$

The verbatim LaTeX code of Sec. B1 is in List. B.1.

Listing B.1: Sample LaTeX code for equations and notations usage

```
The following examples show how to typeset equations in \LaTeX.

In~\eqref{eq:conv}, the output signal \gls{not:output_sigt} is the
    result of the convolution of the input signal \gls{not:input_sigt}
    and the impulse response \gls{not:ir}.

\begin{eqnarray}
     y\left( t \right) = h\left( t \right) * x\left( t \right)=\int_{-\
         infty}^{+\infty}h\left( t-\tau \right)x\left( \tau \right) \
         mathrm{d}\tau
   \label{eq:conv}
\end{eqnarray}

Other example equations are as follows.

\begin{eqnarray}
   \left[ \dfrac{ V_{1} }{ I_{1} } \right] =
   \begin{bmatrix}
      A & B \\
      C & D
   \end{bmatrix}
   \left[ \dfrac{ V_{2} }{ I_{2} } \right]
   \label{eq:ABCD}
\end{eqnarray}

\begin{eqnarray}
{1\over 2} < \left\lfloor \mathrm{mod}\left(\left\lfloor {y \over 17} \
    right\rfloor 2^{-17 \lfloor x \rfloor - \mathrm{mod}(\lfloor y\
    rfloor, 17)},2\right)\right\rfloor,
\end{eqnarray}

\begin{eqnarray}
| \zeta(x)^3\zeta(x+iy)^4\zeta(x+2iy) | =
\exp\sum_{n,p}\frac{3+4\cos(ny\log p) +\cos (2ny\log p)}{np^{nx}}\ge 1
\end{eqnarray}
```

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B2 Notations

In order to use the standardized notation, the user is highly suggested to see the ISO 80000-2 standard [ISO, 2009]. The following were taken from `isomath-test.tex` .

Math alphabets

If there are other symbols in place of Greek letters in a math alphabet, it uses T1 or OT1 font encoding instead of OML.

mathnormal	$A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, \alpha, \beta, \pi, \nu, \omega, v, w, 0, 1, 9$
mathit	$A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, ff, fi, ß, \circ, !, v, w, 0, 1, 9$
mathrm	$\mathrm{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, ff, fi, ß, \circ, !, v, w, 0, 1, 9}$
mathbf	$\mathbf{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, ff, fi, ß, \circ, !, v, w, 0, 1, 9}$
mathsf	$\mathsf{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, ff, fi, ß, \circ, !, v, w, 0, 1, 9}$
mathtt	$\mathtt{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, \uparrow, \downarrow, ß, \circ, !, v, w, 0, 1, 9}$

New alphabets bold-italic, sans-serif-italic, and sans-serif-bold-italic.

mathbfit	$\boldsymbol{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, \alpha, \beta, \pi, \nu, \omega, v, w, 0, 1, 9}$
mathsfit	$\mathit{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, \alpha, \beta, \pi, \nu, \omega, v, w, 0, 1, 9}$
mathsfbfit	$\boldsymbol{\mathit{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, \alpha, \beta, \pi, \nu, \omega, v, w, 0, 1, 9}}$

Do the math alphabets match?
$ax\alpha\omega\boldsymbol{ax\alpha\omega}\mathsf{ax\alpha\omega}\boldsymbol{\mathsf{ax\alpha\omega}}$ $TC\Theta\Gamma\boldsymbol{TC\Theta\Gamma}\mathsf{TC\Theta\Gamma}\boldsymbol{\mathsf{TC\Theta\Gamma}}TC\Theta\Gamma$

Vector symbols

Alphabetic symbols for vectors are boldface italic, $\boldsymbol{\lambda} = \boldsymbol{e}_1 \cdot \boldsymbol{a}$, while numeric ones (e.g. the zero vector) are bold upright, $\boldsymbol{a} + \mathbf{0} = \boldsymbol{a}$.

Matrix symbols

Symbols for matrices are boldface italic, too:[1] $\boldsymbol{\Lambda} = \boldsymbol{E} \cdot \boldsymbol{A}$.

[1] However, matrix symbols are usually capital letters whereas vectors are small ones. Exceptions are physical quantities like the force vector $\boldsymbol{F}$ or the electrical field $\boldsymbol{E}$.

Tensor symbols

Symbols for tensors are sans-serif bold italic,

$$\boldsymbol{\alpha} = \boldsymbol{e} \cdot \boldsymbol{a} \quad \Longleftrightarrow \quad \alpha_{ijl} = e_{ijk} \cdot a_{kl}.$$

The permittivity tensor describes the coupling of electric field and displacement:

$$\boldsymbol{D} = \epsilon_0 \boldsymbol{\epsilon}_\mathrm{r} \boldsymbol{E}$$

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Bold math version

The "bold" math version is selected with the commands `\boldmath` or `\mathversion{bold}`

mathnormal	$A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, \alpha, \beta, \pi, \nu, \omega, v, w, 0, 1, 9$
mathit	$A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, ff, fi, ß, \circ, !, v, w, 0, 1, 9$
mathrm	$\mathrm{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, ff, fi, ß, \circ, !, v, w, 0, 1, 9}$
mathbf	$\mathbf{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, ff, fi, ß, \circ, !, v, w, 0, 1, 9}$
mathsf	$\mathsf{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, ff, fi, ß, \circ, !, v, w, 0, 1, 9}$
mathtt	$\mathtt{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, \uparrow, \downarrow, ß, \circ, !, v, w, 0, 1, 9}$

New alphabets bold-italic, sans-serif-italic, and sans-serif-bold-italic.

mathbfit	$\boldsymbol{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, \alpha, \beta, \pi, \nu, \omega, v, w, 0, 1, 9}$
mathsfit	$\mathsfit{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, \alpha, \beta, \pi, \nu, \omega, v, w, 0, 1, 9}$
mathsfbfit	$\mathsfbfit{A, B, \Gamma, \Delta, \Theta, \Lambda, \Xi, \Pi, \Sigma, \Phi, \Psi, \Omega, \alpha, \beta, \pi, \nu, \omega, v, w, 0, 1, 9}$

Do the math alphabets match?

$ax\alpha\omega ax\alpha\omega ax\alpha\omega \quad TC\Theta\Gamma TC\Theta\Gamma TC\Theta\Gamma$

Vector symbols

Alphabetic symbols for vectors are boldface italic, $\boldsymbol{\lambda = e_1 \cdot a}$, while numeric ones (e.g. the zero vector) are bold upright, $\boldsymbol{a + 0 = a}$.

Matrix symbols

Symbols for matrices are boldface italic, too:[2] $\boldsymbol{\Lambda = E \cdot A}$.

Tensor symbols

Symbols for tensors are sans-serif bold italic,

$$\boldsymbol{\alpha = e \cdot a} \quad \Longleftrightarrow \quad \boldsymbol{\alpha_{ijl} = e_{ijk} \cdot a_{kl}}.$$

The permittivity tensor describes the coupling of electric field and displacement:

$$\boldsymbol{D = \epsilon_0 \epsilon_r E}$$

[2] However, matrix symbols are usually capital letters whereas vectors are small ones. Exceptions are physical quantities like the force vector $\boldsymbol{F}$ or the electrical field $\boldsymbol{E}$.

The verbatim LaTeX code of Sec. B2 is in List. B.2.

Listing B.2: Sample LaTeX code for notations usage

```
% A teststring with Latin and Greek letters::
\newcommand{\teststring}{%
% capital Latin letters
% A,B,C,
A,B,
% capital Greek letters
%\Gamma,\Delta,\Theta,\Lambda,\Xi,\Pi,\Sigma,\Upsilon,\Phi,\Psi,
\Gamma,\Delta,\Theta,\Lambda,\Xi,\Pi,\Sigma,\Phi,\Psi,\Omega,
% small Greek letters
\alpha,\beta,\pi,\nu,\omega,
% small Latin letters:
% compare \nu, \omega, v, and w
v,w,
% digits
0,1,9
}


\subsection*{Math alphabets}

If there are other symbols in place of Greek letters in a math
alphabet, it uses T1 or OT1 font encoding instead of OML.

\begin{eqnarray*}
\mbox{mathnormal} &  & \teststring \\
\mbox{mathit} &  & \mathit{\teststring}\\
\mbox{mathrm} &  & \mathrm{\teststring}\\
\mbox{mathbf} &  & \mathbf{\teststring}\\
\mbox{mathsf} &  & \mathsf{\teststring}\\
\mbox{mathtt} &  & \mathtt{\teststring}
\end{eqnarray*}
 New alphabets bold-italic, sans-serif-italic, and sans-serif-bold-
    italic.
\begin{eqnarray*}
\mbox{mathbfit}     &  & \mathbfit{\teststring}\\
\mbox{mathsfit}     &  & \mathsfit{\teststring}\\
\mbox{mathsfbfit} &  & \mathsfbfit{\teststring}
\end{eqnarray*}
%
Do the math alphabets match?

$
\mathnormal  {a x \alpha \omega}
\mathbfit    {a x \alpha \omega}
\mathsfbfit{a x \alpha \omega}
\quad
\mathsfbfit{T C \Theta \Gamma}
\mathbfit    {T C \Theta \Gamma}
\mathnormal  {T C \Theta \Gamma}
$

\subsection*{Vector symbols}
```

```
Alphabetic symbols for vectors are boldface italic,
$\vec{\lambda}=\vec{e}_{1}\cdot\vec{a}$,
while numeric ones (e.g. the zero vector) are bold upright,
$\vec{a} + \vec{0} = \vec{a}$.

\subsection*{Matrix symbols}

Symbols for matrices are boldface italic, too:%
\footnote{However, matrix symbols are usually capital letters whereas
    vectors
are small ones. Exceptions are physical quantities like the force
vector $\vec{F}$ or the electrical field $\vec{E}$.%
}
$\matrixsym{\Lambda}=\matrixsym{E}\cdot\matrixsym{A}.$


\subsection*{Tensor symbols}

Symbols for tensors are sans-serif bold italic,

\[
   \tensorsym{\alpha}  =  \tensorsym{e}\cdot\tensorsym{a}
   \quad \Longleftrightarrow \quad
   \alpha_{ijl}  =  e_{ijk}\cdot a_{kl}.
\]


The permittivity tensor describes the coupling of electric field and
displacement: \[
\vec{D}=\epsilon_{0}\tensorsym{\epsilon}_{\mathrm{r}}\vec{E}\]



\newpage
\subsection*{Bold math version}

The ``bold'' math version is selected with the commands
\verb+\boldmath+ or \verb+\mathversion{bold}+

{\boldmath
   \begin{eqnarray*}
   \mbox{mathnormal} &  & \teststring \\
   \mbox{mathit} &  & \mathit{\teststring}\\
   \mbox{mathrm} &  & \mathrm{\teststring}\\
   \mbox{mathbf} &  & \mathbf{\teststring}\\
   \mbox{mathsf} &  & \mathsf{\teststring}\\
   \mbox{mathtt} &  & \mathtt{\teststring}
   \end{eqnarray*}
    New alphabets bold-italic, sans-serif-italic, and sans-serif-bold-
        italic.
   \begin{eqnarray*}
   \mbox{mathbfit}     &  & \mathbfit{\teststring}\\
   \mbox{mathsfit}     &  & \mathsfit{\teststring}\\
   \mbox{mathsfbfit} &  & \mathsfbfit{\teststring}
   \end{eqnarray*}
   %
   Do the math alphabets match?
```

```
    $
    \mathnormal  {a x \alpha \omega}
    \mathbfit    {a x \alpha \omega}
    \mathsfbfit{a x \alpha \omega}
    \quad
    \mathsfbfit{T C \Theta \Gamma}
    \mathbfit    {T C \Theta \Gamma}
    \mathnormal  {T C \Theta \Gamma}
    $

    \subsection*{Vector symbols}

    Alphabetic symbols for vectors are boldface italic,
    $\vec{\lambda}=\vec{e}_{1}\cdot\vec{a}$,
    while numeric ones (e.g. the zero vector) are bold upright,
    $\vec{a} + \vec{0} = \vec{a}$.




    \subsection*{Matrix symbols}

    Symbols for matrices are boldface italic, too:%
    \footnote{However, matrix symbols are usually capital letters whereas
        vectors
    are small ones. Exceptions are physical quantities like the force
    vector $\vec{F}$ or the electrical field $\vec{E}$.%
    }
    $\matrixsym{\Lambda}=\matrixsym{E}\cdot\matrixsym{A}.$


    \subsection*{Tensor symbols}

    Symbols for tensors are sans-serif bold italic,

    \[
        \tensorsym{\alpha}  =  \tensorsym{e}\cdot\tensorsym{a}
        \quad \Longleftrightarrow \quad
        \alpha_{ijl}  =  e_{ijk}\cdot a_{kl}.
    \]

    The permittivity tensor describes the coupling of electric field and
    displacement: \[
    \vec{D}=\epsilon_{0}\tensorsym{\epsilon}_{\mathrm{r}}\vec{E}\]
}
```

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B3 Abbreviation

This section shows examples of the use of LaTeXcommands in conjunction with the items that are in the `abbreviation.tex` and in the `glossary.tex` files. Please see List. B.3. **To lessen the LaTeX compilation time, it is suggested that you use `\acr{ }` only for the first occurrence of the word to be abbreviated.**

Again please see List. B.3. Here is an example of first use: alternating current (ac). Next use: ac. Full: alternating current (ac). Here's an acronym referenced using `\acr` : hyper-text markup language (html). And here it is again: html. If you are used to the `glossaries` package, note the difference in using `\gls` : hyper-text markup language (html). And again (no difference): hyper-text markup language (html). Here are some more entries:

- extensible markup language (xml) and cascading style sheet (css).
- Next use: xml and css.
- Full form: extensible markup language (xml) and cascading style sheet (css).
- Reset again.
- Start with a capital. Hyper-text markup language (html).
- Next: Html. Full: Hyper-text markup language (html).
- Prefer capitals? Extensible markup language (XML). Next: XML. Full: extensible markup language (XML).
- Prefer small-caps? Cascading style sheet (CSS). Next: CSS. Full: cascading style sheet (CSS).
- Resetting all acronyms.
- Here are the acronyms again:
- Hyper-text markup language (HTML), extensible markup language (XML) and cascading style sheet (CSS).
- Next use: HTML, XML and CSS.
- Full form: Hyper-text markup language (HTML), extensible markup language (XML) and cascading style sheet (CSS).

- Provide your own link text: style sheet.

The verbatim LaTeX code of Sec. B3 is in List. B.3.

Listing B.3: Sample LaTeX code for abbreviations usage

```
Again please see List.~\ref{lst:abbrv}. Here is an example of first use:
    \acr{ac}. Next use: \acr{ac}. Full: \gls{ac}.  Here's an acronym
   referenced using \verb| \acr |: \acr{html}.  And here it is again: \
   acr{html}. If you are used to the \texttt{glossaries} package, note
   the difference in using \verb| \gls |: \gls{html}. And again (no
   difference): \gls{html}. Here are some more entries:

\begin{itemize}

   \item \acr{xml} and \acr{css}.

   \item Next use: \acr{xml} and \acr{css}.

   \item Full form: \gls{xml} and \gls{css}.

   \item Reset again. \glsresetall{abbreviation}

   \item Start with a capital. \Acr{html}.

   \item Next: \Acr{html}. Full: \Gls{html}.

   \item Prefer capitals? \renewcommand{\acronymfont}[1]{\
      MakeTextUppercase{#1}} \Acr{xml}. Next: \acr{xml}. Full: \gls{xml
      }.

   \item Prefer small-caps? \renewcommand{\acronymfont}[1]{\textsc{#1}}
      \Acr{css}. Next: \acr{css}. Full: \gls{css}.

   \item Resetting all acronyms.\glsresetall{abbreviation}

   \item Here are the acronyms again:

   \item \Acr{html}, \acr{xml} and \acr{css}.

   \item Next use: \Acr{html}, \acr{xml} and \acr{css}.

   \item Full form: \Gls{html}, \gls{xml} and \gls{css}.

   \item Provide your own link text: \glslink{[textbf]css}{style}

\end{itemize}
```

B4 Glossary

This section shows examples of the use of `\gls{ }` commands in conjunction with the items that are in the `glossary.tex` and `notation.tex` files. Note that entries in `notation.tex` are prefixed with "`not:`" label (see List. B.4).

Please make sure that the entries in `notation.tex` are those that are referenced in the LaTeX document files used by this Thesis. Please comment out unused notations and be careful with the commas and brackets in `notation.tex` .

- Matrices are usually denoted by a bold capital letter, such as $\boldsymbol{A}$. The matrix's (i, j)th element is usually denoted a_{ij}. Matrix $\mathbf{I}$ is the identity matrix.
- A set, denoted as $\mathcal{S}$, is a collection of objects.
- The universal set, denoted as $\mathcal{U}$, is the set of everything.
- The empty set, denoted as $\emptyset$, contains no elements.
- The cardinality of a set, denoted as $|\mathcal{S}|$, is the number of elements in the set.

The verbatim LaTeX code for the part of Sec. B4 is in List. B.4.

Listing B.4: Sample LaTeX code for glossary and notations usage

```
\begin{itemize}

   \item \Glspl{matrix} are usually denoted by a bold capital letter,
       such as $\mathbfit{A}$. The \gls{matrix}'s $(i,j)$th element is
       usually denoted $a_{ij}$. \Gls{matrix} $\mathbf{I}$ is the
       identity \gls{matrix}.

   \item A set, denoted as \gls{not:set}, is a collection of objects.

   \item The universal set,  denoted as \gls{not:universalSet}, is the
       set of everything.

   \item The empty set, denoted as \gls{not:emptySet}, contains no
       elements.

   \item The cardinality of a set, denoted as \gls{not:cardinality}, is
       the number of elements in the set.

\end{enumerate}
```

B5 Figure

This section shows several ways of placing figures. PDFLaTeX compatible files are PDF, PNG, and JPG. Please see the `figure` subdirectory.

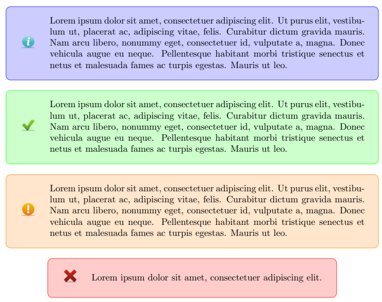


Fig. B.1 A quadrilateral image example.

Fig. B.1 is a gray box enclosed by a dark border. List. B.5 shows the corresponding LaTeX code.

Listing B.5: Sample LaTeX code for a single figure

```
\begin{figure}[!htbp]
   \centering
      \includegraphics[width=0.5\textwidth]{example}
   \caption{A quadrilateral image example.}
   \label{fig:example}
\end{figure}
\cleardoublepage

Fig.~\ref{fig:example} is a gray box enclosed by a dark border. List.~\
    ref{lst:onefig} shows the corresponding \LaTeX \ code.
\end{figure}
```

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetuer id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo.

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetuer id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo.

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetuer id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo.

Lorem ipsum dolor sit amet, consectetuer adipiscing elit.

(a) A sub-figure in the top row.

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetuer id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo.

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetuer id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo.

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetuer id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo.

Lorem ipsum dolor sit amet, consectetuer adipiscing elit.

(b) A sub-figure in the middle row.

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetuer id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo.

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetuer id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo.

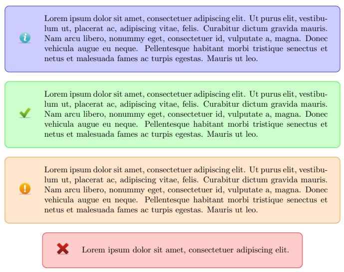
Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Ut purus elit, vestibulum ut, placerat ac, adipiscing vitae, felis. Curabitur dictum gravida mauris. Nam arcu libero, nonummy eget, consectetuer id, vulputate a, magna. Donec vehicula augue eu neque. Pellentesque habitant morbi tristique senectus et netus et malesuada fames ac turpis egestas. Mauris ut leo.

Lorem ipsum dolor sit amet, consectetuer adipiscing elit.

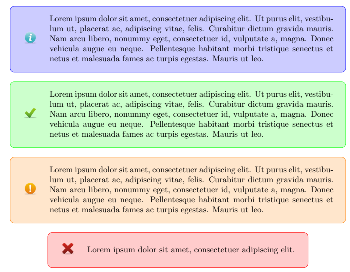
(c) A sub-figure in the bottom row.

Listing B.6: Sample LaTeX code for three figures on top of each other

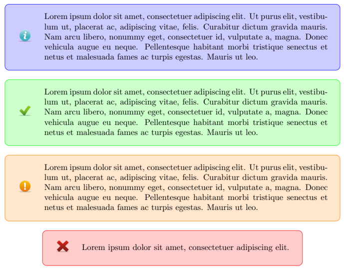
```
\begin{figure}[!htbp]
\centering
\subbottom[A sub-figure in the top row.]{
\includegraphics[width=0.35\textwidth]{example}
\label{fig:top}
}
\vfill
\subbottom[A sub-figure in the middle row.]{
\includegraphics[width=0.35\textwidth]{example}
\label{fig:mid}
}
\vfill
\subbottom[A sub-figure in the bottom row.]{
\includegraphics[width=0.35\textwidth]{example}
\label{fig:botm}
}
\caption{Figures on top of each other}
\label{fig:tmb}
\end{figure}
```



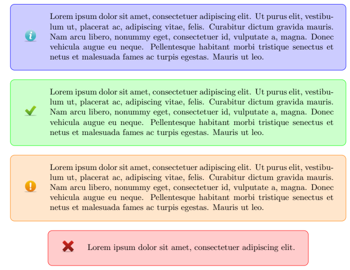
(a) A sub-figure in the upper-left corner.



(b) A sub-figure in the upper-right corner.



(c) A sub-figure in the lower-left corner.



(d) A sub-figure in the lower-right corner

Fig. B.3 Four figures in each corner. See List. B.7 for the corresponding LaTeX code.

Listing B.7: Sample LaTeX code for the four figures

```
\begin{figure}[!htbp]
\centering
\subbottom[A sub-figure in the upper-left corner.]{
\includegraphics[width=0.45\textwidth]{example}
\label{fig:upprleft}
}
\hfill
\subbottom[A sub-figure in the upper-right corner.]{
\includegraphics[width=0.45\textwidth]{example}
\label{fig:uppright}
}
\vfill
\subbottom[A sub-figure in the lower-left corner.]{
\includegraphics[width=0.45\textwidth]{example}
\label{fig:lowerleft}
}
\hfill
\subbottom[A sub-figure in the lower-right corner]{
\includegraphics[width=0.45\textwidth]{example}
\label{fig:lowright}
}
\caption{Four figures in each corner. See List.~\ref{lst:fourfigs} for
    the corresponding \LaTeX \ code.}
\label{fig:fourfig}
\end{figure}
```

B6 Table

This section shows an example of placing a table (a long one). Table B.1 are the triples.

TABLE B.1 FEASIBLE TRIPLES FOR HIGHLY VARIABLE GRID

Time (s)	Triple chosen	Other feasible triples
0	(1, 11, 13725)	(1, 12, 10980), (1, 13, 8235), (2, 2, 0), (3, 1, 0)
2745	(1, 12, 10980)	(1, 13, 8235), (2, 2, 0), (2, 3, 0), (3, 1, 0)
5490	(1, 12, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
8235	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
10980	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
13725	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
16470	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
19215	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
21960	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
24705	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
27450	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
30195	(2, 2, 2745)	(2, 3, 0), (3, 1, 0)
32940	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
35685	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
38430	(1, 13, 10980)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
41175	(1, 12, 13725)	(1, 13, 10980), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
43920	(1, 13, 10980)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
46665	(2, 2, 2745)	(2, 3, 0), (3, 1, 0)
49410	(2, 2, 2745)	(2, 3, 0), (3, 1, 0)
52155	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
54900	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
57645	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
60390	(1, 12, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
63135	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
65880	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
68625	(2, 2, 2745)	(2, 3, 0), (3, 1, 0)
71370	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
74115	(1, 12, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
76860	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
79605	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
82350	(1, 12, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
85095	(1, 12, 13725)	(1, 13, 10980), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
87840	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
90585	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
93330	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
96075	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
98820	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
101565	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
104310	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
107055	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
109800	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
112545	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
115290	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
118035	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
120780	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
123525	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)

Continued on next page

Continued from previous page

Time (s)	Triple chosen	Other feasible triples
126270	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
129015	(2, 2, 2745)	(2, 3, 0), (3, 1, 0)
131760	(2, 2, 2745)	(2, 3, 0), (3, 1, 0)
134505	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
137250	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
139995	(2, 2, 2745)	(2, 3, 0), (3, 1, 0)
142740	(2, 2, 2745)	(2, 3, 0), (3, 1, 0)
145485	(1, 12, 16470)	(1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0)
148230	(2, 2, 2745)	(2, 3, 0), (3, 1, 0)
150975	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
153720	(1, 12, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
156465	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
159210	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
161955	(1, 13, 16470)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)
164700	(1, 13, 13725)	(2, 2, 2745), (2, 3, 0), (3, 1, 0)

List. B.8 shows the corresponding LaTeX code.

Listing B.8: Sample LaTeX code for making typical table environment

```
\begin{center}
{\scriptsize
\begin{tabularx}{\textwidth}{p{0.1\textwidth}|p{0.2\textwidth}|p{0.5\textwidth}}
\caption{Feasible triples for highly variable grid} \label{tab:triple_grid} \\
\hline
\hline
\textbf{Time (s)} &
\textbf{Triple chosen} &
\textbf{Other feasible triples} \\
\hline
\endfirsthead
\multicolumn{3}{c}%
{\textit{Continued from previous page}} \\
\hline
\hline
\textbf{Time (s)} &
\textbf{Triple chosen} &
\textbf{Other feasible triples} \\
\hline
\endhead
\hline
\multicolumn{3}{r}{\textit{Continued on next page}} \\
\endfoot
\hline
\endlastfoot
\hline

0 & (1, 11, 13725) & (1, 12, 10980), (1, 13, 8235), (2, 2, 0), (3, 1, 0) \\
2745 & (1, 12, 10980) & (1, 13, 8235), (2, 2, 0), (2, 3, 0), (3, 1, 0) \\
5490 & (1, 12, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
8235 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
10980 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
13725 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
16470 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
19215 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
21960 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
24705 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
27450 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
30195 & (2, 2, 2745) & (2, 3, 0), (3, 1, 0) \\
32940 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
35685 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
38430 & (1, 13, 10980) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
```

```
43 41175 & (1, 12, 13725) & (1, 13, 10980), (2, 2, 2745), (2, 3, 0), (3, 1,
       0) \\
44 43920 & (1, 13, 10980) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
45 46665 & (2, 2, 2745) & (2, 3, 0), (3, 1, 0) \\
46 49410 & (2, 2, 2745) & (2, 3, 0), (3, 1, 0) \\
47 52155 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3, 1,
       0) \\
48 54900 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
49 57645 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
50 60390 & (1, 12, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
51 63135 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
52 65880 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
53 68625 & (2, 2, 2745) & (2, 3, 0), (3, 1, 0) \\
54 71370 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
55 74115 & (1, 12, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
56 76860 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
57 79605 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
58 82350 & (1, 12, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
59 85095 & (1, 12, 13725) & (1, 13, 10980), (2, 2, 2745), (2, 3, 0), (3, 1,
       0) \\
60 87840 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
61 90585 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
62 93330 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
63 96075 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
64 98820 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
65 101565 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
66 104310 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
67 107055 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
68 109800 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
69 112545 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3,
       1, 0) \\
70 115290 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
71 118035 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
72 120780 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
73 123525 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
74 126270 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3,
       1, 0) \\
75 129015 & (2, 2, 2745) & (2, 3, 0), (3, 1, 0) \\
76 131760 & (2, 2, 2745) & (2, 3, 0), (3, 1, 0) \\
77 134505 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
78 137250 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
79 139995 & (2, 2, 2745) & (2, 3, 0), (3, 1, 0) \\
80 142740 & (2, 2, 2745) & (2, 3, 0), (3, 1, 0) \\
81 145485 & (1, 12, 16470) & (1, 13, 13725), (2, 2, 2745), (2, 3, 0), (3,
       1, 0) \\
82 148230 & (2, 2, 2745) & (2, 3, 0), (3, 1, 0) \\
83 150975 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
84 153720 & (1, 12, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
85 156465 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
86 159210 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
87 161955 & (1, 13, 16470) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
88 164700 & (1, 13, 13725) & (2, 2, 2745), (2, 3, 0), (3, 1, 0) \\
89 \end{tabularx}
90 }
91 \end{center}
```

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B7 Algorithm or Pseudocode Listing

Table B.2 shows an example pseudocode. Note that if the pseudocode exceeds one page, it can mean that its implementation is not modular. List. B.9 shows the corresponding LaTeX code.

TABLE B.2 CALCULATION OF $y = x^n$

Input(s):		
n	:	nth power; $n \in \mathbb{Z}^+$
x	:	base value; $x \in \mathbb{R}^+$
Output(s):		
y	:	result; $y \in \mathbb{R}^+$

Require: $n \geq 0 \vee x \neq 0$
Ensure: $y = x^n$
1: $y \Leftarrow 1$
2: **if** $n < 0$ **then**
3: $X \Leftarrow 1/x$
4: $N \Leftarrow -n$
5: **else**
6: $X \Leftarrow x$
7: $N \Leftarrow n$
8: **end if**
9: **while** $N \neq 0$ **do**
10: **if** N is even **then**
11: $X \Leftarrow X \times X$
12: $N \Leftarrow N/2$
13: **else** $\{N$ is odd$\}$
14: $y \Leftarrow y \times X$
15: $N \Leftarrow N - 1$
16: **end if**
17: **end while**

Listing B.9: Sample LaTeX code for algorithm or pseudocode listing usage

```
\begin{table}[!htbp]
   \caption{Calculation of $y = x^n$}
   \label{tab:calcxn}
   {\footnotesize
   \begin{tabular}{lll}
   \hline
   \hline
   {\bfseries Input(s):} & & \\
   $n$ & : & $n$th power; $n \in \mathbb{Z}^{+}$ \\
   $x$ & : & base value; $x \in \mathbb{R}^{+}$ \\
   \hline
   {\bfseries Output(s):} & & \\
   $y$ & : & result; $y \in \mathbb{R}^{+}$  \\
   \hline
   \hline
   \\
   \end{tabular}
   }
   \begin{algorithmic}[1]
   {\footnotesize
      \REQUIRE $n \geq 0 \vee x \neq 0$
      \ENSURE $y = x^n$
      \STATE $y \Leftarrow 1$
      \IF{$n < 0$}
            \STATE $X \Leftarrow 1 / x$
            \STATE $N \Leftarrow -n$
      \ELSE
            \STATE $X \Leftarrow x$
            \STATE $N \Leftarrow n$
      \ENDIF
      \WHILE{$N \neq 0$}
            \IF{$N$ is even}
                  \STATE $X \Leftarrow X \times X$
                  \STATE $N \Leftarrow N / 2$
            \ELSE[$N$ is odd]
                  \STATE $y \Leftarrow y \times X$
                  \STATE $N \Leftarrow N - 1$
            \ENDIF
      \ENDWHILE
   }
   \end{algorithmic}
\end{table}
```

B8 Program/Code Listing

List. B.10 is a program listing of a C code for computing Fibonacci numbers by calling the actual code. Please see the `code` subdirectory.

Listing B.10: Computing Fibonacci numbers in C (./code/fibo.c)

```
/* fibo.c -- It prints out the first N Fibonacci
 *           numbers.
 */

#include <stdio.h>

int main(void) {
    int n;         /* Number of fibonacci numbers we will print */
    int i;         /* Index of fibonacci number to be printed next */
    int current;   /* Value of the (i)th fibonacci number */
    int next;      /* Value of the (i+1)th fibonacci number */
    int twoaway;   /* Value of the (i+2)th fibonacci number */

    printf("How many Fibonacci numbers do you want to compute? ");
    scanf("%d", &n);
    if (n<=0)
       printf("The number should be positive.\n");
    else {
      printf("\n\n\tI \t Fibonacci(I) \n\t=====================\n");
      next = current = 1;
      for (i=1; i<=n; i++) {
   printf("\t%d \t\t\t%d\n", i, current);
   twoaway = current+next;
   current = next;
   next    = twoaway;
      }
    }
}

/* The output from a run of this program was:

How many Fibonacci numbers do you want to compute? 9

   I   Fibonacci(I)
   =====================
   1      1
   2      1
   3      2
   4      3
   5      5
   6      8
   7      13
   8      21
   9      34

*/
```

List. B.11 shows the corresponding LaTeX code.

Listing B.11: Sample LaTeX code for program listing

```
List.~\ref{lst:fib_c} is a program listing of a C code for computing
    Fibonacci numbers by calling the actual code. Please see the \verb|
    code | subdirectory.
```

B9 Referencing

Referencing chapters: This appendix is in Appendix B, which is about examples in using various LaTeX commands.

Referencing sections: This section is Sec. B9, which shows how to refer to the locations of various labels that have been placed in the LaTeX files. List. B.12 shows the corresponding LaTeX code.

Listing B.12: Sample LaTeX code for referencing sections

```
Referencing sections: This section is Sec.~\ref{sec:ref}, which shows
    how to refer to the locations of various labels that have been
    placed in the \LaTeX \ files. List.~\ref{lst:refsec} shows the
    corresponding \LaTeX \ code.
```

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

B9.1 A subsection

Referencing subsections: This section is Sec. B9.1, which shows how to refer to a subsection. List. B.13 shows the corresponding LaTeX code.

Listing B.13: Sample LaTeX code for referencing subsections

```
Referencing subsections: This section is Sec.~\ref{sec:subsec}, which
    shows how to refer to a subsection. List.~\ref{lst:refsub} shows the
     corresponding \LaTeX \ code.
```

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

B9.1.1 A sub-subsection

Referencing sub-subsections: This section is Sec. B9.1.1, which shows how to refer to a sub-subsection. List. B.14 shows the corresponding LaTeX code.

Listing B.14: Sample LaTeX code for referencing sub-subsections

```
Referencing sub-subsections: This section is Sec.~\ref{sec:subsubsec},
    which shows how to refer to a sub-subsection. List.~\ref{lst:
    refsubsub} shows the corresponding \LaTeX \ code.
```

Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Etiam lobortis facilisis sem. Nullam nec mi et neque pharetra sollicitudin. Praesent imperdiet mi nec ante. Donec ullamcorper, felis non sodales commodo, lectus velit ultrices augue, a dignissim nibh lectus placerat pede. Vivamus nunc nunc, molestie ut, ultricies vel, semper in, velit. Ut porttitor. Praesent in sapien. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. Duis fringilla tristique neque. Sed interdum libero ut metus. Pellentesque placerat. Nam rutrum augue a leo. Morbi sed elit sit amet ante lobortis sollicitudin. Praesent blandit blandit mauris. Praesent lectus tellus, aliquet aliquam, luctus a, egestas a, turpis. Mauris lacinia lorem sit amet ipsum. Nunc quis urna dictum turpis accumsan semper.

B10 Index

For key words or topics that are expected (or the user would like) to appear in the Index, use `index{key}` , where `key` is an example keyword to appear in the Index. For example, Fredholm integral and Fourier operator of the following paragraph are in the Index.

If we make a very large matrix with complex exponentials in the rows (i.e., cosine real parts and sine imaginary parts), and increase the resolution without bound, we approach the kernel of the Fredholm integral equation of the 2nd kind, namely the Fourier operator that defines the continuous Fourier transform.

List. B.15 is a program listing of the above-mentioned paragraph.

Listing B.15: Sample LaTeX code for Index usage

```
If we make a very large matrix with complex exponentials in the rows (i.
    e., cosine real parts and sine imaginary parts), and increase the
    resolution without bound, we approach the kernel of the \index{
    Fredholm integral} Fredholm integral equation of the 2nd kind,
    namely the \index{Fourier} Fourier operator that defines the
    continuous Fourier transform.
```

B11 Adding Relevant PDF Pages (e.g. Standards, Datasheets, Specification Sheets, Application Notes, etc.)

Selected PDF pages can be added (see List. B.16), but note that the options must be tweaked. See the manual of `pdfpages` for other options.

Listing B.16: Sample LaTeX code for including PDF pages

```
\includepdf[pages={8-10},%
offset=3.5mm -10mm,%
scale=0.73,%
frame]
{./reference/Xilinx2015-UltraScaleArchitectureOverview.pdf}
```

Virtex UltraScale FPGA Feature Summary

Table 6: **Virtex UltraScale FPGA Feature Summary**

	VU065	VU080	VU095	VU125	VU160	VU190	VU440
Logic Cells	626,640	780,000	940,800	1,253,280	1,621,200	1,879,920	4,432,680
CLB Flip-Flops	716,160	891,424	1,075,200	1,432,320	1,852,800	2,148,480	5,065,920
CLB LUTs	358,080	445,712	537,600	716,160	926,400	1,074,240	2,532,960
Maximum Distributed RAM (Mb)	4.8	3.9	4.8	9.7	12.7	14.5	28.7
Block RAM/FIFO w/ECC (36Kb each)	1,260	1,421	1,728	2,520	3,276	3,780	2,520
Total Block RAM (Mb)	44.3	50.0	60.8	88.6	115.2	132.9	88.6
CMT (1 MMCM, 2 PLLs)	10	16	16	20	30	30	30
I/O DLLs	40	64	64	80	120	120	120
Fractional PLLs	5	8	8	10	15	15	0
Maximum HP I/Os(1)	468	780	780	780	650	650	1,404
Maximum HR I/Os(2)	52	52	52	104	52	52	52
DSP Slices	600	672	768	1,200	1,560	1,800	2,880
System Monitor	1	1	1	2	3	3	3
PCIe Gen3 x8	2	4	4	4	5	6	6
150G Interlaken	3	6	6	6	8	9	0
100G Ethernet	3	4	4	6	9	9	3
GTH 16.3Gb/s Transceivers	20	32	32	40	52	60	48
GTY 30.5Gb/s Transceivers	20	32	32	40	52	60	0

Notes:
1. HP = High-performance I/O with support for I/O voltage from 1.0V to 1.8V.
2. HR = High-range I/O with support for I/O voltage from 1.2V to 3.3V.

Virtex UltraScale Device-Package Combinations and Maximum I/Os

Table 7: **Virtex UltraScale Device-Package Combinations and Maximum I/Os**

Package[1][2][3]	Package Dimensions (mm)	VU065	VU080	VU095	VU125	VU160	VU190	VU440
		HR, HP GTH, GTY	HR, HP GTH, GTY	HR, HP GTH, GTY	HR, HP GTH, GTY	HR, HP GTH, GTY	HR, HP GTH, GTY	HR, HP GTH, GTY
FFVC1517	40x40	52, 468 20, 20	52, 468 20, 20	52, 468 20, 20				
FFVD1517	40x40		52, 286 32, 32	52, 286 32, 32				
FLVD1517	40x40				52, 286 40, 32			
FFVB1760	42.5x42.5		52, 650 32, 16	52, 650 32, 16				
FLVB1760	42.5x42.5				52, 650 36, 16			
FFVA2104	47.5x47.5		52, 780 28, 24	52, 780 28, 24				
FLVA2104	47.5x47.5				52, 780 28, 24			
FFVB2104	47.5x47.5		52, 650 32, 32	52, 650 32, 32				
FLVB2104	47.5x47.5				52, 650 40, 36			
FLGB2104	47.5x47.5					52, 650 40, 36	52, 650 40, 36	
FFVC2104	47.5x47.5			52, 364 32, 32				
FLVC2104	47.5x47.5				52, 364 40, 40			
FLGC2104	47.5x47.5					52, 364 52, 52	52, 364 52, 52	
FLGB2377	50x50							52, 1248 36, 0
FLGA2577	52.5x52.5						0, 448 60, 60	
FLGA2892	55x55							52, 1404 48, 0

Notes:

1. Go to Ordering Information for package designation details.
2. All packages have 1.0mm ball pitch.
3. Packages with the same last letter and number sequence, e.g., A2104, are footprint compatible with all other UltraScale architecture-based devices with the same sequence. The footprint compatible devices within this family are outlined. See the UltraScale Architecture Product Selection Guide for details on inter-family migration.

Virtex UltraScale+ FPGA Feature Summary

Table 8: **Virtex UltraScale+ FPGA Feature Summary**

	VU3P	VU5P	VU7P	VU9P	VU11P	VU13P
Logic Cells	689,640	1,051,010	1,379,280	2,068,920	2,147,040	2,862,720
CLB Flip-Flops	788,160	1,201,154	1,576,320	2,364,480	2,453,760	3,271,680
CLB LUTs	394,080	600,577	788,160	1,182,240	1,226,880	1,635,840
Max. Distributed RAM (Mb)	12.0	18.3	24.1	36.1	34.8	46.4
Block RAM/FIFO w/ECC (36Kb each)	720	1,024	1,440	2,160	2,016	2,688
Block RAM (Mb)	25.3	36.0	50.6	75.9	70.9	94.5
UltraRAM Blocks	320	470	640	960	1,152	1,536
UltraRAM (Mb)	90.0	132.2	180.0	270.0	324.0	432.0
CMTs (1 MMCM and 2 PLLs)	10	20	20	30	12	16
Max. HP I/O(1)	520	832	832	832	624	832
DSP Slices	2,280	3,474	4,560	6,840	8,928	11,904
System Monitor	1	2	2	3	3	4
GTY Transceivers 32.75Gb/s	40	80	80	120	96	128
PCIe Gen3 x16 and Gen4 x8	2	4	4	6	3	4
150G Interlaken	3	4	6	9	9	12
100G Ethernet w/RS-FEC	3	4	6	9	6	8

Notes:
1. HP = High-performance I/O with support for I/O voltage from 1.0V to 1.8V.

Virtex UltraScale+ Device-Package Combinations and Maximum I/Os

Table 9: **Virtex UltraScale+ Device-Package Combinations and Maximum I/Os**

Package (1)(2)(3)	Package Dimensions (mm)	VU3P	VU5P	VU7P	VU9P	VU11P	VU13P
		HP, GTY	HP, GTY	HP, GTY	HP, GTY	HP, GTY	HP, GTY
FFVC1517	40x40	520, 40					
FLVF1924	45x45					624, 64	
FLVA2104	47.5x47.5		832, 52	832, 52	832, 52		
FHVA2104	52.5x52.5(4)						832, 52
FLVB2104	47.5x47.5		702, 76	702, 76	702, 76	624, 76	
FHVB2104	52.5x52.5(4)						702, 76
FLVC2104	47.5x47.5		416, 80	416, 80	416, 104	416, 96	
FHVC2104	52.5x52.5(4)						416, 104
FLVA2577	52.5x52.5				448, 120	448, 96	448, 128

Notes:
1. Go to Ordering Information for package designation details.
2. All packages have 1.0mm ball pitch.
3. Packages with the same last letter and number sequence, e.g., A2104, are footprint compatible with all other UltraScale devices with the same sequence. The footprint compatible devices within this family are outlined.
4. These 52.5x52.5mm overhang packages have the same PCB ball footprint as the corresponding 47.5x47.5mm packages (i.e., the same last letter and number sequence) and are footprint compatible.

Appendix C
PUBLICATION LIST AND AWARD

Journal

1. ...
2. ...

Conference

1. ...
2. ...

De La Salle University

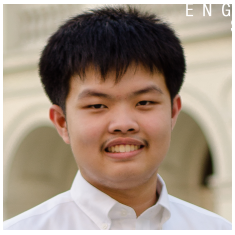
Others

1. ...
2. ...

Award

1. ...
2. ...

Appendix D
VITA

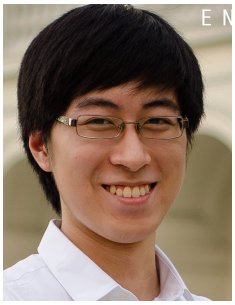


Sean Herbie P. Chua took his primary and secondary education in Grace Christian College. He is currently taking up Bachelor of Science in Computer Engineering in De La Salle University. He has programmed several applications, C programming, Java programming, and Android programming. He also has a background on PIC programming. In his previous courses, he and his teammates have created a wall follower. His interest is creating new innovations and upgrading current technology to simplify some task.

Jerald Steven G. Limqueco is a third year engineering student taking up B.Sc. Computer Engineering at De La Salle University. He has designed and programmed several electronic circuits using Arduino and PIC as microcontrollers in some of his previous projects. He has also programmed several applications using java and C language. His research interests include environmental friendly gadgets, mobile robots that can help the society and agricultural technologies.

De La Salle University

Ervin Lester G. Lu is a third year engineering student taking up B.Sc. Computer Engineering at De La Salle University. He has designed and programmed several applications using C and Java languages, and electronic circuits using Arduino and PIC as microcontrollers in some of his previous projects. His research interests include educational mobile applications, environmental friendly innovations, and agriculture technologies.



Sean Wyndell T. Que is a third year engineering student taking up B.Sc. Computer Engineering at De La Salle University. He has designed and programmed several electronic circuits using PIC microcontrollers and mobile appliations using C and Java languages. His research interests include cool electronic gadgets and awesome mobile appliations.

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