Main Title or Report Id
Title

ITUROBLAB

https://kontrol.itu.edu.tr/en/research/laboratories/robotics-laboratory
https://robotics.itu.edu.tr

https://github.com/ITUROBLAB

Name SURNAME, Second AUTHOR, Third AUTHOR

October 31, 2022

Abstract

In this report, ... Give abstract in a single paragraph (summary of your report including what you did, why you did, what you obtained, the repository link where the details can be found, and superiority of your achievement, if any).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. Cras viverra metus rhoncus sem. Nulla et lectus vestibulum urna fringilla ultrices. Phasellus eu tellus sit amet tortor gravida placerat. Integer sapien est, iaculis in, pretium quis, viverra ac, nunc. Praesent eget sem vel leo ultrices bibendum. Aenean faucibus. Morbi dolor nulla, malesuada eu, pulvinar at, mollis ac, nulla. Curabitur auctor semper nulla. Donec varius orci eget risus. Duis nibh mi, congue eu, accumsan eleifend, sagittis quis, diam. Duis eget orci sit amet orci dignissim rutrum.

Table of Contents

1 Problem Definition

Paper reference (citation) Du et al. [1] ... Adding equation reference (1) ... In line equation mode $\lim_{x \to 3}$ to give equation in a sentence.

$$\dot{x}(t) = \int_0^{\tau} x(t)dt \tag{1}$$

where $\dot{x}(t)$ is velocity of the mass and ...

1.1 Adding sub-section

Multi line equations example:

$$\begin{aligned} x_1 &= 3 + y^2 && (2)\\ &= a^2 \\ &= b^2 && (3) \end{aligned}$$

1.1.1 Adding sub-sub-section

Nulla malesuada porttitor diam. Donec felis erat, congue non, volutpat at, tincidunt tristique, libero. Vivamus viverra fermentum felis. Donec nonummy pellentesque ante. Phasellus adipiscing semper elit. Proin fermentum massa ac quam. Sed diam turpis, molestie vitae, placerat a, molestie nec, leo. Maecenas lacinia. Nam ipsum ligula, eleifend at, accumsan nec, suscipit a, ipsum. Morbi blandit ligula feugiat magna. Nunc eleifend consequat lorem. Sed lacinia nulla vitae enim. Pellentesque tincidunt purus vel magna. Integer non enim. Praesent euismod nunc eu purus. Donec bibendum quam in tellus. Nullam cursus pulvinar lectus. Donec et mi. Nam vulputate metus eu enim. Vestibulum pellentesque felis eu massa.

Table 1: Example table

Title 1	**Title 2**	Title 3
x^2	2	3
4	5	6

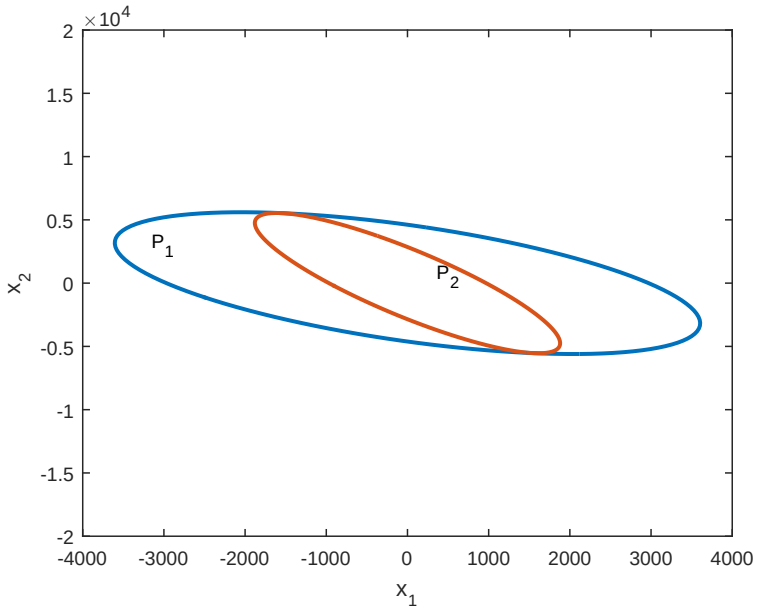

Figure 1: Example figure 1

2 Second Section

The objective function in (4) can be maximized .... If we define $\vec{p}_i \triangleq \left[\vec{p}_i^T, 1\right]^T$ and ..., the compact form of the equation is achieved as

$$\sum_{i=1}^{N_p} \exp\left(-\frac{\|\mathbb{A}\vec{p}_i - \vec{m}_{c_k(i)}\|^2}{2\sigma^2}\right) \tag{4}$$

where $\mathbb{A}$ is the combination of ... Nam dui ligula, fringilla a, euismod sodales, sollicitudin vel, wisi. Morbi auctor lorem non justo. Nam lacus libero, pretium at, lobortis vitae, ultricies et, tellus. Donec aliquet, tortor sed accumsan bibendum, erat ligula aliquet magna, vitae ornare odio metus a mi. Morbi ac orci et nisl hendrerit mollis. Suspendisse ut massa. Cras nec ante. Pellentesque a nulla. Cum sociis natoque penatibus et magnis dis parturient montes, nascetur ridiculus mus. Aliquam tincidunt urna. Nulla ullamcorper vestibulum turpis. Pellentesque cursus luctus mauris.

Giving reference to a table: Table 1 and to figures: Fig. 1 and Fig. 2.

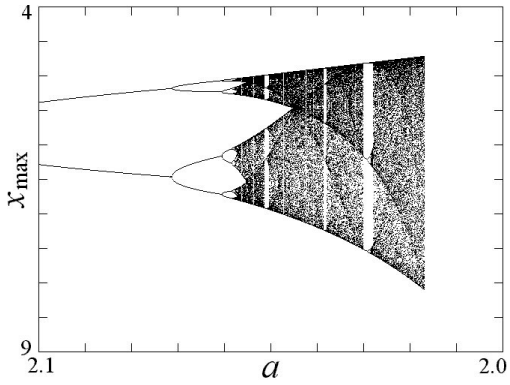

Figure 2: Example figure 2

3 Third Section

The better way of adding a figure is eps files as shown in Fig. 3.

Adding text with bullets

- ITU
- Robotics
- Lab

or using enumeration

1. ITU
2. Robotics
3. Lab

No number equation

$$\sum_{i=1}^{N_p} \mathbf{x}^T \mathbb{P}_i^T C_i \mathbb{P}_i \Delta_i = \sum_{i=1}^{N_p} \pi_i^T C_i \mathbb{P}_i \Delta_i \Rightarrow \mathbf{x}^T \left(\sum_{i=1}^{N_p} \mathbb{P}_i^T C_i \mathbb{P}_i \Delta_i \right) = \sum_{i=1}^{N_p} \pi_i^T C_i \mathbb{P}_i \Delta_i$$

Giving a reference in a sentence [2]. Giving multi-reference once [1, 3–5]. Fusce mauris. Vestibulum luctus nibh at lectus. Sed bibendum, nulla a faucibus semper, leo velit ultricies tellus, ac venenatis arcu wisi vel nisl. Vestibulum diam. Aliquam pellentesque, augue quis sagittis posuere, turpis lacus congue quam, in hendrerit risus eros eget felis. Maecenas eget erat in sapien mattis porttitor. Vestibulum porttitor. Nulla facilisi. Sed a turpis eu lacus commodo facilisis. Morbi fringilla, wisi in dignissim interdum, justo lectus sagittis dui, et vehicula libero dui cursus dui. Mauris tempor ligula sed lacus. Duis cursus enim ut augue. Cras ac magna. Cras nulla. Nulla egestas. Curabitur a leo. Quisque egestas wisi eget nunc. Nam feugiat lacus vel est. Curabitur consectetuer.

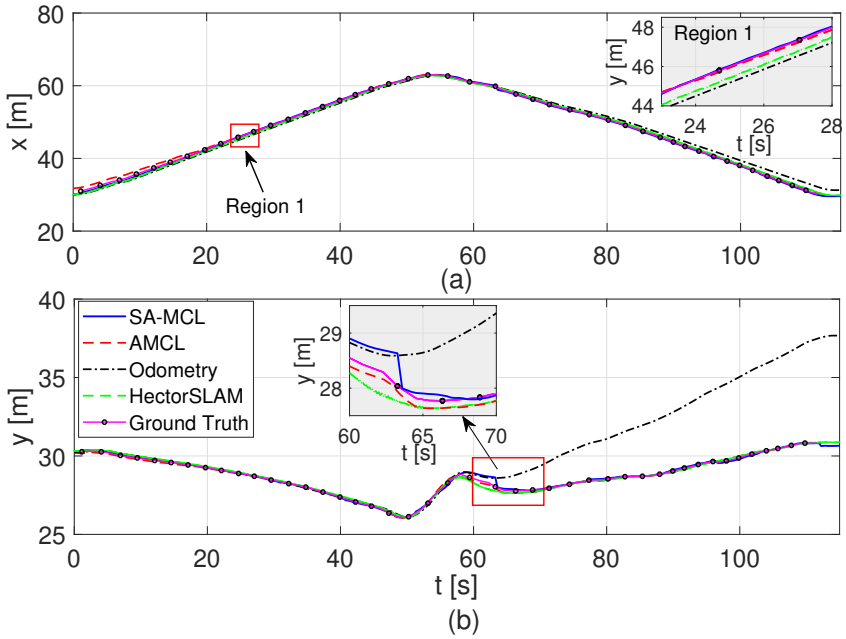

Figure 3: Example figure 3

4 Conclusions

To put in a nut shell, in this report, we find the .... Closed form solution of the problem is shown step by step. Quisque ullamcorper placerat ipsum. Cras nibh. Morbi vel justo vitae lacus tincidunt ultrices. Lorem ipsum dolor sit amet, consectetuer adipiscing elit. In hac habitasse platea dictumst. Integer tempus convallis augue. Etiam facilisis. Nunc elementum fermentum wisi. Aenean placerat. Ut imperdiet, enim sed gravida sollicitudin, felis odio placerat quam, ac pulvinar elit purus eget enim. Nunc vitae tortor. Proin tempus nibh sit amet nisl. Vivamus quis tortor vitae risus porta vehicula.

References

[1] S. Du, N. Zheng, S. Ying, and J. Liu, "Affine iterative closest point algorithm for point set registration," *Pattern Recognition Letters*, vol. 31, no. 9, pp. 791–799, 2010. doi: 10.1016/j.patrec.2010.01.020

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