

Title Presentation

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① Research Contents

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Research Contents of This Project



Figure 1: Research Contents of This Project

Research progress



Figure 2: Research progress

Results

Results

- XXXX
- XXXX
- XXXX
- XXXX
- XXXX
- XXXX

Case 1

Unnumbered equation

Example of unnumbered equation:

$$k : [-\pi, \pi] \rightarrow [0, 1]$$

Case 2

numbered equation

- Example of numbered equation: the input is an image

$$\mathbf{x} \in \mathbb{R}^{C_{\text{in}} \times H \times W} \quad (1)$$

where C_{in} represents number of input channels, H is the height of image, and W is the width of image.

Case 3

Table

Example of tables, shown in 1.

Table 1: Unique elements in train.csv

column	# unique values
posting_id	34250
image	32412
image_phash	28735
title	33117
label_group	11014

Case 4

Parallel figures

Example of parallel figures.



Figure 3: Example figure 1



Figure 4: Example figure 2

Future work

Future work

- XXXX
- XXXX
- XXXX
- XXXX

Scheduling

Scheduling

- XXXX[1]
- XXXX[2]
- XXXX[3]
- XXXX[4]

Bibliography I

- [1] Webster III R J, Jones B A. Design and Kinematic Modeling of Constant Curvature Continuum Robots: A Review[J]. The International Journal of Robotics Research, 2010, 29(13): 1661-1683.
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Bibliography II

- [4] Gravagne I A, Rahn C D, Walker I D. Large Deflection Dynamics and Control for Planar Continuum Robots[J]. IEEE/ASME Transactions on Mechatronics, 2003, 8(2): 299-307.

Thanks for your attention!

Q & A