

# Title Presentation

Student: Jingxuan Yang

Supervisor: Prof. XX

Tsinghua University

May 20, 2022

# Contents

1 Research Contents

2 Results

3 Future Work

# 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  $C_{\text{in}}$  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.
- [2] Jones B A, Walker I D. Kinematics for Multisection Continuum Robots[J]. IEEE Transactions on Robotics, 2006, 22(1): 43-55.
- [3] McMahan W, Jones B A, Walker I D. Design and Implementation of a Multi-section Continuum Robot: Air-Octor[C] // IEEE/RSJ International Conference on Intelligent Robots and Systems, Shanghai, China, 2005: 2578-2585.

## 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