

A Simple Example of a Latex Thesis

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Declaration

This thesis is an account of research undertaken between February 2004 and October 2004 at The Department of Physics, Faculty of Science, The Australian National University, Canberra, Australia.

Except where acknowledged in the customary manner, the material presented in this thesis is, to the best of my knowledge, original and has not been submitted in whole or part for a degree in any university.

Mickey M. Mouse
October, 2004

Acknowledgements

I would like to thank my lucky stars, and the cat, for not eating me.

Abstract

This thesis tells a great story about what I achieved in my research project. The abstract is short, but informative. it makes clear the general area in which I worked, and what I achieved.

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Figures and References

This chapter gives examples of how to reference the literature, and how to include a figure. To use Latex effectively you either need someone you can ask questions of, or a good book. The book I find most useful is Math into Latex.

Here's an example of including a figure. Figures need to have size information in them. The only ones I know how to make work are encapsulated postscript files, or eps files. If your figures are not in eps form you may need to find a graphics program which can convert formats. Notice how I can refer to the figure, Fig. 1.1.

And this sentence includes an example citation [BHSB16]. Although I, Pascal, think that the bibliographystyle still needs some fine-tuning. And we need to check if and how authors can be cited by name. (Only loosely related: some useful packages should be included as well, such as hyperref to get links.)

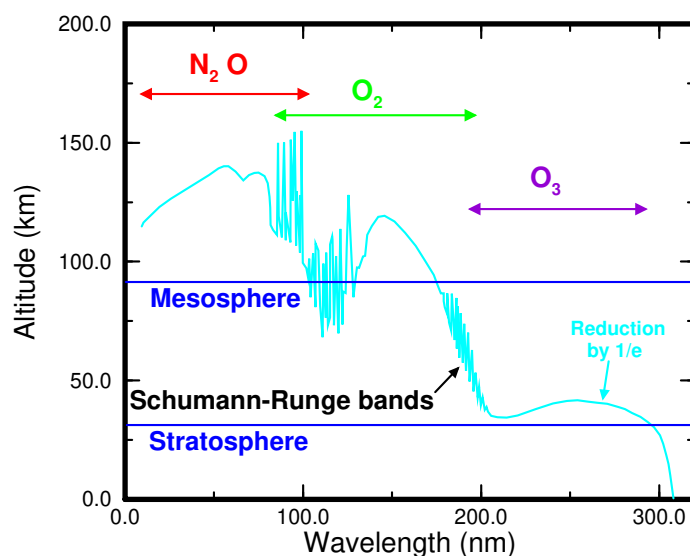


Figure 1.1: This is an example of how to include an eps (encapsulated postscript) figure. Maths is OK in the caption $\epsilon^2 = \Delta$.

How to do Maths

This chapter gives some examples of including maths into your thesis.

An example of a differential equation:

$$\frac{\partial^2 \psi}{\partial t^2} - 2i \frac{mv_\theta}{r} \frac{\partial \psi}{\partial t} - \frac{1}{r} \frac{\partial}{\partial r} \left(r c^2 \frac{\partial \psi}{\partial r} \right) + \frac{m^2}{r^2} (c^2 - v_\theta^2) \psi = 0 . \quad (2.1)$$

Equations can also be inline $\phi(t, r, \theta, z) = \psi(t, r) e^{-im\theta}$, i.e. not displayed separately from the text. I can also refer to equations, Eq. (2.1).

Bibliography

- [BHSB16] Susanne Biundo, Daniel Höller, Bernd Schattenberg, and Pascal Bercher. Companion-technology: An overview. *Künstliche Intelligenz*, 30(1):11–20, 2016. Special Issue on Companion Technologies.