

CZECH TECHNICAL UNIVERSITY IN PRAGUE

FACULTY OF ELECTRICAL ENGINEERING
DEPARTMENT OF CYBERNETICS
MULTI-ROBOT SYSTEMS



My Thesis Title Can Span Multiple Lines

Doctoral Thesis

Ing. John Smith

Prague, January 2021

Ph.D. programme: Electrical Engineering and Information Technology
Branch of study: Artificial Intelligence and Biocybernetics

Supervisor: Ing. My Supervisor, Ph.D.
Supervisor-Specialist: Ing. My Specialist, Ph.D.

Acknowledgments

Firstly, I would like to express my gratitude to my supervisor.

Copyright

This thesis is a compilation of several articles published and submitted during my Ph.D. studies. The included publications are presented under the copyrights of IEEE, and Springer for posting the works for internal institutional uses. The works are protected by the copyrights of respective publishers and can not be further reprinted without the publishers' permission.

© IEEE, 2020

© Springer, 2020

Abstract

The study of autonomous Unmanned Aerial Vehicles (UAVs) has become a prominent sub-field of mobile robotics.

Keywords Unmanned Aerial Vehicles, Automatic Control

Abstrakt

Výzkum na poli autonomních bezpilotních prostředků (UAV) se stal významným oborem mobilní robotiky.

Klíčová slova Bepilotní Prostředky, Automatické Řízení

Abbreviations

GPS Global Positioning System

LiDAR Light Detection and Ranging

UAV Unmanned Aerial Vehicle

Contents

1	Introduction	1
1.1	Related works	1
1.2	Contributions	1
1.3	Mathematical notation	1
2	How to write thesis in LaTeX	2
2.1	Versioning with git	2
2.2	Forming paragraphs	2
2.3	Linguistic anti patterns	2
2.3.1	Narrative	2
2.3.2	Pronouns	2
2.4	Mathematical notation with LaTeX	2
2.4.1	Common errors	3
2.4.2	Equations	3
2.5	Using footnotes	4
2.6	Referencing document elements	4
2.7	Abbreviations with Acronym	4
2.8	Units of measurements with Siunitx	4
2.9	Hyphens and dashes	4
2.10	Double quotation marks	5
2.11	2D Diagrams with Tikz	5
2.12	Data plots with PGFPlots	5
2.13	3D Plots with Sketch	6
2.14	Image collages with Subfig	6
2.15	Citations with Biblatex	6
2.16	Image overlays with Tikz	7
2.17	General tips	7
3	Conclusion	9
A	References	10
A.1	Thesis core publications	10
A.2	Thesis-related author's publications	10
A.3	Cited references	10
B	Citations of Author's Publications	11

■ 1 Introduction

First, introduce the reader to the research topic. Start with the most general view and slowly converge to the particular field, sub-field, and the challenges you face. You can cite others' work here [1c].

■ 1.1 Related works

This section should contain related state-of-the-art works and their relation to the author's work. We usually cite the original works like this [3]. You can also cite multiple papers at once like this [1c], [2a].

■ 1.2 Contributions

This section should describe the author's contributions to the field of research.

■ 1.3 Mathematical notation

It is a good practice to define basic mathematical notation in the introduction. See Table 1.1 for an example.

$\mathbf{x}, \boldsymbol{\alpha}$	vector, pseudo-vector, or tuple
$\hat{\mathbf{x}}, \hat{\boldsymbol{\omega}}$	unit vector or unit pseudo-vector
$\hat{\mathbf{e}}_1, \hat{\mathbf{e}}_2, \hat{\mathbf{e}}_3$	elements of the <i>standard basis</i>
$\mathbf{X}, \boldsymbol{\Omega}$	matrix
\mathbf{I}	identity matrix
$x = \mathbf{a}^\top \mathbf{b}$	inner product of $\mathbf{a}, \mathbf{b} \in \mathbb{R}^3$
$\mathbf{x} = \mathbf{a} \times \mathbf{b}$	cross product of $\mathbf{a}, \mathbf{b} \in \mathbb{R}^3$
$\mathbf{x} = \mathbf{a} \circ \mathbf{b}$	element-wise product of $\mathbf{a}, \mathbf{b} \in \mathbb{R}^3$
$\mathbf{x}_{(n)} = \mathbf{x}^\top \hat{\mathbf{e}}_n$	n^{th} vector element (row), $\mathbf{x}, \mathbf{e} \in \mathbb{R}^3$
$\mathbf{X}_{(a,b)}$	matrix element, (row, column)
x_d	x_d is <i>desired</i> , a reference
$\dot{x}, \ddot{x}, \dddot{x}, \ddot{\ddot{x}}$	1 st , 2 nd , 3 rd , and 4 th time derivative of x
$x_{[n]}$	x at the sample n
$\mathbf{A}, \mathbf{B}, \mathbf{x}$	LTI system matrix, input matrix and input vector
$SO(3)$	3D special orthogonal group of rotations
$SE(3)$	$SO(3) \times \mathbb{R}^3$, special Euclidean group

Table 1.1: Mathematical notation, nomenclature and notable symbols.

■ 2 How to write thesis in LaTeX

■ 2.1 Versioning with git

Write the LaTeX in such a way that it could be versioned by git, which will help when collaborating with other people. This means writing **one sentence per line**. Even when you use third-party platforms, such as the OverLeaf, you can still share the repository through Git.

■ 2.2 Forming paragraphs

A paragraph is formed in LaTeX by an uninterrupted block of non-empty lines. It is recommended to keep a single sentence per line (helps with versioning using git). A new paragraph is started after an empty line.

This is a new paragraph. It is strongly recommended to **avoid** the use of the *newline* (`\\`) feature of LaTeX for forming paragraphs as it doesn't format the new paragraph properly (no space at beginning of the new paragraph).

■ 2.3 Linguistic anti patterns

■ Narrative

We recommend to write your thesis in plural form of the first-person narrative in combination with passive tense, e.g.:

- We discourage the use of any other form, and/or
- any other form is discouraged, but **not**
- I discourage you from using the first-person narrative.

Moreover, avoid “instructional” or “teacher”-like style of writing, such as “**Now, we multiply the matrix \mathbf{A} by the scalar c to get the scaled matrix \mathbf{B} .**” A better way of writing the same information would be e.g. “Now, the scaled matrix \mathbf{B} is obtained by multiplying the matrix \mathbf{A} by the scalar c .”

■ Pronouns

The use of pronouns (it, this, they) is strongly **discouraged**. Although, pronouns make it easier for you as a writer to form the flow of the text, pronouns also make it much more difficult for the reader to follow the text. The reader is forced to retain more of the context to substitute and understand what the author meant. Moreover, pronouns can easily become vague (there is more than one way how to interpret them) and can become invalid while making editorial changes to the text, i.e., when moving sentences around. A technical text should be written in a way that makes it as easy to read and comprehend as possible and as hard to misunderstand or misinterpret as possible at the same time.

■ 2.4 Mathematical notation with LaTeX

Take care to use the correct mathematical symbols and common ways of denoting mathematical concepts. Use bold fonts to visually distinguish vectors and matrices (\mathbf{x} , \mathbf{A}) and

scalars (k , N).

■ Common errors

A frequent error, carried over from programming languages, is using the asterisk symbol ($*$) to denote multiplication. The asterisk correctly denotes convolution. Similarly, the cross sign (\times) typically denotes the cross product (it can also be used for stating dimensions, such as $10\text{ m} \times 10\text{ m}$) and thus should not be used for scalar multiplication. In English mathematical notation, **scalar multiplication is typically not denoted at all**.

This custom may sometimes make it unclear whether a sequence of letters denotes multiplication of several scalars or a multi-letter variable, such as

$$T = T0 + coef f meas, \quad (2.1)$$

where the variables in this hypothetical equation are T , $T0$, $coef$ and $meas$. For this reason, **avoid using multi-letter variable naming** and strive to denote mathematical variables with single letters optionally with a lower or upper index, or other modifiers ($\hat{}$, $\bar{}$, etc.). The equation above could be modified to be

$$T = T_0 + cT_{\text{meas}}. \quad (2.2)$$

If the multiplication is still unclear (e.g. when multiplying many single-letter scalars), the \cdot symbol may be used such as

$$P \cdot V = n \cdot R \cdot T. \quad (2.3)$$

■ Equations

Mathematical equations should be numbered and should be a part of a sentence. For example, a discrete LTI system update is described as

$$\mathbf{x}_{[k+1]} = \mathbf{A}\mathbf{x}_{[k]} + \mathbf{B}\mathbf{u}_{[k]}, \quad (2.4)$$

where $\mathbf{x}_{[k]} \in \mathbb{R}^m$ is the state vector at the sample k , $\mathbf{u}_{[k]} \in \mathbb{R}^n$ is the input vector, $\mathbf{A} \in \mathbb{R}^{m \times m}$ is the main system matrix, and $\mathbf{B} \in \mathbb{R}^{m \times n}$ is the system input matrix. Proper punctuation should be used after the equation, as if it were an ordinary object in the sentence.

Do not put any empty lines before the equation. If the sentence that the equation is a part of continues after the equation (as is the case here), do not put empty lines after the equation either. That would create a new paragraph mid-sentence. **For an example of how not to do it, the equation**

$$\sigma(x) = \frac{1}{1 + e^{-x}} \quad (2.5)$$

describes the logistic function often used in machine learning. Observe how a new paragraph is created for the equation and then for this block of text (compare with the proper typesetting above). Not only does this not look correct, it may also cause incorrect page breaking.

■ 2.5 Using footnotes

Do not be afraid to use footnotes for additional information, such as http links¹. We use footnote links whenever we want to *point* to a website, rather than to cite it as a source. Like with everything, do not overdo it.

■ 2.6 Referencing document elements

LaTeX allows you to dynamically reference to parts of the documents, such as

- figures: Fig. 2.4, Figure 2.4,
- equations: eq. (2.4), (2.4),
- code: Lst. 2.1,
- and any other object that can contain a `\label`.

Check the section in the `document_setup.tex` that contains useful macros for unifying the references:

```
\newcommand{\reffig}[1]{Fig.~\ref{#1}}
\newcommand{\reflst}[1]{Lst.~\ref{#1}}
\newcommand{\refalg}[1]{Alg.~\ref{#1}}
\newcommand{\refsec}[1]{Sec.~\ref{#1}}
\newcommand{\refstab}[1]{Table~\ref{#1}}
\newcommand{\refeq}[1]{\eqref{#1}}
```

Listing 2.1: LaTeX macros for referencing to document elements.

■ 2.7 Abbreviations with Acronym

Abbreviations are handled by the *acronym* package. Example sentence with abbreviations: “UAV is a flying vehicle that commonly uses Light Detection and Ranging (LiDAR) and Global Positioning System (GPS) receiver”. Note that the acronyms are only explained once in the document by default. It is good practice to re-explain acronyms used both in the abstract and the rest of the document as the abstract is often presented separately. This can be achieved by resetting the internal status of the acronyms (“forgetting” that they were explained) using the `\acresetall` command after the abstract. Please, read the documentation².

■ 2.8 Units of measurements with Siunitx

Typesetting of units has never been more accessible with the Siunitx package. Acceleration is measured in ms^{-2} . Gravity accelerates objects at a rate $\approx 9.81 \text{ ms}^{-2}$ near the sea level. You can define your units if you want.

■ 2.9 Hyphens and dashes

Hyphens and dashes are the various form of the symbol “-” used in many situations. There are also various ways how to typeset the symbol in LaTeX.

- The *hyphen* is used to compound words, e.g., “the eye-opener”. The hyphen is typeset as a single *minus/hyphen* character: -.

¹This repository: <https://github.com/ctu-mrs/thesis-template>.

²Acronym package: <http://mirrors.ctan.org/macros/latex/contrib/acronym/acronym.pdf>

- The *en-dash* is used to specify ranges of values, e.g., “between 2–10”. The en-dash is typeset as two consecutive hyphens characters: --.
- The *em-dash* is used to separate complex sentences in place of commas, parenthesis and colons — each with its particular rules. The em-dash is typeset as three consecutive hyphens characters: ---.

Check the <https://www.thepunctuationguide.com/> for all the details.

■ 2.10 Double quotation marks

“Double quotes” in English are composed of a pair of opening (“) and closing (”) symbols. The opening symbol is typeset as two backtick characters: ‘‘ (typically below the Esc key on the English keyboard), and the closing quotes as two apostrophes: ’’. The LaTeX engine will convert them automatically to the opening and closing symbols. A more robust solution is to use the `csquotes` package and the `\enquote` command which also takes care of nested quoting and other peculiarities.

■ 2.11 2D Diagrams with Tikz

Tikz is a powerful tool for drawing 2D (and 3D) shapes and diagrams. Check the documentation and examples: https://www.overleaf.com/learn/latex/TikZ_package. The benefit of using *Tikz*, instead of some other third-party drawing program, are:

- fonts are the same as in LaTeX,
- you can typeset math in LaTeX,
- you can use references to other parts of your document,
- you can version the image in git,
- the images are easily adjustable while editing your document.

Check Fig. 2.1 for example.

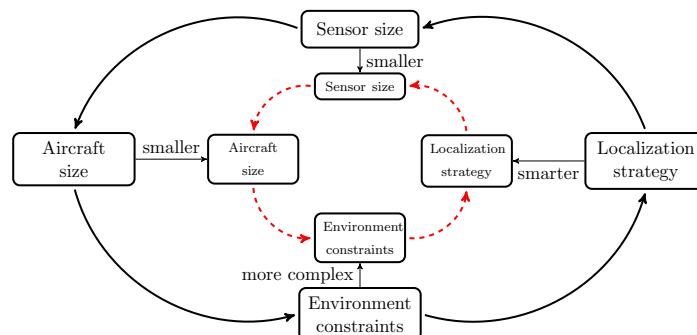


Figure 2.1: Example of a 2D diagram using tikz *PGFPlots*.

■ 2.12 Data plots with PGFPlots

PGFPlots produces nice 2D and 3D data plots from data stored in CSV. The plot parameters can be versioned and easily adjusted by editing the plot definition file.

- Documentation and manual: <https://ctan.org/pkg/pgfplots>
- Compile the plots individually and then include the pdfs because it can take longer.
- Example located in `fig/plots/example_plot`, see Fig. 2.2.

- You could include the latex file directly. However, it will take longer to compile, and platforms such as Overleaf can have a problem with that.

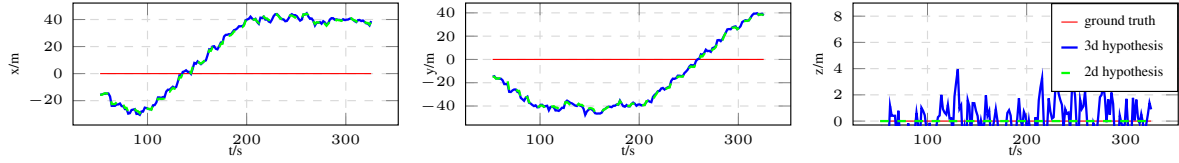


Figure 2.2: Example of a 2D plot using *PGFPlots*.

■ 2.13 3D Plots with Sketch

Sketch is a tool for defining a 3D scene using simple descriptive language. The 3D scene is then converted to *Tikz*, which is later compiled to pdf. The benefits of using *Sketch* are similar to using *Tikz*: LaTeX fonts, versioning using git, and cleanness of the result. See the example image in Fig. 2.3.

- Documentation and manual: <http://www.frontiernet.net/~eugene.reessler/>
- Cross-compilation from *Sketch* to pdf using the `fig/sketch/compile_sketch.sh` script.

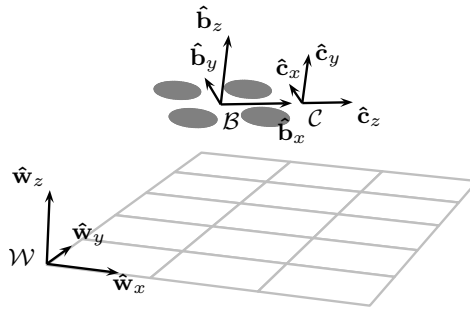


Figure 2.3: Depiction of the used coordinate systems. The image was drawn using *Sketch*.

■ 2.14 Image collages with Subfig

We recommend using the *subfig* package, which provides the `\subfloat` command. It is more versatile than the simpler *subcaption* package. Check Fig. 2.4 for an example.

■ 2.15 Citations with Biblalex

Biblalex is probably the most powerful citation package for LaTeX. It consumes the standard `.bib` file. However, it can sort and filter the citations using the `keywords` tag. Citing references is done using the `cite` command, e.g., [1c]. You can also define some nice citation boxes, such as this one:

- [1c] **T. Baca**, M. Petrlik, M. Vrba, V. Spurny, R. Penicka, D. Hert, *et al.*, “The MRS UAV System: Pushing the Frontiers of Reproducible Research, Real-world Deployment, and Education with Autonomous Unmanned Aerial Vehicles,” *Journal of Intelligent & Robotic Systems*, vol. 102, no. 26, pp. 1–28, 1 May 2021



(a) A UAV, the T650 model.



(b) Another UAV, again, the T650 model.

Figure 2.4: The caption should mention both subfigures, the Fig. 2.4a and the Fig. 2.4b. You can just refer to them as (a) and (b) in the main Figure’s caption, but beware, you need to keep it correct as you edit.

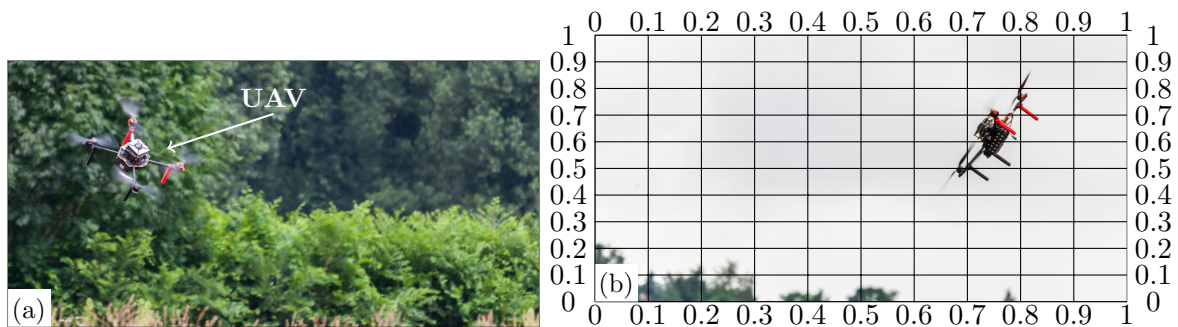


Figure 2.5: Example of using Tikz for image overlays. (a) shows a final product, (b) shows a grid useful for nailing down the coordinates.

■ 2.16 Image overlays with Tikz

Tikz is very useful to create custom image overlays. The overlay can be set such that the image is spanned by Cartesian coordinates $(x, y) \in [0, 1]^2$. Example can be seen in Fig. 2.5.

■ 2.17 General tips

In general, strive to make the paper easy to read and understand, and hard to misunderstand or misinterpret. Here are some more specific tips on how to achieve that (and other general suggestions).

- **Be consistent.** This applies in all contexts. For example, if you decide to use the name “LiDAR”, do not mix it with “LIDAR” or “Lidar”, do not mix different mathematical notations, ensure your Figures have the same style and use the same graphics for the same concepts, etc.
- After you finish writing or modifying any of:
 - a sentence,
 - a paragraph,
 - a section/chapter,
 - the whole paper/thesis,

re-read it to make sure that it makes sense, it is coherent and correct, and doesn’t

contain typos.

- If you're using a LLM-based tool (ChatGPT etc.) for grammar-proofing or even formulation of sentences, **do not just copy-paste its response** to your query. The previous rule applies doubly here. LLMs tend to often produce confident-sounding nonsense, sentences with reformulated duplicated content, or with a slightly changed meaning. They are a good tool to get inspiration to start writing about a subject, for grammar-checking, or for finding alternative, nice-sounding formulations, but they can lie or warp facts — take care when using them!

3 Conclusion

Summarize the achieved results. Can be similar as an abstract or an introduction, however, it should be written in past tense.

■ A References

References to the author's work are listed first, followed by other references cited within this work. The authored references contain his contribution and the number of citations based on Web of Science (WoS), Scopus, and Google Scholar (GS). The citation counts were gathered on [insert date here](#).

■ A.1 Thesis core publications

Core articles in peer-reviewed journals

- [1c] **T. Baca**, M. Petrlik, M. Vrba, V. Spurny, R. Penicka, D. Hert, and M. Saska, "The MRS UAV System: Pushing the Frontiers of Reproducible Research, Real-world Deployment, and Education with Autonomous Unmanned Aerial Vehicles," *Journal of Intelligent & Robotic Systems*, vol. 102, no. 26, pp. 1–28, 1 May 2021, **Contributions: TB: 60%, MP: 10%, VM: 6%, VS: 6%, RP: 6%, DH: 6%, MS: 6%, IF 2.646 (Q2 in Robotics)**.

■ A.2 Thesis-related author's publications

Thesis-related conference articles

- [2a] **T. Baca**, G. Loianno, and M. Saska, "Embedded Model Predictive Control of Unmanned Micro Aerial Vehicles," in *IEEE International Conference on Methods and Models in Automation and Robotics (MMAR)*, IEEE, 2016, pp. 992–997, **80% contribution, citations: 25 in WoS, 29 in Scopus, 88 in GS**.

■ A.3 Cited references

- [3] A. Benallegue, A. Mokhtari, and L. Fridman, "High-order sliding-mode observer for a quadrotor UAV," *International Journal of Robust and Nonlinear Control: IFAC-Affiliated Journal*, vol. 18, no. 4-5, pp. 427–440, 2008.

■ B Citations of Author's Publications

Citations of the author's work were extracted from the Web of Science. First- and second-order self-citations are excluded. The data were gathered on [insert date here](#).

[1c] **T. Baca**, M. Petrlik, M. Vrba, V. Spurny, R. Penicka, D. Hert, *et al.*, “The MRS UAV System: Pushing the Frontiers of Reproducible Research, Real-world Deployment, and Education with Autonomous Unmanned Aerial Vehicles,” *Journal of Intelligent & Robotic Systems*, vol. 102, no. 26, pp. 1–28, 1 May 2021

- P. Arias-Perez, J. Fernandez-Conde, D. M. Gomez, J. M. Canas, and P. Campoy, “A Middleware Infrastructure for Programming Vision-Based Applications in UAVs,” *Drones*, vol. 6, no. 11, 2022.
- T. Manoni, D. Albani, J. Horyna, P. Petrcek, M. Saska, and E. Ferrante, “Adaptive arbitration of aerial swarm interactions through a Gaussian kernel for coherent group motion,” *Frontiers in Robotics and AI*, vol. 9, 2022.
- K. Guo, C. Liu, X. Zhang, X. Yu, Y. Zhang, L. Xie, and L. Guo, “A Bio-Inspired Safety Control System for UAVs in Confined Environment With Disturbance,” *IEEE Transactions on Cybernetics*,