* **Introduction**
* **Theoretical Background**
  + Flapping Wings Dynamic in Bats
  + Feed Forward and Back Controlling
  + PID Controller
  + Evolutionary Algorithm: Covariance Matrix Adaptation
  + ModBus Communication Protocol
* **Literature Review**
  + Evolutionary Algorithm to Train Robots
  + Bat Robots
* **Materials**
  + Batbot
    - Kinematic
    - PyBoard and MicroPyhton
    - Magnetic Encoder
    - MCU
    - PCA
    - Servo Motors
    - DC Motor
    - Communication
      * Wireless Uart
      * RC
  + 6 Axis Sensor
  + Static Test Bench
  + Dynamic Test Bench
* **Optimization Algorithm**
  + Python Code
  + Workflow Diagram
  + Score Calculation
* **Batbot Version 1 (only one DOF per leg)**
  + Characteristics
  + Straight Flight Experiment
  + Conclusions
* **Batbot Version 2 (2 DOF per leg)**
  + Characteristics
  + Wing Folding influence in Lift
  + Hind Legs Movement Parametrization
  + Optimization Results
  + Force Analysis
  + Conclusions
* **Batbot Version 3 (Gear improvement for higher frequencies)**
  + Characteristics
  + Dynamic Test
  + Hand Controlled Experiment
    - Tied short distance
    - Tied long distance
    - 3 Axis Rotation Control
    - Free Flight Experiment
  + Conclusions
* **Batbot Version 4 (Longer legs, compact embedded circuit)**
  + Characteristics
  + Hand Controlled Experiment
    - Straight Flight
    - Hover Flight
      * Leg movements strategies and their influence in rotation
  + Optimization Algorithm Refinement
  + Self Sustained Hovering with MCU and PID
* **Discussion**
* **Conclusion**