

# Thesis Name

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# **1   Abstract**

This document describes the sequence to build a robotic arm; including modelling, simulation, real-time control and implementation.

## **2 Introduction**

Introduction

### **3 State of the art**

State of the art

### 3.1 Kinematics

## 3.2 Inverse Kinematics

## 4 Development and analysis

Abstract



## 5 Implementation

Abstract

## 6 Conclusion

Abstract