

# Hello world title

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**Abstract**—put abstract hese  
**Index Terms**—Robotics, Control, Systems

APPENDIX A  
PRELIMINARY WORK

## I. INTRODUCTION

intro content

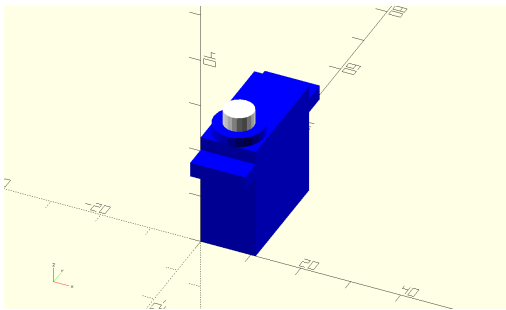


Fig. 1: A picture of a servo

A. *Manufacturing*  
subsection

$$G_1 = m_1 g^T \frac{\partial A_0^1}{\partial \theta_1} \bar{p}_1 \tag{1}$$

## II. RESULTS AND DISCUSSION

- A. *Positional Accuracy*
- B. *Geometric Accuracy*
- C. *Repeatability*

## III. CONCLUSION

## IV. RECOMMENDATIONS