Hello world title

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

I. INTRODUCTION
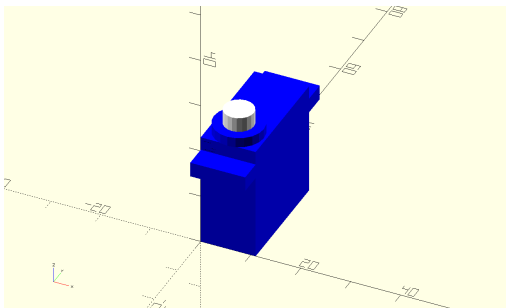
intro content

Fig. 1: A picture of a servo

A. Manufacturing

subsection

$$G_1 = m_1 g^T \frac{\partial A_0^1}{\partial \theta_1} \bar{p_1} \qquad (1)$$

II. RESULTS AND DISCUSSION

A. Positional Accuracy

B. Geometric Accuracy

C. Repeatability

III. CONCLUSION

IV. RECOMMENDATIONS

APPENDIX A
PRELIMINARY WORK