

Inconsistencies from motivating study

Excluding inconsistencies in text spacing and line breaks

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font styles

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xetex

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The contributions of the paper are: (i) a general *framework for program instrumentation*, which defines a space of program transformations that work by rewriting individual statements (Section 2); (ii) an application strategy *search algorithm* in this space, for a given program (Section 3); (iii) two *instantiations* of the framework—one for instrumentation operators to handle specifications with *quantifiers* (Section 4.1), and one for *extended quantifiers* (Section 4.2); (iv) machine-checked proofs of the correctness of the instrumentation operators

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(Section 4.1), and one for *extended qi*
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difference in quotation marks

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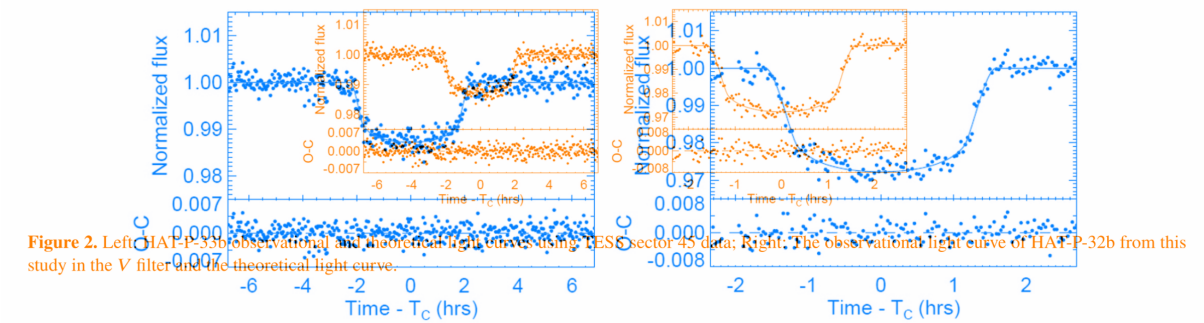
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image placement



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Title Suppressed Due to Excessive Size

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Symmetry-Aware Robot Design

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Abstract

Robot design aims at learning to create robots that can be easily controlled and per-

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Abstract

Robot design aims at learning to create robots that can be easily controlled and perform tasks

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dimensions of hyperlink boxes

at which point. And we can prove
Theorem 4.2 in Appendix A.9.

D algorithm in Algorithm 1 and
tailed version in Appendix A.1.

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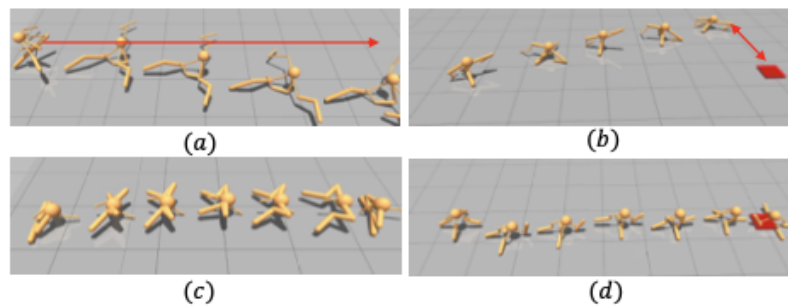
is Theorem 4.2 in Appendix A.9.

gorithm in Algorithm 1 and we also
in Appendix A.1.

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image placement

this image appears at different places relative to the text (page 1 on pdftex, page 2 on xetex)



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references

Humans have been dreaming of creating creatures with morphological intelligence for decades (Sims, 1994a;b; Yuan et al., 2021; Gupta et al., 2021b). A promis-

Humans have been dreaming of creating creatures with morphological intelligence for decades (????). A promising solution for this challenging problem is to generate

(a) PDF generated by Xe_{La}TeX

(b) PDF generated by Lua_{La}TeX

Figure 8: Differences in references: Lua_{La}TeX renders “????” instead of the correct citations (arXiv:2306.00036 [27])

image placement

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CONTENTS

1. Introduction
2. The Sarkisov program for Mf CY pairs
3. Proof of Theorem A

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CONTENTS

1. Introduction

2. The Sarkisov program for Mf CY pairs

3. Proof of Theorem A

4. Extremal contractions

5. Proof of Theorem B

6. Proof of Theorem C

References

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table header and footer:

Object	$X^\dagger \subseteq \text{Ambient}$	Ambient coords. & wts.	Eqn. of X^\dagger in Ambient	Eqn. of D^\dagger in X^\dagger
1	$X^\dagger = \mathbb{P}^3$	$\begin{array}{cccc} x_0 & x_1 & x_2 & x_3 \\ 1 & 1 & 1 & 1 \end{array}$	0	$x_0x_1x_2^2 + Bx_3 + C$
2	$X^\dagger = \mathbb{F}_1^3$	$\begin{array}{cccc} x_0 & x_1 & x_2 & x_3 & x \\ 1 & 1 & 1 & 0 & -1 \\ 0 & 0 & 0 & 1 & 1 \end{array}$	0	$x_0x_1x_2^2 + Bx_3x + Cx^2$
2 ^a	$X^\dagger = \mathbb{F}_2^3$	$\begin{array}{cccc} x_0 & x_1 & x_2 & x_3 & x \\ 1 & 1 & 1 & 0 & -2 \\ 0 & 0 & 0 & 1 & 1 \end{array}$	0	$x_0x_2^2 + Bx_3x + x_1Cx^2$
2 ^b	$X^\dagger = \mathbb{F}_2^3$	$\begin{array}{cccc} x_0 & x_1 & x_2 & x_3 & x \\ 1 & 1 & 1 & 0 & -2 \\ 0 & 0 & 0 & 1 & 1 \end{array}$	0	$x_1x_2^2 + Bx_3x + x_0Cx^2$
3 ^a	$X^\dagger = \mathbb{P}(1^3, 2)$	$\begin{array}{cccc} x_0 & x_1 & x_2 & y \\ 1 & 1 & 1 & 2 \end{array}$	0	$x_0y^2 + By + x_1C$
3 ^b	$X^\dagger = \mathbb{P}(1^3, 2)$	$\begin{array}{cccc} x_0 & x_1 & x_2 & y \\ 1 & 1 & 1 & 2 \end{array}$	0	$x_1y^2 + By + x_0C$
4	$X_4 \subset \mathbb{P}(1^3, 2^2)$	$\begin{array}{ccccc} x_0 & x_1 & x_2 & y_0 & y_1 \\ 1 & 1 & 1 & 2 & 2 \end{array}$	$y_0y_1 + C -$ $-L(x_0y_1 - x_1y_0 - B)$	$x_0y_1 - x_1y_0 - B$
5 ^a	$X_4 \subset \mathbb{P}(1^4, 2)$	$\begin{array}{cccc} x_0 & x_1 & x_2 & y \\ 1 & 1 & 1 & 1 & 2 \end{array}$	$y(y + Q) - C +$ $+x_3((x_0 + x_1)y + x_1Q + B)$	$y + x_1x_3$
5 ^b	$X_4 \subset \mathbb{P}(1^4, 2)$	$\begin{array}{cccc} x_0 & x_1 & x_2 & y \\ 1 & 1 & 1 & 1 & 2 \end{array}$	$y(y - Q) - C +$ $+x_3((x_0 + x_1)y - x_0Q + B)$	$y + x_0x_3$

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Object	$X^\dagger \subseteq \text{Ambient}$	Ambient coords. & wts.	Eqn. of X^\dagger in Ambient	Eqn. of D^\dagger in X^\dagger
1	$X^\dagger = \mathbb{P}^3$	$\begin{array}{cccc} x_0 & x_1 & x_2 & x_3 \\ 1 & 1 & 1 & 1 \end{array}$	0	$x_0x_1x_2^2 + Bx_3 + C$
2	$X^\dagger = \mathbb{F}_1^3$	$\begin{array}{cccc} x_0 & x_1 & x_2 & x_3 & x \\ 1 & 1 & 1 & 0 & -1 \\ 0 & 0 & 0 & 1 & 1 \end{array}$	0	$x_0x_1x_2^2 + Bx_3x + Cx^2$
2 ^a	$X^\dagger = \mathbb{F}_2^3$	$\begin{array}{cccc} x_0 & x_1 & x_2 & x_3 & x \\ 1 & 1 & 1 & 0 & -2 \\ 0 & 0 & 0 & 1 & 1 \end{array}$	0	$x_0x_2^2 + Bx_3x + x_1Cx^2$
2 ^b	$X^\dagger = \mathbb{F}_2^3$	$\begin{array}{cccc} x_0 & x_1 & x_2 & x_3 & x \\ 1 & 1 & 1 & 0 & -2 \\ 0 & 0 & 0 & 1 & 1 \end{array}$	0	$x_1x_2^2 + Bx_3x + x_0Cx^2$
3 ^a	$X^\dagger = \mathbb{P}(1^3, 2)$	$\begin{array}{cccc} x_0 & x_1 & x_2 & y \\ 1 & 1 & 1 & 2 \end{array}$	0	$x_0y^2 + By + x_1C$
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4	$X_4 \subset \mathbb{P}(1^3, 2^2)$	$\begin{array}{ccccc} x_0 & x_1 & x_2 & y_0 & y_1 \\ 1 & 1 & 1 & 2 & 2 \end{array}$	$y_0y_1 + C -$ $-L(x_0y_1 - x_1y_0 - B)$	$x_0y_1 - x_1y_0 - B$
5 ^a	$X_4 \subset \mathbb{P}(1^4, 2)$	$\begin{array}{cccc} x_0 & x_1 & x_2 & y \\ 1 & 1 & 1 & 1 & 2 \end{array}$	$y(y + Q) - C +$ $+x_3((x_0 + x_1)y + x_1Q + B)$	$y + x_1x_3$
5 ^b	$X_4 \subset \mathbb{P}(1^4, 2)$	$\begin{array}{cccc} x_0 & x_1 & x_2 & y \\ 1 & 1 & 1 & 1 & 2 \end{array}$	$y(y - Q) - C +$ $+x_3((x_0 + x_1)y - x_0Q + B)$	$y + x_0x_3$

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references

How to read Table 1. The

of Theorem C.

The first row of Table 1

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(\mathbb{P}^3, D) of Theorem C.

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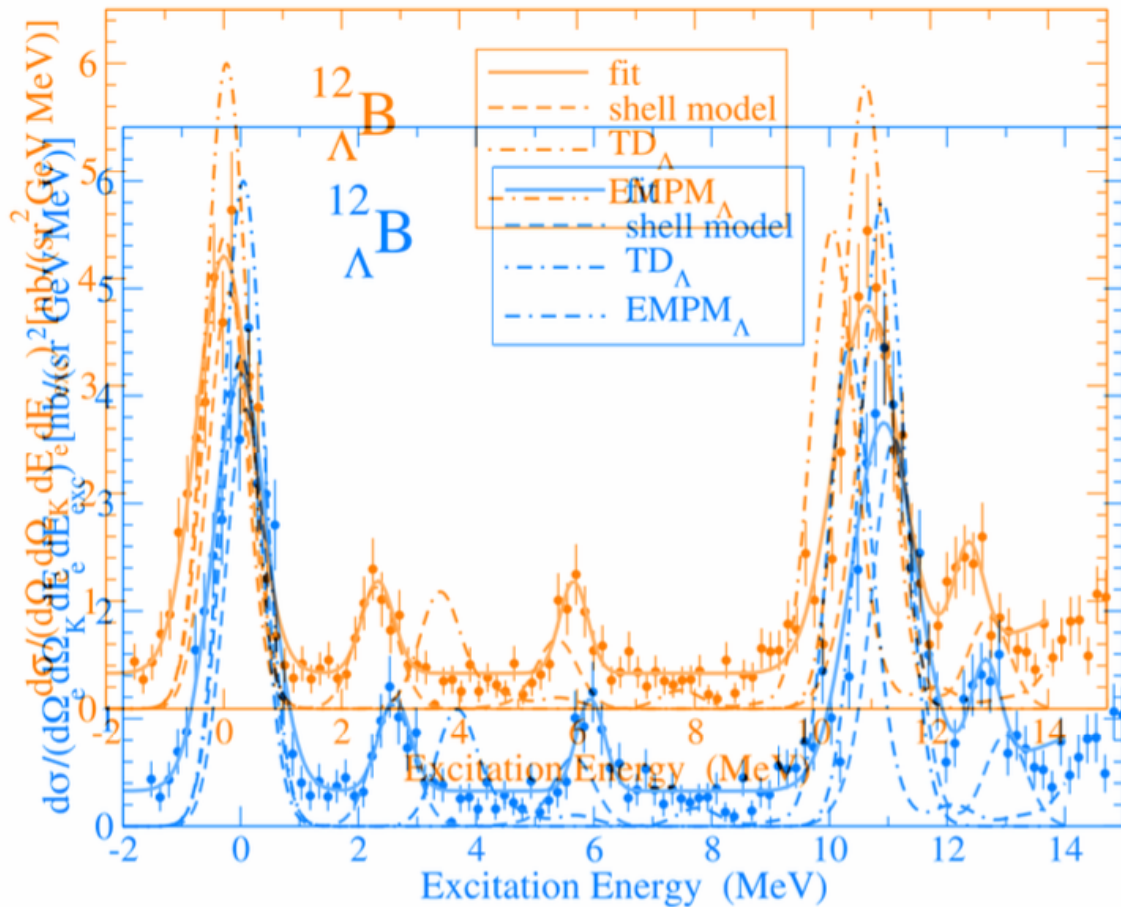


FIG. 1: The TD_{Λ} (dash-dot line), and $EMPM_{\Lambda}$ (double-dash-

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