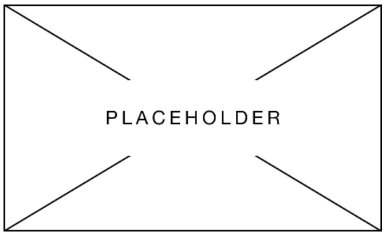

Some Placeholder Title

A Master Thesis

written by

Name
my@email.dk
potential-number

The code for this project is available at
`url-to-some-github`

Overarching Institution
Specific Department

Word Count : [some word count]
Date of Hand In

Abstract

Some abstract text explaining the goal, methods and conclusion of the project.

Contents

Acknowledgements

We would like to thank our supervisor Christoffer Sloth for the guidance he provided during the project.

Acronyms

acronym-abbr actorym-description.

glossary-multi-abbr glossary-multi-long.

Terms

glossary term glossary term description.

glossary-multi-long (glossary-multi-abbr) glossary-multi-description.

Chapter 1

Example section

This document demonstrate the use of figures, references, SI units, glossary, math notation, lists, and otherwise relevant formatting specifications. Paragraphs are typically separated using `\medskip`.

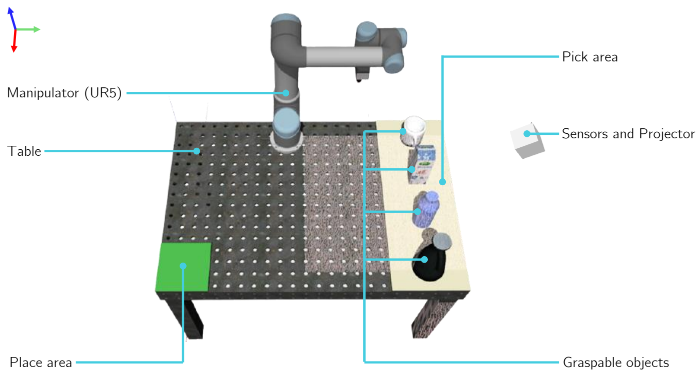

Fig. 1: An example image using actorym-description.

To exemplify math notation, consider the mapping between the joint configuration of a robot

$$\mathbf{q} = \begin{bmatrix} q_1 & q_2 & \cdots & q_n \end{bmatrix}^\mathsf{T}, \tag{1}$$

and glossary term, given as a homogeneous transformation

$$\mathbf{T}_B^A = \begin{bmatrix} \mathbf{R}_B^A & \mathbf{t}_B^A \\ \mathbf{0}^{1\times 3} & 1 \end{bmatrix}, \tag{2}$$

where $\mathbf{R}_B^A$ and $\mathbf{t}_B^A$ is the rotation and translation, respectively, from frame $\{A\}$ to frame $\{B\}$, denoted using a homogeneous transformation matrix $\mathbf{T}(\mathbf{q}) \in \mathbb{R}^{4\times 4}$ as a function of the joint configuration in (1), as described in [**robotics-book**].

Complex table/figure hybrids with aligned captions and functioning labels can be implemented using `minipage`, as shown in Table 1 and Fig. 2. Use \cite as a placeholder for citations.

Method / **Pose**	1	2	3
Linear	18.97 s	20.35 s	22.85 s
Parabolic	13.66 s	14.93 s	17.33 s

Table 1: Trajectory durations of the interpolation-based trajectory generation methods.

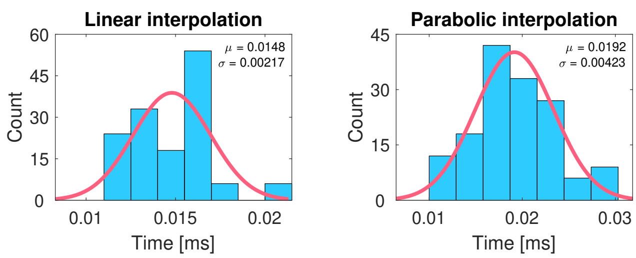

Fig. 2: Average planning time for each of the interpolation-based trajectory generation methods.

For numbers, units and ranges, the `siunitx` package is used, which allows to express a number 10, a range of 5 s to 6 s, or a SI unit of 5.73 ± 1.09 s. Inline row-vectors (with the transpose symbol) can be written as $\mathbf{a} = \begin{bmatrix} \mathbf{a}_p & \mathbf{a}_o \end{bmatrix}^\mathsf{T}$, where as parentheses can be automatically written using (a, b) or $\left\{\frac{a}{b}, c\right\}$. Also, shorthands for $\mathbf{A}^{-1}$, $\mathbf{A}^{\dagger}$and $\mathbf{A}^\mathsf{T}$.

Chapter 2

Introduction

Subject matter terms are addressed with `\gls{glossary-label}` like so glossary term.
Acronyms are addressed with either with their long equivalent `\acrlong{gls-label}` which gives actorym-description or the short equivalent `\acrshort{gls-label}` which gives acronym-abbr.
Subject matter terms can also be multi structure `\gls{glossary-multi-label}` which gives glossary-multi-long (glossary-multi-abbr) (see terms and acronyms above).

Chapter 3

Problem 1

3.1 Introduction

Here we write the introduction for problem 1.

3.2 Related Work

Here we cite the related work by `\cite{source-label}` like this [1]

Chapter 4

Problem 2

Chapter 5

Discussion

Chapter 6

Conclusion

Bibliography

[1] Quigley, Morgan et al. “ROS: an open-source Robot Operating System”. In: *ICRA Workshop on Open Source Software* 3 (Jan. 2009).

Appendix A

Appendix A Title