Title

Presentation

Student: Jingxuan Yang

Supervisor: Prof. XX

Tsinghua University

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Research Contents of This Project

Figure 1: Research Contents of This Project

Research progress

Figure 2: Research progress

Results

Results

- XXXX
- XXXX
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- XXXX
- XXXX
- XXXX

Case 1

Unnumbered equation

Example of unnumbered equation:

$$k : [-\pi, \pi] \to [0, 1]$$

Case 2

numbered equation

- Example of numbered equation: the input is an image

$$\boldsymbol{x} \in \mathbb{R}^{C_{\text{in}} \times H \times W} \tag{1}$$

where C_{in} represents number of input channels, H is the height of image, and W is the width of image.

Case 3

Table

Example of tables, shown in 1.

Table 1: Unique elements in train.csv

column	# unique values
posting_id	34250
image	32412
image_phash	28735
title	33117
label_group	11014

Case 4

Parallel figures

Example of parallel figures.

Figure 3: Example figure 1

Figure 4: Example figure 2

Future work

Future work

- XXXX
- XXXX
- XXXX
- XXXX

Scheduling

Scheduling

- XXXX[1]
- XXXX[2]
- XXXX[3]
- XXXX[4]

Bibliography I

[1] Webster III R J, Jones B A. Design and Kinematic Modeling of Constant Curvature Continuum Robots: A Review[J]. The International Journal of Robotics Research, 2010, 29(13): 1661-1683.

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[3] McMahan W, Jones B A, Walker I D. Design and Implementation of a Multi-section Continuum Robot: Air-Octor[C] // IEEE/RSJ International Conference on Intelligent Robots and Systems, Shanghai, China, 2005: 2578-2585.

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[4] Gravagne I A, Rahn C D, Walker I D. Large Deflection Dynamics and Control for Planar Continuum Robots[J]. IEEE/ASME Transactions on Mechatronics, 2003, 8(2) : 299-307.

Thanks for your attention!

Q & A