# Title

# Presentation

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# Contents

1. Research Contents
2. Results
3. Future Work

# Research Contents of This Project




Figure 1: Research Contents of This Project

# Research progress




Figure 2: Research progress

# Results

## Results

- XXXX
- XXXX
- XXXX
- XXXX
- XXXX
- XXXX

# Case 1

## Unnumbered equation

Example of unnumbered equation:

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

# 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 $C_{\text{in}}$ 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.

[2] Jones B A, Walker I D. Kinematics for Multisection Continuum Robots[J]. IEEE Transactions on Robotics, 2006, 22(1): 43-55.

[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.

# Bibliography II

[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