Dissertation for Doctor of Philosophy

The Title

John Park

School of Mechatronics

Gwangju Institute of Science and Technology

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박 사 학 위 논 문

제목

홍 길 동

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광 주 과 학 기 술 원

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The Title

Advisor: My Advisor

by

John Park

School of Mechatronics

Gwangju Institute of Science and Technology

A thesis submitted to the faculty of the Gwangju Institute of Science and Technology in partial fulfillment of the requirements for the degree of Doctor of Philosophy in the School of Mechatronics

Gwangju, Republic of Korea

November 30, 2014

Approved by

_____

Professor My Advisor

Thesis Advisor

The Title

John Park

Accepted in partial fulfillment of the requirements for the

degree of Doctor of Philosophy

November 30, 2014

Thesis Advisor _____

Prof. My Advisor

Committee Member _____

Prof. Professor 1

Committee Member _____

Prof. Professor 2

Dedicated to

my family.

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Abstract

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최근 제어 시스템

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Chapter 1

Introduction

1.1 BibTeX

Compile in a sequence of pdfLaTeX $\rightarrow$ BibTeX $\rightarrow$ pdfLaTeX $\rightarrow$ pdfLaTeX to get the final document.

1.2 Equation

$$\dot{x} = f(t, x). \tag{1.1}$$

From the system in (1.1)...

[1]

1.3 Theorem

Theorem 1.1. *The equilibrium point of...*

Proof. We have

$$\dot{V} \leq 0.$$

As a consequence, ... $\square$

Figure 1.1: Figure caption

1.4 Figure

Never mind the location of Figure 1.1.

1.5 Table

Never mind the location of Table 1.1.

Table 1.1: Table caption

	y_1	y_2
x_1	1	2
x_2	3	4

Chapter 2

Conclusion

Bibliography

1. B. D. O. Anderson, C. Yu, B. Fidan, and J. M. Hendrickx, “Rigid graph control architectures for autonomous formations,” *IEEE Control Systems Magazine*, vol. 28, no. 6, pp. 48–63, 2008.

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