

Thesis for Master's Degree

# The Title

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2015

# The Title

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by

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

Gwangju, Republic of Korea

November 30, 2014

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Professor My Advisor

Thesis Advisor

# The Title

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Accepted in partial fulfillment of the requirements for the  
degree of Master of Science

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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20110000 Advisor.

## **Abstract**

In recent years,

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# Chapter 1

## Introduction

### 1.1 BibTeX

Compile in a sequence of pdfLaTeX  $\rightarrow$  BibTeX  $\rightarrow$  pdfLaTeX  $\rightarrow$  pdfLaTeX [1] to get the final document.

### 1.2 Equation

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

From the system in (1.1)...

### 1.3 Theorem

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

*Proof.* We have

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

As a consequence, ...

□

### 1.4 Figure

Never mind the location of Figure 1.1.

Table 1.1: ...

7C0	hexadecimal
3700	octal
11111000000	binary
1984	decimal

## 1.5 Table

Never mind the location of Table 1.1.

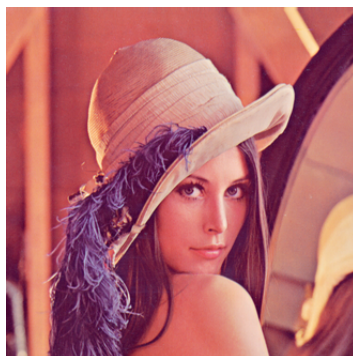


Figure 1.1: ...

## **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.

## Acknowledgements

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