

Bachelor Thesis

Preparing Examination Work Report in BSc/MSc/MEng in Computer Engineering Programme at Örebro University Using <u>ETEX</u>

Author Names Computer Science Studies from the School of Science and Technology at Örebro University



Author Names

Preparing Examination Work Report in BSc/MSc/MEng in Computer Engineering Programme at Örebro University Using LETEX

Supervisors:

Examiner:

First Supervisor, Affiliation Second Supervisor, Affiliation Examiner

© Author Names, 2024

Abstract

Abstract is a short overview of the content of the work. The main goal of abstract is to give a reader an idea about the work, without the need to read it all. Thus, the abstract should be concise, but at the same time concrete on the content of the work.

Typically, abstract is not more than one page long, and presents the work in a brief and concise way. Often abstract follows the outline of the work presents a problem, method, and results.

Keywords

Template, BSc, MSc, Thesis, Computer Science, Computer Engineering

Contents

1	Introduction1.1Problem Formulation1.2Division of Work1.3Outline	3			
2	Related Works				
3	Implementation	5			
4	Results	7			
5	Conclusions 5.1 Review of Project Goals 5.2 Context 5.3 Future Works	8 8 8 8			
R	eferences	10			

Chapter 1 Introduction

This is the introduction. Here, you need to introduce your reader to the topic and guide through some logical steps to the problem formulation. Please remember who is your reader: if you consider your typical reader to be an engineer, then you probably do not need to start by explaining what is a computer. But you do need to give enough information to explain the reader why the problem you have chosen for your work is important and relevant.

Please, keep in mind that your thesis is the main deliverable of your exam work. Of course, a significant contribution (either theoretical, or scientific, or engineering) must be done in order to provide the content for the thesis. Majority (but not all) of learning objectives are evaluated by the examiner based on the thesis, the work presented in it, and the form of presentation.

1.1 **Problem Formulation**

At some point, after some general introduction, you need to formulate and frame your problem. This is directly related to the learning objective *F1a*.

The problem or the goal of the project must be clear and specific. You might want to split it us into sub-goals and objectives. You might also want to apply so called, SMART criteria for each objective, meaning that they need to be Specific, Measurable, Attainable, Relevant, and Time-bound. Applying this criteria might help you to avoid focusing on something that is irrelevant or might not be possible to achieve given the timeframe.

Robot Operating System (ROS)

1.2 Division of Work

If the thesis is written in a group, it is important to provide a clear statement on the division of work and contribution of each of the co-authors.

1.3 Outline

In the end of the introduction, you need provide the structure of the remaining parts of the thesis. So, you can say something like this: The rest of this thesis is organised as follows:

Chapter 2 gives an overview of relevant previous works in the field of something and something else.

Chapter 5 contains conclusions. Not many, but some.

Chapter 2 Related Works

The review of related works is directly targeting learning objective *F1b* and is a compulsory and vital part of any engineering or scientific work.

In your role as a researcher or an engineer, you must be up to date with the state-ofthe-art in your field. You should be able to critically review what has been done before and then be able to apply it, when possible and appropriate, the a problem at hands.

In most cases, this part of the thesis takes from 20% to 40% or even more of the whole volume of the thesis. It might look alarming if this part of the thesis is too shallow, however, every work if unique and is thoroughly evaluated on an individual basis.

You can cite works by using their keys in the bib files, like in this example [10, 11, 23, 24, 4, 5, 17, 1, 3, 6, 2, 7, 15, 18, 16, 12, 22, 15, 13, 21, 20, 14, 19, 9, 8].

The bib file can be created by hand or imported from other applications, such as Mendeley or CrossRef.

Notice that hyperrefs are enabled. This means references (to chapters, sections, figures, tables, algorithms, etc) are links, which can be clicked to navigate through the thesis. Also, backrefs are enabled, which means that references include "cited on page(s)" links.

Chapter 3 Implementation

This chapter contains the essence of your work, what you have done to address your problem, goals, and objectives. In some cases, this part can be split into the description of the method applied and into its implementation. But it can also be all in the same chapter, depending entirely on the nature of the presented work and the preferences of the author(s).

The main learning objective addressed in this part is *F*2, however, it also contributes to other objectives.

It is important to clearly outline what work has been performed within the timeframe of this thesis and what came from previous or related projects. This helps to evaluate individual technical contribution of the work and helps to resolve ambiguities.

Figure 3.1 contains a liquid. Table 3.1 contains some stuff. Algorithm 1 is also shown. Please, make sure that any figure, table, or other float is referenced in the main text!



Figure 3.1: Long caption. This figure shows something.

Table 5.1: Long caption. This is a table.					
		Heading1	Heading2		
Heading3	Heading5	Some stuff in a table.	Some stuff in a table.		
	Heading6	Some stuff in a table.	Some stuff in a table.		

Table 3.1: Long caption. This is a table.

Algorithm 1 Long caption. This is an algorithm. Require: The first input. **Require:** The second input. **Ensure:** The output. 1: First statement. 2: for all Something. do

- if A condition. then 3:
- Statement. 4:
- else if Another condition. then 5:
- Statement. 6:
- 7: else
- Statement. 8:
- end if 9:
- Statement. 10:
- 11: end for

Chapter 4 **Results**

This chapter presents results, that were obtained by applying the method outlined in Chapter 3 to the problem stated in Chapter 1, taking into account previous works, reviewed in Chapter 2.

This chapter is directly targeting learning objective *F3*.

It is important that this chapter must review results of the work in an objective way. It may include objective interpretation of the results, however it should not contain authors reflections or conclusions.

Chapter 5 Conclusions

These are conclusions. Here you can look at the problem, method, results, and reflect on the overall project outcomes, particular objectives and other aspects.

5.1 Review of Project Goals

If you provided clear and detailed goals and objectives in the introductory part of your thesis, then it is a good idea to review them here and outline how (ir if, or to what extent) each of them has been achieved.

5.2 Context

It is important to be able to put your work in the environmental, societal, ethical, and enterprise context. Of course, not all works contribute significantly to each of the aspects, however it is important to provide critical review of your work.

This part helps to address learning objective V4.

5.3 Future Works

In most cases, the completed work open new opportunities. Or it might be that not all possible ways to solve the problem could be explored. In this section you can outline possible directions of future work that you find the most relevant given your knowledge and experiences in this project.

Acronyms

ROS Robot Operating System

References

- Henrik Andreasson. Local Visual Feature based Localisation and Mapping by Mobile Robots. PhD thesis, Örebro University, Department of Technology, 2008. (Cited on page 4.)
- [2] Pontus Bergsten. Observers and controllers for Takagi-Sugeno fuzzy systems. PhD thesis, Örebro University, Örebro University, 2002. (Cited on page 4.)
- [3] Abdelbaki Bouguerra. *Robust Execution of Robot Task-Plans: A Knowledge-based Approach*. PhD thesis, Örebro University, Department of Technology, 2008. (Cited on page 4.)
- [4] Katarina Boustedt. *Flip Chip for High Frequency Applications : Materials Aspects*. PhD thesis, Örebro University, Department of Technology, 2007. (Cited on page 4.)
- [5] Pär Buschka. *An Investigation of Hybrid Maps for Mobile Robots*. PhD thesis, Örebro University, Department of Technology, 2005. (Cited on page 4.)
- [6] Peter Gillström. Alternatives to Pickling; Preparation of Carbon and Low Alloyed Steel Wire Rod. PhD thesis, Örebro University, Department of Technology, 2006. (Cited on page 4.)
- [7] Boyko Iliev. *Minimum-time Sliding Mode Control of Robot Manipulators*. PhD thesis, Örebro University, Department of Technology, 2004. (Cited on page 4.)
- [8] Fredrik Johansson. Evaluating the Performance of TEWA Systems. PhD thesis, Örebro University, School of Science and Technology, 2010. Fredrik Johansson forskar ocksa vid Skövde Högskola, Informatics Research Centre / Fredrik Johansson also does research at the University of Skövde, Informatics Research Centre. (Cited on page 4.)
- [9] Alexander Karlsson. Evaluating Credal Set Theory as a Belief Framework in High-Level Information Fusion for Automated Decision-Making. PhD thesis, Örebro University, School of Science and Technology, 2010. Examining Committee: Arnborg, Stefan, Professor (KTH Royal Institute of Technology), Kjellström, Hedvig, Associate Professor (Docent) (KTH Royal Institute of Technology), Saffiotti, Alessandro, Professor (Örebro University). (Cited on page 4.)
- [10] Sören Larsson. An industrial robot as carrier of a laser profile scanner : Motion control, data capturing and path planning. PhD thesis, Örebro University, Department of Technology, 2008. (Cited on page 4.)
- [11] Kevin LeBlanc. Cooperative Anchoring : Sharing Information about Objects in Multi-Robot systems. PhD thesis, Örebro University, School of Science and Technology, 2010. (Cited on page 4.)

- [12] Malin Lindquist. Electronic Tongue for Water Quality Assessment. PhD thesis, Örebro University, Department of Technology, 2007. (Cited on page 4.)
- [13] Robert Lundh. Robots that Help Each Other : Self-Configuration of Distributed Robot Systems. PhD thesis, Örebro University, School of Science and Technology, 2009. (Cited on page 4.)
- [14] Martin Magnusson. The Three-Dimensional Normal-Distributions Transform : An Efficient Representation for Registration, Surface Analysis, and Loop Detection. PhD thesis, Örebro University, School of Science and Technology, 2009. (Cited on page 4.)
- [15] Magnus Otterskog. *Propagation Environment Modeling Using Scattered Field Chamber*. PhD thesis, Örebro University, Department of Technology, 2006. (Cited on page 4.)
- [16] Henrik Överstam. The Interdependence of Plastic Behaviour and Final Properties of Steel Wire, Analysed by the Finite Element Method. PhD thesis, Örebro University, Department of Technology, 2004. (Cited on page 4.)
- [17] Martin Persson. Semantic Mapping using Virtual Sensors and Fusion of Aerial Images with Sensor Data from a Ground Vehicle. PhD thesis, Örebro University, Department of Technology, 2008. (Cited on page 4.)
- [18] Ola Pettersson. Model-Free Execution Monitoring in Behavior-Based Mobile Robotics. PhD thesis, Örebro University, Department of Technology, 2004. (Cited on page 4.)
- [19] Mohamed Rahayem. Segmentation and Fitting for Geometric Reverse Engineering : Processing data captured by a laser profile scanner mounted on an industrial robot. PhD thesis, Örebro University, School of Science and Technology, 2010. (Cited on page 4.)
- [20] Parivash Ranjbar. Sensing the Environment : Development of Monitoring Aids for Persons with Profound Deafness or Deafblindness. PhD thesis, Örebro University, School of Science and Technology, 2009. (Cited on page 4.)
- [21] Alexander Skoglund. Programming by Demonstration of Robot Manipulators. PhD thesis, Örebro University, School of Science and Technology, 2009. (Cited on page 4.)
- [22] Gustav Tolt. Fuzzy Similarity-based Image Processing. PhD thesis, Örebro University, Department of Technology, 2005. (Cited on page 4.)
- [23] Marco Trincavelli. Gas Discrimination for Mobile Robots. PhD thesis, Örebro University, School of Science and Technology, 2010. (Cited on page 4.)
- [24] Zbigniew Wasik. A Behavior-Based Control System for Mobile Manipulation. PhD thesis, Örebro University, Örebro University, 2005. (Cited on page 4.)