

# This is the title

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## 1 Introduction

This is the introduction.

## 2 Methods

### 2.1 This is a subsection

. This is an equation:

$$m\ddot{x} + c\dot{x} + kx = 0 \tag{1}$$

The equation for spring mass damper is shown in Eqn. 1. We can also write this equation inline by using dollar sign like so,  $m\ddot{x} + c\dot{x} + kx = 0$ .

A quadratic equation

$$x^2 - 5x + 3 \tag{2}$$

A matrix:

$$M = \begin{bmatrix} 1 & 2 \\ 3 & 4 \end{bmatrix}$$

Another matrix

$$\begin{pmatrix} x & x^2 \\ 2x & 3 \end{pmatrix} \tag{3}$$

This is a figure The rowdy figure is shown in Fig. 1 and the important table is shown in Tab. 2.1

This is the first and last reference in this paper [1].

This is **bold**. This is *italic*. **This is red in color**.



Figure 1: This is UTSA rowdy

cell1	cell2	cell3
cell4	cell5	cell6
cell7	cell8	cell9

## References

- [1] Eimei Oyama, Nak Young Chong, Arvin Agah, and Taro Maeda. Inverse kinematics learning by modular architecture neural networks with performance prediction networks. In *Robotics and Automation, 2001. Proceedings 2001 ICRA. IEEE International Conference on*, volume 1, pages 1006–1012. IEEE, 2001.