

International Journal of Humanoid Robotics
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INSTRUCTIONS FOR TYPESETTING MANUSCRIPTS USING COMPUTER SOFTWARE*

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The abstract should summarize the context, content and conclusions of the paper in less than 200 words. It should not contain any references or displayed equations. Typeset the abstract in 8 pt Times roman with baselineskip of 10 pt, making an indentation of 1.5 pica on the left and right margins.

Keywords: Keyword1; keyword2; keyword3.

1. General Appearance

Contributions to the *International Journal of Humanoid Robotics* should be about 15 to 20 printed pages long, but shorter communications and longer reviews will also be considered for publication. Authors are encouraged to have their contribution checked for grammar. American spelling should be used. Abbreviations are allowed but should be spelt out in full when first used. Integers ten and below are to be spelt out. Italicize foreign language phrases (e.g. Latin, French).

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2. Major Headings

Major headings should be typeset in boldface with the first letter of important words capitalized.

2.1. *Sub-headings*

Sub-headings should be typeset in boldface italic and capitalize the first letter of the first word only. Section number to be in boldface roman.

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Sections, sub-sections and sub-subsections are numbered in Arabic. Use double spacing before all section headings, and single spacing after section headings. Flush left all paragraphs that follow after section headings.

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Lists may be laid out with each item marked by a dot:

- item one,
- item two.

Items may also be numbered in lowercase roman numerals:

- (i) item one
- (ii) item two
 - (a) Lists within lists can be numbered with lowercase roman letters,
 - (b) second item.

3. Equations

Displayed equations should be numbered consecutively in each section, with the number set flush right and enclosed in parentheses

$$\mu(n, t) = \frac{\sum_{i=1}^{\infty} 1(d_i < t, N(d_i) = n)}{\int_{\sigma=0}^t 1(N(\sigma) = n) d\sigma}. \quad (1)$$

Equations should be referred to in abbreviated form, e.g. “Eq. (1)”. In multiple-line equations, the number should be given on the last line.

Displayed equations are to be centered on the page width. Standard English letters like x are to appear as x (italicized) in the text if they are used as mathematical symbols. Punctuation marks are used at the end of equations as if they appeared directly in the text.

Theorem 1. *Theorems, lemmas, etc. are to be numbered consecutively in the paper. Use double spacing before and after theorems, lemmas, etc.*

Proof. Proofs should end with □

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Figures are to be inserted in the text nearest their first reference. Figures should be embedded in electronic form from a computer-based drawing package or from high quality scanned images.

Where possible, *vector-based* formats (e.g. .eps, .ps, .pdf) should be used with resolutions of 600 dpi for line-based artwork. Otherwise, *pixel-based* graphics (e.g. .tif, .gif, .jpeg) with resolutions of at least 300 dpi should be used for photographs and complex half-tone images. Images where line-based artwork and half-tone images are used in combination should be at least 300 dpi. When saving images in .jpg format, care should be taken to save using the lowest compression (maximum quality) possible.

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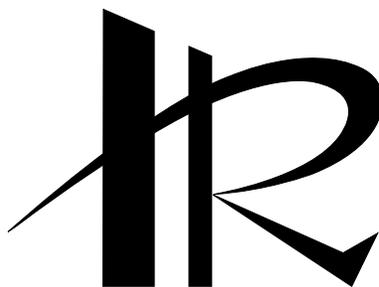


Fig. 1. The journal's logo.

Figures are to be sequentially numbered in Arabic numerals. The caption must be placed below the figure. Typeset in 8 pt Times roman with baselineskip of 10 pt. Use double spacing between a caption and the text that follows immediately.

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5. Tables

Tables should be inserted in the text as close to the point of reference as possible. Some space should be left above and below the table.

Table 1. Comparison of acoustic for frequencies for piston-cylinder problem.

Piston mass	Analytical frequency (Rad/s)	TRIA6- S_1 model (Rad/s)	% Error
1.0	281.0	280.81	0.07
0.1	876.0	875.74	0.03
0.01	2441.0	2441.0	0.0
0.001	4130.0	4129.3	0.16

Note: Table notes

^aTable footnote A

^bTable footnote B

Tables should be numbered sequentially in the text in Arabic numerals. Captions are to be centralized above the tables. Typeset tables and captions in 8 pt Times roman with baselineskip of 10 pt.

If tables need to extend over to a second page, the continuation of the table should be preceded by a caption, e.g. “*Table 2. (Continued)*”

6. References

References in the text are to be numbered consecutively in Arabic numerals, in the order of first appearance. They are to be typed in superscripts after punctuation marks, e.g. “. . . in the statement.³”

References are to be listed in the order cited in the text. Use the style shown in the following examples. For journal names, use the standard abbreviations. Typeset references in 9 pt Times roman.

7. Footnotes

Footnotes should be numbered sequentially in superscript lowercase roman letters.^a

Acknowledgements

This section should come before the References. Funding information may also be included here.

^aFootnotes should be typeset in 8 pt Times roman at the bottom of the page.

Appendix A. Appendices

Appendices should be used only when absolutely necessary. They should come before the References. If there is more than one appendix, number them alphabetically. Equations number occurring in the Appendix is a continuation from the last equation number of the main text

$$\delta x_1 = \frac{\Delta x_1}{M_\eta}, \quad (\text{A.1})$$

$$\delta x_2 = \frac{\Delta x_2}{M_\varphi}, \quad (\text{A.2})$$

in the x_1 and x_2 directions respectively. It is clear in general from Eq. (1) that the scale factors M_η and M_φ cannot simultaneously be integer, so that the size of elementary phase-space cell should be able to take continuously varying values.

References

Journal paper:

1. G. Capi, Y. Nasu, L. Barolli, K. Mitobe and K. Takeda, Application of genetic algorithms for biped robot gait synthesis optimization during walking and going up stairs, *Advanced Robotics* **15**(6) (2001) 675–694.

Authored book:

2. U. Nehmzow, *Mobile Robotics: A Practical Introduction*, 2nd edn. (Springer-Verlag, New York, 2003), pp. 25–27.

Edited book:

3. G. A. Carpenter and S. Grossberg (eds.), *Neural Networks for Vision and Image Processing* (MIT Press, Cambridge, Massachusetts, 1992), pp. 45–60.

Review volume:

4. M. H. Chignell and P. A. Hancock, Horn clause representations in human-machine systems with adaptive control, in *Trends in Ergonomics/Human Factors III*, ed. W. Karwowski (Elsevier, Amsterdam, 1986), p. 76.

Series book:

5. R. M. H. Cheng and R. Rajagopalan, Binary-camera vision for guidance control of the automated guided vehicle, in *Recent Trends in Mobile Robots*, Series in Robotics and Automated Systems, Vol. 11 (World Scientific, New Jersey, 1994), p. 83.

Proceedings:

6. A. Dasgupta and Y. Nakamura, Making feasible walking motion of humanoid robots from human motion capture data, in *IEEE Int. Conf. Robotics and Automation (ICRA)* (IEEE Press, Detroit, USA, 1999), pp. 1044–1049.

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Second-Author is the author of over X technical publications. His/her research interests include Mind topics, Body topics and Application topics (see IJHR's flyer).