

# Bare Demo of IEEEtran.cls for Journals

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**Abstract**—The abstract goes here.

**Index Terms**—IEEEtran, journal, L<sup>A</sup>T<sub>E</sub>X, paper, template.

## I. INTRODUCTION

**T**HIS demo file is intended to serve as a “starter file” for IEEE journal papers produced under L<sup>A</sup>T<sub>E</sub>X using IEEEtran.cls version 1.6 and later. May all your publication endeavors be successful.

mds

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**Michael Shell** Biography text here.

### A. Subsection Heading Here

Subsection text here. Since the rotation of joint  $k$  has no effect on orientations of  $z_1, \dots, z_k$ , it is implied that  $z_k$  is only a function of  $q_1, \dots, q_{k-1}$ . Therefore, each  $T_{ij}$ , for  $i > j$ , is a function of  $q_1, \dots, q_{i-1}$ . It can be shown that if there exist at least  $n - 2$  pairs of adjacent parallel joint axes, then  $T$  is independent of  $q$  making (??) a LTI system.

Now defining the joint torque signal by

$$\tau_J = (M_L + T^T J)\ddot{q} + (C - J\dot{T})\dot{q} + g \quad (1)$$

manipulator dynamics (??) can be rewritten as

1) *Subsubsection Heading Here*: Subsubsection text here.

**John Doe** Biography text here.

## II. CONCLUSION

The conclusion goes here.

### APPENDIX I

#### PROOF OF THE FIRST ZONKLAR EQUATION

Appendix one text goes here.

### APPENDIX II

Appendix two text goes here.

## ACKNOWLEDGMENT

The authors would like to thank...

**Jane Doe** Biography text here.

## REFERENCES

- [1] H. Kopka and P. W. Daly, *A Guide to L<sup>A</sup>T<sub>E</sub>X*, 3rd ed. Harlow, England: Addison-Wesley, 1999.