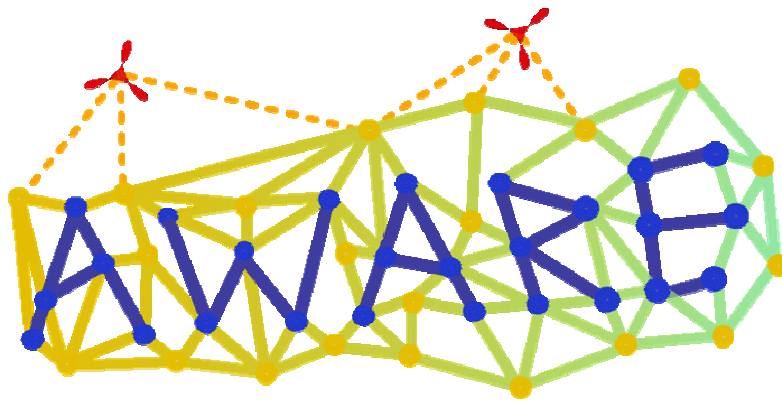


< Document Title >

< optional: subtitle >



Platform for Autonomous self-deploying and
operation of Wireless sensor-actuator networks
cooperating with AeRial objEcts

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1. INTRODUCTION

1.1 PURPOSE AND SCOPE

1.2 DEFINITIONS AND ACRONYMS

Term	Definition
A1	Acronym 1
A2	Acronym 2

2. CHAPTER LEVEL 1

2.1 CHAPTER LEVEL 2

2.1.1 Chapter level 3

2.1.1.1 Chapter level 4

[illegible]

See Figure 1.

See Table 1.

See Section 1.

New methods for multi-robot cooperation are presented in [2].

Text text text text text text text text text text text text:

- Item 1.
 - Item 2.
 - Item 3.

Text text text text text text text text text text text text:

1. Enum 1.
 - a. Enum 2.
 - i. Enum 3.



Figure 1: Figure description



Table 1: Table description.

	k_s	k_0	c_3	c_5
Careful/Sparse	0.432	0.546	0.762	0.749
Careful/Dense	0.543	0.562	0.872	0.786
Aggressive/Sparse	0.875	0.983	0.123	0.342
Aggressive/Dense	0.343	0.874	0.983	0.982



3. REFERENCES

- [1] S. C. Botelho and R. Alami. M+: a scheme for multi-robot cooperation through negotiated task allocation and achievement. In *Proceedings of the IEEE International Conference on Robotics and Automation*, Detroit, 1999.
- [2] B.P. Gerkey and M.J. Mataric. Sold!: Auction methods for multi-robot coordination. *IEEE Transactions on Robotics and Automation*, 18(5):758–768, 2002.