Instructions for preparing an extended abstract for the ECCOMAS Thematic Conference on Multibody Dynamics 2015

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Abstract

Authors are requested to submit an extended abstract of a maximum of two pages (including references and figures) no later than November 28, 2014, to the conference website: http://www.multibody2015.org. The uploaded file must be in the PDF format.

The abstract must be written in English. It must contain the full names, addresses and e-mails of the authors. In case of joint authorship, the name of the speaker who will present the paper at the conference should be underlined. The reference marks can be omitted if all authors are from the same affiliation.

Equations must be numbered consecutively using right flushed Arabic numbers in brackets as shown in Equation (1)

$$\mathbf{M}\ddot{\mathbf{q}} + \mathbf{\Phi}_{\mathbf{q}}^{T}\alpha\left(\ddot{\mathbf{\Phi}} + 2\xi\,\omega\dot{\mathbf{\Phi}} + \omega^2\mathbf{\Phi}\right) = \mathbf{Q} \tag{1}$$

All symbols of the equation should be explained.

Figures and graphs must be included using the same style as shown in Figure 1. The contents of the Figure should be explained in its caption.
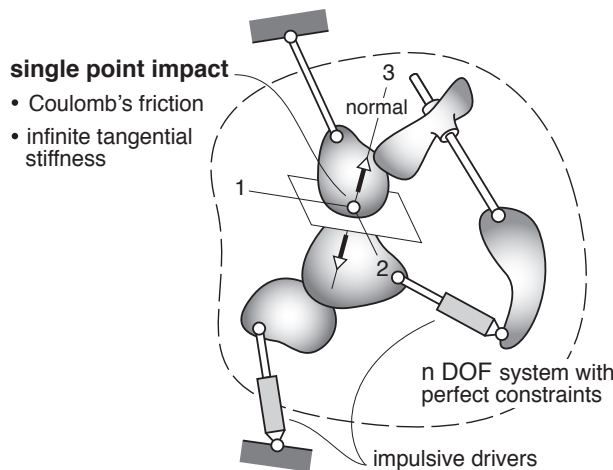

Figure 1: Example of a figure and its caption.

Tables should be included using the same style as shown in Table 1. The contents of the table should be explained in its header.

Table 1: Example of a table and its header.

T11	T12	T13	T14
T21	T22	T23	T24

Number citations consecutively in square brackets. Type the reference list at the end of the abstract following the style shown below, where [1] exemplifies the case of a textbook, [2] is an article in a journal and [3, 4] are articles in conference proceedings.

We very much look forward to welcoming you in Barcelona! Best wishes and the warmest regards from the Organizing Committee of the ECCOMAS Thematic Conference on Multibody Dynamics 2015.

References

[1]   J-C. Samin, P. Fisette. Symbolic Modeling of Multibody Systems. Kluwer Academic Publishers, Dordrecht, 2003.

[2]   J.M. Font-Llagunes, A. Barjau, R. Pàmies-Vilà, J. Kövecses. Dynamic analysis of impact in swing-through crutch gait using impulsive and continuous contact models. Multibody System Dynamics, Vol. 28, No. 3, pp. 257–282, 2012.

[3]   R. Seifried, W. Schiehlen. Computational analysis and experimental investigations of impacts in multibody systems. In P. Eberhard (Ed.) IUTAM Symposium on Multiscale Problems in Multibody System Contacts, pp. 269–280, Springer, 2007.

[4]   F. Naets, R. Pastorino, J. Cuadrado, W. Desmet. Use of sub-system global model parameterization models in extended Kalman filtering for online coupled state/force estimation. In Z. Terze (Ed.) Proceedings ECCOMAS Thematic Conference on Multibody Dynamics, pp. 391–400, Zagreb, Croatia, 2013.