

Quick Markdown Reference

Beamer presentation with Pandoc

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Available at

- gitlab.laas.fr/gsaurel/talks : howto.md
- homepages.laas.fr/gsaurel/howto.pdf

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1 First Part

2 Second Part

First Part

How-to Slides

Formating: *em* **bold** mono ~~strikethrough~~ text_{subscript}^{superscript}

- eggs
- butter
- ham

- eggs
 - butter
 - ham
-
- 1 Thing
 - 2 Do
 - 3 Words
 - 4 You

```
#!/usr/bin/env python3
from math import pi as  $\pi$ 

class Circle:
    """Define a circle from its radius."""
    def __init__(self, r):
        # such maths, very difficult, wow
        if r < 0:
            raise AttributeError('wrong radius')
        self.P = 2 *  $\pi$  * r
        self.S =  $\pi$  * r ** 2
```

Second Part

$$\vec{\nabla} \cdot \vec{\mathcal{E}} = \frac{\rho}{\epsilon_0}$$

$$\vec{\nabla} \times \vec{\mathcal{E}} = -\frac{\partial \vec{\mathcal{B}}}{\partial t}$$

$$\vec{\nabla} \cdot \vec{\mathcal{B}} = 0$$

$$\vec{\nabla} \times \vec{\mathcal{B}} = \mu_0 \vec{\mathcal{J}} + \epsilon_0 \frac{\partial \vec{\mathcal{E}}}{\partial t}$$

Right	Left	Default	Center
12	12	12	12
123	123	123	123
<i>1</i>	1	1	\pm



Figure 1: Doc

Look ! The trees... They're moving !

— Saurel, Taïx, and Laumond (2016)

Saurel, Guilhem, Michel Taïx, and Jean-Paul Laumond. 2016. “transHumUs: A poetic experience in mobile robotics.” In *IEEE International Conference on Robotics and Automation (ICRA)*, 2908–14. Stockholm, Sweden.
<https://doi.org/10.1109/ICRA.2016.7487455>.