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***Abstract*—Autonomous underwater robots often rely on visual input for decision making. However, due to many factors such as light refraction and particles in the water, images are often times very noisy. We propose a method using Generative Adversarial Networks (GANs) to denoise underwater images, and show that these images provide both increased accuracy for an underwater tracking algorithm, as well as a more visually appealing image.**

I. Introduction

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II. Related Work

III. Technical Approach

IV. Conclusion

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Acknowledgment

The authors would like to thank...

References

[1] H. Kopka and P. W. Daly, *A Guide to LaTeX*, 3rd ed. Harlow, England: Addison-Wesley, 1999.