Bare Demo of IEEEtran.cls for Conferences

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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

This demo file is intended to serve as a "starter file" for IEEE conference papers produced under LaTeX using IEEEtran.cls version 1.8 and later. I wish you the best of success.

mds

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A. Subsection Heading Here

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II. Conclusion

The conclusion goes here.

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.