RAL/ICRA Paper Related Work

Project Scope

- Target conf:
  - Robotics and Automation Letters
  - International Conference on Robotics and Automation
- Primary research areas:
  - Quaternion-based EKF
  - Quaternion-based pose estimation
  - Vision-based navigation
  - Depth estimation from vision
  - Visual feature tracking
- Secondary research areas:
  - Visual inertial odometry

Todo

- [ ] Find RAL and ICRA papers on
- [ ] Summarize papers
- [ ] Work on the Related Works section
- [ ] Mind-Map paper structure
- [ ] Mind-Map research threads and methods

RAL Paper Structure

- Abstract
- Introduction
- Related Work
- Proposed Method
- Experiments
- Conclusion and Future Work

ICRA Paper Structure

- Abstract
- Introduction
- Related Work
- Proposed Method
- Experiments
- Conclusion and Future Work

Papers

Paper Entry Template

- [ ] 001 - ([CONF]) [title]

Other Papers

- [ ] 001 - ([CONF]) [title]

2022

- [ ] 001 - (RAL) Kineverse A Symbolic Articulation Model Framework for Model-Agnostic Mobile Manipulation

2021

- [ ] 001 - (ICRA) DOT Dynamic Object Tracking for Visual SLAM

2020

- [ ] 001 - (RAL) Vision-Based Dynamic Virtual Fixtures for Tools Collision Avoidance in Robotic Surgery

Summaries

Summary Template

001 - ([CONF]) [title]

- code
- Abstract:
- Main Contribs:
  - XYZ:
- Intro:
  - Contribs:
- Related work: see mind-map.
- Method: Experiments and Results:
- Sensors:
- Hardware:
- Sensor-Fusion:
- Dataset details:
- Additional details:

2022 Summaries

001 - (RAL) Kineverse A Symbolic Articulation Model Framework for Model-Agnostic Mobile Manipulation

- code
- Abstract:
- Main Contribs:
  - XYZ:
- Intro:
  - Contribs:
- Related work: see mind-map.

- Method: Experiments and Results:
- Sensors:
- Hardware:
- Sensor-Fusion:
- Dataset details:
- Additional details:

2021 Summaries

001 - (ICRA) DOT Dynamic Object Tracking for Visual SLAM

- code
- Abstract:
- Main Contribs:
    - XYZ:
- Intro:
    - Contribs:
- Related work: see mind-map.
- Method: Experiments and Results:
- Sensors:
- Hardware:
- Sensor-Fusion:
- Dataset details:
- Additional details: