

# A clustered of SOTA Paper

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## CONTENTS

<b>[Chapter: 1] Template</b>	2
<b>I Introduction</b>	2
I-A Definitions . . . . .	2
I-A1 Levels . . . . .	2
<b>II Motivation</b>	2
<b>III Background</b>	2
III-A Types of visual grasping . . . . .	2
III-A1 6-D pose grasping . . . . .	2
III-B Simultaneous Localization and Map- ping (SLAM) . . . . .	2
III-B1 Kimera . . . . .	2
<b>IV Our Methods</b>	2
IV-A Conceptual Architecture . . . . .	2
IV-A1 Problem Definition and In- put Space . . . . .	2
<b>V Implementation</b>	2
<b>References</b>	3

## Chapter 1: Template

**[Last edit: Sept, 2022]** *Abstract*—This document describes the most common article elements and how to use the IEEEtran class with L<sup>A</sup>T<sub>E</sub>X to produce files that are suitable for submission to the Institute of Electrical and Electronics Engineers (IEEE). IEEEtran can produce conference, journal and technical note (correspondence) papers with a suitable choice of class options.

*Index Terms*—Class, IEEEtran, L<sup>A</sup>T<sub>E</sub>X, paper, style, template, typesetting.

### I. INTRODUCTION

**I**NTRODUDUCTION starts here

#### A. Definitions

Here, we will define [1] as in Figure 1.



Fig. 1. A Caption

#### 1) Levels:

**Level.1** ABC

**Level.2** Something

**Level.3** Repeat **Level.2**

### II. MOTIVATION

### III. BACKGROUND

**Here we will write about backgrounds**

#### A. Types of visual grasping

**surveys on different types of grasping approacches**

#### 1) 6-D pose grasping:

#### B. SLAM

#### 1) Kimera:

### IV. OUR METHODS

#### A. Conceptual Architecture

#### 1) Problem Definition and Input Space:

$$\hat{\xi} = \begin{bmatrix} \hat{\omega} & v \\ 0 & 0 \end{bmatrix}, \quad \hat{\omega} = \begin{bmatrix} \omega_1 \\ \omega_2 \\ \omega_3 \end{bmatrix}^{\wedge} = \begin{bmatrix} 0 & -\omega_3 & \omega_2 \\ \omega_3 & 0 & -\omega_1 \\ -\omega_2 & \omega_1 & 0 \end{bmatrix} \quad (1)$$

### V. IMPLEMENTATION

## GLOSSARY

**SLAM** Simultaneous Localization and Mapping. 1, 2

**SOTA** State-Of-The-Art. 1

## REFERENCES

- [1] “Friction is preferred over grasp configuration in precision grip grasping,” <https://journals.physiology.org/doi/epdf/10.1152/jn.00021.2021>.