

A clustered of SOTA Paper

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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^AT_EX 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^AT_EX, paper, style, template, typesetting.

I. INTRODUCTION

INTRODUDUCTION starts here

A. Definitions

Here, we will define [1] as in Figure 2.



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

Chapter 2: Template2

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Index Terms—Class, IEEEtran, L^AT_EX, paper, style, template, typesetting.

VI. INTRODUCTION

INTRODUDUCTION starts here

A. Definitions

Here, we will define [1] as in Figure 2.



Fig. 2. A Caption

1) Levels:

Level.1 ABC

Level.2 Something

Level.3 Repeat **Level.2**

VII. MOTIVATION

VIII. 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:

IX. OUR METHODS

A. Conceptual Architecture

1) Problem Definition and Input Space:

$$\hat{\xi} = \begin{bmatrix} \hat{\omega} & v \\ 0 & 0 \end{bmatrix}, \quad \hat{\omega} = \begin{bmatrix} \omega_1 \\ \omega_2 \\ \omega_3 \end{bmatrix}^{\wedge} = \begin{bmatrix} 0 & -\omega_3 & \omega_2 \\ \omega_3 & 0 & -\omega_1 \\ -\omega_2 & \omega_1 & 0 \end{bmatrix} \quad (2)$$

X. IMPLEMENTATION

GLOSSARY

SLAM Simultaneous Localization and Mapping. 1–3

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>.