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 LaTeX 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, LaTeX, 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: Template

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VI. Introduction

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Fig. 2. A Caption

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X. 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.