Table 2. Identified works

Category	Title
SA-HITL	A Constraint-based Flight Control System Architecture for UAVs using the iTaSC Framework
	A robotic shared control teleoperation method based on learning from demonstrations
	Assisted Control for Semi-Autonomous Power Infrastructure Inspection using Aerial Vehicles
	Human–Robot Shared Control Based on Locally Weighted Intent Prediction for a Teleoperated Hydraulic Manipulator System
	Human-robot shared control system based on 3D point cloud and teleoperation
	Inspection of Pole-Like Structures Using a Visual-Inertial Aided VTOL Platform with Shared Autonomy
	Occlusion-Free Visual Servoing for the Shared Autonomy Teleoperation of Dual-Arm Robots
	Unobtrusive and assistive obstacle avoidance for tele-operation of ground vehicles
	Vertical infrastructure inspection using a Quadcopter and shared autonomy control
	VFH+ based shared control for remotely operated mobile robots
SA-HITL	A Haptic Shared-Control Architecture for Guided Multi-Target Robotic Grasping
	An assisted telemanipulation approach: combining autonomous grasp planning with haptic cues
	Enhancing Bilateral Teleoperation using Camera-Based Online Virtual Fixtures Generation
	Human-in-the-loop Fabrication of 3D Surfaces with Natural Tree Branches
	Method for generating real-time interactive virtual fixture for shared teleoperation in unknown environments
	Model-based telerobotic control with virtual fixtures for satellite servicing tasks
	Motion visualization and human-robot shared control for robotic excavators
	Semi-Autonomous Control of Leader-Follower Excavator using Admittance Control for Synchronization and Autonomy
	Shared Control in Robot Teleoperation With Improved Potential Fields
	Shared Teleoperation for Nuclear Plant Robotics Using Interactive Virtual Guidance Generation and Shared Autonomy Approaches
	UAV Haptic Interface for Dynamic Obstacle Avoidance
	Vision Based Virtual Fixture Generation for Teleoperated Robotic Manipulation
	Visual and force-feedback guidance for robot-assisted interventions in the beating heart with real-time MRI
HI-HITL	A Closed-Loop Shared Control Framework for Legged Robots
	Affordance-Based Grasping and Manipulation in Real World Applications
	An Intention Guided Hierarchical Framework for Trajectory-based Teleoperation of Mobile Robots
	Assistive grasping with an augmented reality user interface
	Autonomous Assistance for Versatile Grasping with Rescue Robots
	Interactive and Immersive Process-Level Digital Twin for Collaborative Human–Robot Construction Work
	Interactive Scene Segmentation for Efficient Human-in-the-Loop Robot Manipulation
	Non-Prehensile Manipulation in Clutter with Human-In-The-Loop
	Semi-Autonomous Teleoperation via Learning Non-Prehensile Manipulation Skills
	Template-Based Manipulation in Unstructured Environments for Supervised Semi-Autonomous Humanoid Robots
	ViTa: Visual Task Specification Interface for Manipulation with Uncalibrated Visual Servoing
HI-HOTL	A paced shared-control teleoperated architecture for supervised automation of multilateral surgical tasks
	A Probabilistic Shared-Control Framework for Mobile Robots
	A Shared-Autonomy Approach to Goal Detection and Navigation Control of Mobile Collaborative Robots
	Adaptive Compliant Skill Learning for Contact-Rich Manipulation With Human in the Loop
	An Electromyography Based Shared Control Framework for Intuitive Robotic Telemanipulation
	Collaborative Welding and Joint Sealing Robots With Haptic Feedback
	Guidance Priority Adaptation in Human-Robot Shared Control
	Human-in-the-loop Robotic Grasping using BERT Scene Representation
	Job planning and supervisory control for automated earthmoving using 3D graphical tools
	Shared planning and control for mobile robots with integral haptic feedback
	Teleoperation of Semi-autonomous Robots Through Uncertain Environments
	Trajectory-Based Skill Learning for Overhead Construction Robots Using Generalized Cylinders with Orientation
RI-HOTL	A Blended Human-Robot Shared Control Framework to Handle Drift and Latency
	A Hierarchical Reinforcement Learning Based Control Architecture for Semi-Autonomous Rescue Robots in Cluttered Environments
	A Learning-Based Semi-Autonomous Controller for Robotic Exploration of Unknown Disaster Scenes While Searching for Victims
	A Semi-Autonomous Tele-Impedance Method based on Vision and Voice Interfaces
	Autonomy infused teleoperation with application to brain computer interface controlled manipulation
	Failure Recovery with Shared Autonomy
	Human–Robot Shared Control for Path Generation and Execution
	Investigating Human-Robot Teams for Learning-Based Semi-autonomous Control in Urban Search and Rescue Environments
	Modulating Human Input for Shared Autonomy in Dynamic Environments
	Online Replanning With Human-in-the-Loop for Non-Prehensile Manipulation in Clutter — A Trajectory Optimization Based Approach
	Physical Human-Robot Interaction (pHRI) in 6 DOF with Asymmetric Cooperation
	Potential Hazard-Aware Adaptive Shared Control for Human-Robot Cooperative Driving in Unstructured Environment
	Seeking Human Help to Manage Plan Failure Risks in Semi-Autonomous Mobile Manipulation
	Shared Control With Efficient Subgoal Identification and Adjustment for Human–Robot Collaborative Tasks
	Subgoal Learning via Operator Command Quantification for Human-Machine Shared Control Task Modeling
	Task Learning, Intent Prediction, and Adaptive Blended Shared Control With Application to Excavators
	The Search for Survivors: Cooperative Human-Robot Interaction in Search and Rescue Environments using Semi-Autonomous Robots
	To ask for help or not to ask: A predictive approach to human-in-the-loop motion planning for robot manipulation tasks
	Visual-based Assistive Method for UAV Power Line Inspection and Landing