

cases	doc_1		doc_2		decision	id
			authors	<ul style="list-style-type: none">Sulabh KumraChristopher Kanan	DUPLICATES	177
	authors	<ul style="list-style-type: none">Kumra, S.Kanan, C.	title	Robotic Grasp Detection using Deep Convolutional Neural Networks		
	publication_date	2017-01-01 00:00:00	publication_date	2016-11-24 00:07:39+00:00		
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	doi	10.1109/iros.2017.8202237	doi			
	urls	<ul style="list-style-type: none">http://xplorestaging.ieee.org/ielx7/8119304/8202121/08202237.pdf?arnumber=8202237http://dx.doi.org/10.1109/iros.2017.8202237	urls	<ul style="list-style-type: none">http://arxiv.org/pdf/1611.08036v4http://arxiv.org/abs/1611.08036v4http://arxiv.org/pdf/1611.08036v4		
	id	id-3846317084952049630	id	id6654265446094212297		
	abstract		abstract	Deep learning has significantly advanced computer vision and natural language processing. While there have been some successes in robotics using deep learning, it has not been widely adopted. In this paper, we present a novel robotic grasp detection system that predicts the best grasping pose of a parallel-plate robotic gripper for novel objects using the RGB-D image of the scene. The proposed model uses a deep convolutional neural network to extract features from the scene and then uses a shallow convolutional neural network to predict the grasp configuration for the object of interest. Our multi-modal model achieved an accuracy of 89.21% on the standard Cornell Grasp Dataset and runs at real-time speeds. This redefines the state-of-the-art for robotic grasp detection.		
	versions		versions			