

OD-LSTM: An Efficient Network For Named Entity Recognition

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Abstract

With the risen use of AI application, we need to understand some specific type of message from user's query. Named Entity Recognition(NER) is a basic task for that use. Gazette is very useful when doing NER, however, most of the current method use it in word embedding format, which will bring out the case, we need to retrain model when the word in gazette is greatly changed. In this paper, we propose a conception, called Outer Dictionary(OD) LSTM, which means to use the outer type info of gazette for each word, without using the specific word. Experiments shows it useful when doing NER task, and achieve a great improvement on task with which gazette is heavily depended on.

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\setlength{\pdfpagewidth}{8.5in}
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% Add additional packages here, but check
% the list of disallowed packages
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\title{Title}\\
\author{\{Author 1 \ and Author 2\\
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<code>\addtolength</code>	<code>\baselinestretch</code>	<code>\belowcaption</code>	<code>\belowdisplay</code>
<code>\break</code>	<code>\clearpage</code>	<code>\clip</code>	<code>\columnsep</code>
<code>\float</code>	<code>\input</code>	<code>\input</code>	<code>\linespread</code>
<code>\newpage</code>	<code>\pagebreak</code>	<code>\renewcommand</code>	<code>\setlength</code>
<code>\text height</code>	<code>\tiny</code>	<code>\top margin</code>	<code>\trim</code>
<code>\vskip{-</code>	<code>\vspace{-</code>		

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<code>authblk</code>	<code>babel</code>	<code>caption</code>	<code>cjk</code>
<code>dvips</code>	<code>epsf</code>	<code>epsfig</code>	<code>euler</code>
<code>float</code>	<code>fullpage</code>	<code>geometry</code>	<code>graphics</code>
<code>hyperref</code>	<code>layout</code>	<code>linespread</code>	<code>lmodern</code>
<code>maltepaper</code>	<code>natbib</code>	<code>navigator</code>	<code>pdfcomment</code>
<code>psfig</code>	<code>pstricks</code>	<code>tlenc</code>	<code>titlesec</code>
<code>tocbind</code>	<code>ulem</code>		

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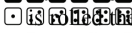
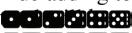
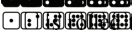
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Address line \\ ... \\ Address line}
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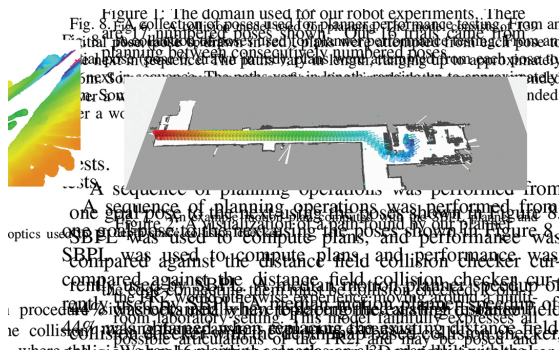


Figure 1: The domain used for our robot experiments. There are 1000 points in the environment, and the path is shown in yellow. The path is shown in yellow, and the environment is shown in gray. The path is shown in yellow, and the environment is shown in gray. The path is shown in yellow, and the environment is shown in gray.

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```
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```
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```

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```
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Thank you for reading these instructions carefully. We look forward to receiving your electronic files!