Using Simulation and Domain Adaptation to Improve Efficiency of Deep Robotic Grasping

☑ 10-20%	☑
☑ 20-40%	☐
☑ 40-60%	☐
☑ 60-80%	☐
☑ 80-100%	☐
☰ Keywork	GraspGan
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☷ 論文性質	sim2real

1.A. Deep Vision-Based Robotic Grasping 最後段

> When trained on the entire real dataset, the best CNN used inthe approach outlined above achieved successful grasps 67:65% of the time. Levineet al. [6] reported an additional increase to 77:18% from also including 2.7 million images from a different robot. We excluded this additional dataset for the sake of a more controlled comparison, so as to avoid additional confounding factors due to domain shift within the real-world

> data.Startingfrom theKuka dataset, our experiments study the effect of adding simulated data and ofreducing the number of real world data points by taking subsets of varying size (down to only 93.841 real world images, which is 1% of the original set).

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