Supplementary Material - ORacle

Table 1. Detailed quantitative results of ORacle-MV-T for scene graph generation.

Relation	*Assisting*	*Cementing*	*Cleaning*	*CloseTo*	*Cutting*	*Drilling*	*Hammering*	*Holding*	*LyingOn*	*Operating*	*Preparing*	*Sawing*	*Suturing*	*Touching*	*Macro Avg*
Prec	0.62	0.96	0.94	0.96	0.98	0.94	0.91	0.87	1.00	0.78	0.88	0.96	1.00	0.78	0.90
Rec	0.89	1.00	0.81	0.95	0.72	1.00	0.98	0.90	1.00	0.99	0.89	1.00	0.96	0.72	0.92
F1	0.73	0.98	0.87	0.95	0.83	0.97	0.95	0.88	1.00	0.87	0.89	0.98	0.98	0.75	0.91

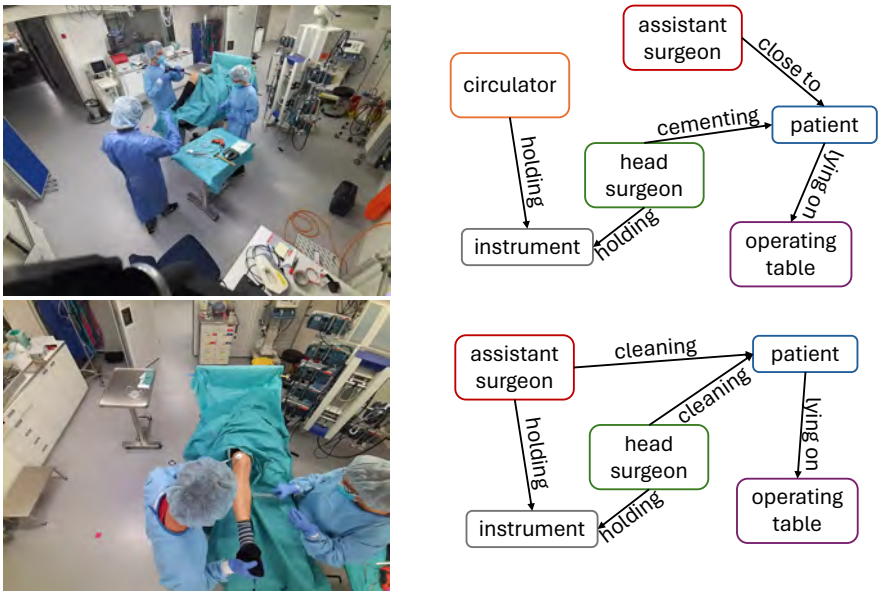

Fig. 1. Result of ORacle-MV-T on a cementing and a cleaning scene. Scene graphs are simplified for readability. Both results are correct.

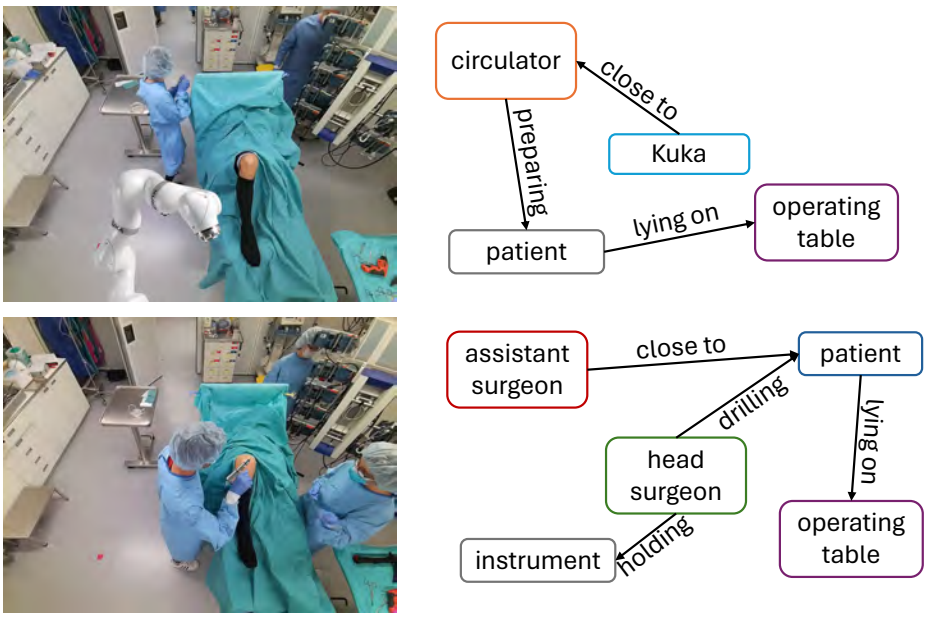

Fig. 2. Result of ORacle-adapt-vis (upper) and ORacle-adapt-text (lower) on two additional examples from our adaptability benchmark. Scene graphs are simplified for readability. Both the Kuka robot and the drilling relation with a visually different drill are correctly recognized.