

389 Appendix A Grasp Visualization

390 In this section, we display the grasps predicted by our *Robust-Grasp* model and the baselines for the
 391 *Real-LCA* experiment reported in Section 4. The grasps are evaluated on a set of novel objects in
 392 three unseen environments and the prediction with the highest grasp success probability is plotted.
 393 While our model is able to generalize across all the environments, the model trained on *Lab-Baxter*
 394 dataset is adversely affected by background patterns. For instance, it is confident in trying to grasp
 395 the leaf patterns in the carpet. It is noteworthy that the *Lab-Baxter* dataset was collected on a single
 396 curated table-top environment. The *DexNet* model on the other hand produced several precise grasps
 397 but suffers with poor depth sensing, especially in the presence of natural light and uneven surfaces.
 398 For the third environment, the sampled grasps were not even on top of the objects.

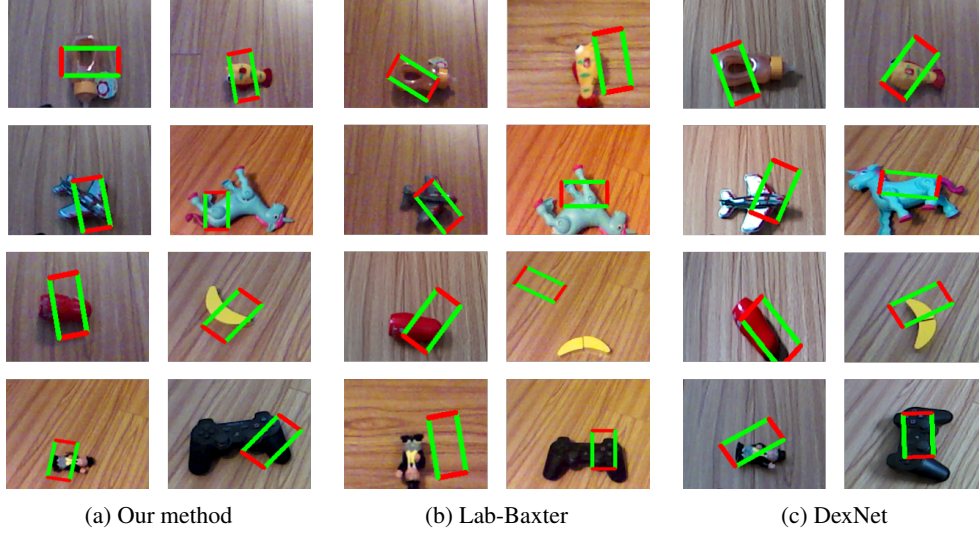


Figure 5: Grasp visualization in 1st testing environment

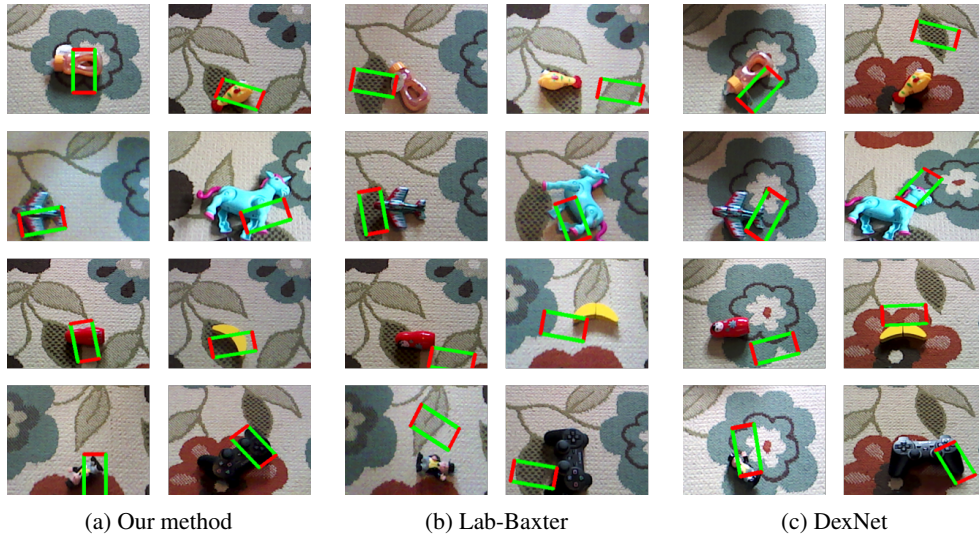


Figure 6: Grasp visualization in 2nd testing environment

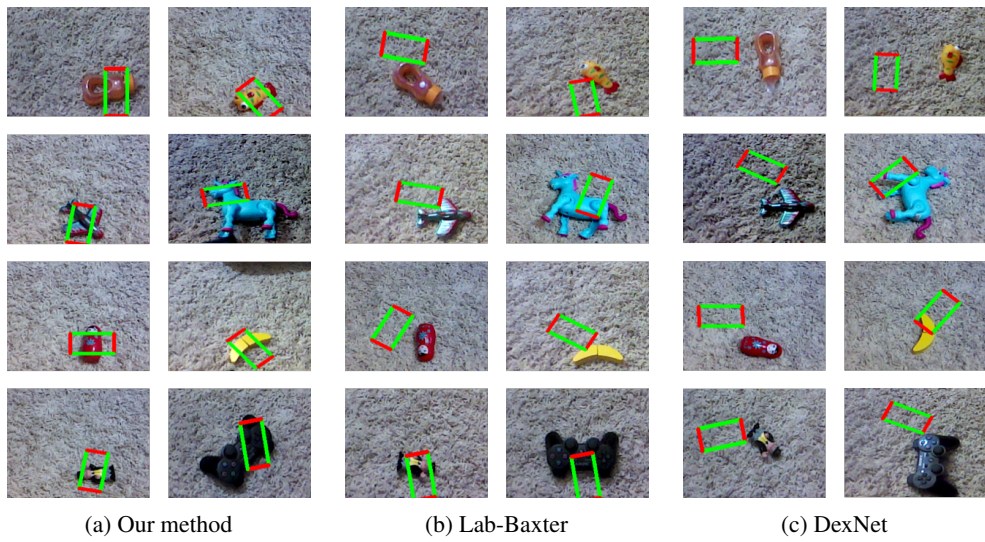


Figure 7: Grasp visualization in 3rd testing environment