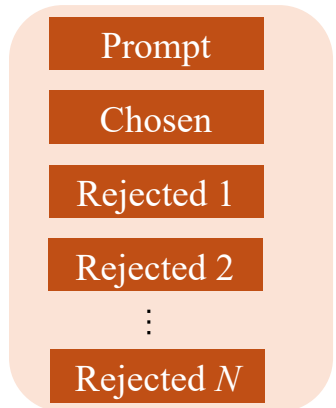


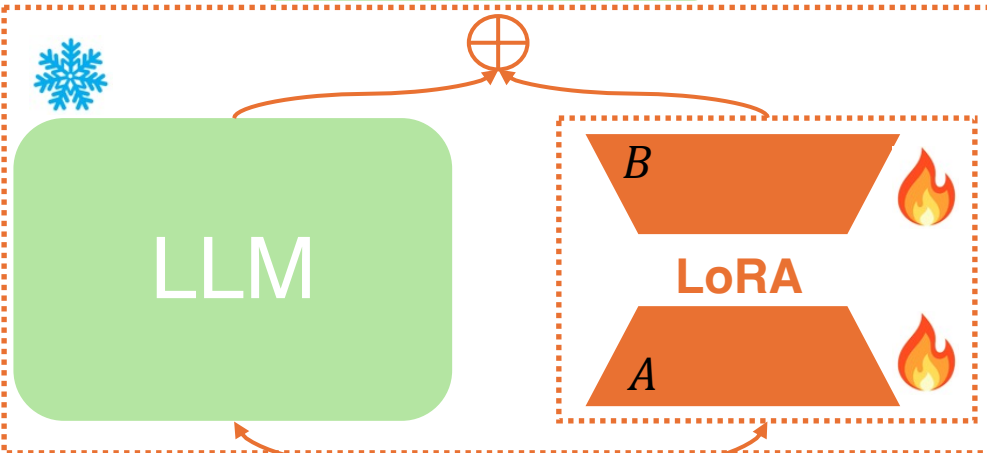
Multi-PrefDrive

$$P(y_1 > y_2 > \dots > y_i > \dots > y_N) = \prod_{i=1}^N \frac{\exp(s_i)}{\sum_{j=i}^N \exp(s_j)}$$

Multi-Preference Dataset



Plackett-Luce
Preference Fine-
Tuning



Q-Former



Driving Prompts

RGB Images

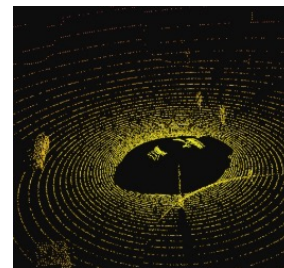
Point Clouds

Action $a \in \mathcal{A}$

Autonomous Driving Scenario



RGB Image



LiDAR

+

Navigation Prompts



Turn left at the next intersection

Driver Navigation Prompt

$$s = (V_t, E_t, O_t, R_t, N_t)$$