

## Decode

# DeepScenario

```
<objectRef objectRef="Ego0"/>
<WayPoint timeStamp="1">
  <DvnamicParameters>
    <Speed speed="0.25"/>
    <Velocity velocityX="-0.0" velocityY="-0.25"
        velocityZ="-0.0"/>
    <AngularVelocity angularVelocityX="-0.001"</pre>
        angularVelocityY="-0.0" angularVelocityZ="0.001"/>
  </DvnamicParameters>
  <GeographicParameters>
    <ObjectPosition positionX="-201.879" positionY="10.27"</p>
        positionZ="217.72"/>
    <ObjectRotation rotationX="0.01" rotationY="180"
        rotationZ="-0.004"/>
  </GeographicParameters>
</WayPoint>
```



Road 🔼

### Weather 🌤

```
"timestamp 1": {
 "Ego0": {
  "position": {
   "x": -201.879.
    "y": 10.27,
   "z": 217.72
  "rotation": {...},
  "velocity": {...},
  "angular velocity": {...}
 "NPC0": {...}
```

"timestamp 2": {...},

"timestamp\_7": {...}



### Parse

Insert



#### (3) **Prompt**

**System Message** 

### **Scenario Description**

Road Weather

#### Timestamp 1

At 0.0 seconds: The 'position' of Ego0 is (-201.879, 10.27, 217.72).

The 'rotation' of Ego0 is ... The 'position' of NPC0 is ...

#### Timestamp 2

At 0.5 seconds: The 'position' of Ego0 is ... The 'position' of NPC0 is ...

#### Timestamp 7

At 3.0 seconds: The 'position' of Ego0 is ... The 'position' of NPC0 is ...

Query



**Output** 

Input

Large

Language

Model

# **Evaluation Output**

At 0.0 seconds: The scenario starts with Ego0 and NPC0 at rest, which is realistic ... At 0.5 seconds: Both Ego0 and NPC0 start to move, and their movements are smooth and coherent with the rainy and night weather conditions

The scenario is realistic as the movements of both Ego0 and NPCO are consistent with the rainy and night weather conditions throughout the entire duration ...

Realistic: True ...