



NexusAD: Exploring the Nexus for Multimodal Perception and Comprehension of Corner Cases in Autonomous Driving

Track 1 | Corner Case Scene Understanding

Trustworthy Visual Intelligence Group

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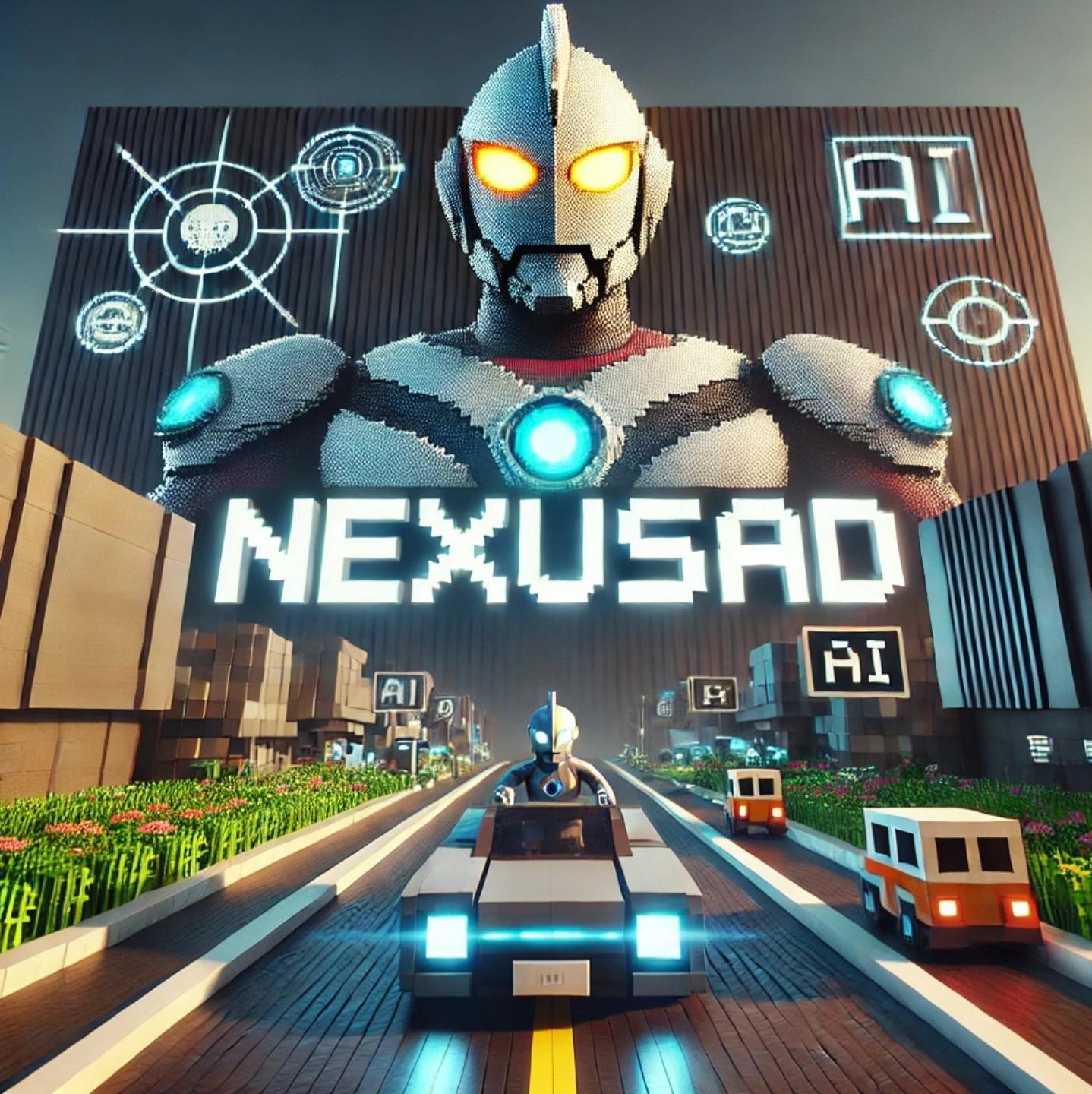
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Workshop W-CODA

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Outline

- Dataset & Tasks
- Challenge
- Method
- Analysis
- Results

/01 Dataset & Tasks

Introduction

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Task1: General Perception

```
vehicles:{  
    vehicles1_description: Red SUV directly in  
    front of the ego car, in the same lane ...,  
    vehicles1_explanation: The red SUV's position  
    and movement will directly affect the ego  
    car's speed ...  
    ...  
},  
vulnerable_road_users:{}  
traffic signs:{  
    traffic sign_description: There is a 'no  
    parking' sign on the right side ...,  
    traffic sign_explanation: This sign does not  
    immediately influence driving behavior, but  
    indicates parking restrictions ...,  
},  
traffic lights:{...},  
...
```



Task2: Regional Perception

```
1: {description and explanation: This is a  
    traffic sign indicating no parking or  
    stopping on the side of the road. It  
    influences the driving behavior by ...,  
    box: [1225,496,1355,719],  
    category_name: traffic_sign  
},  
2: {description and explanation: This is a  
    traffic cone, often used to guide traffic  
    or to signal an area of ...,  
    box: [1023,492,1110,677],  
    category_name: traffic_cone  
}
```



Task3: Driving Suggestions

Maintain a safe following distance from the red SUV ahead as it dictates the pace of traffic. Adhere to the 60 km/h speed limit as indicated by the traffic sign. Stay alert for any unexpected movements from the bus and parked bicycles to the right. Caution should be exercised due to the traffic cone on the right, suggesting a potential road hazard or construction, although it does not presently affect the drivable path.

Task1: General Perception

```
vehicles:{  
    vehicles1_description: A white police car  
    parked on the side of the road ...,  
    vehicles1_explanation: This police car  
    indicates a potential road incident ...  
    ...  
},  
vulnerable_road_users:{}  
traffic signs:{  
    traffic sign_description: A 'No Entry' sign  
    for buses visible on the left side of the  
    road ...,  
    traffic sign_explanation: Informs that buses  
    are not permitted to enter the road ahead ...  
},  
traffic lights:{...},  
...
```



Task2: Regional Perception

```
1: {description and explanation: This is a  
    traffic sign with a symbol indicating  
    that buses are not allowed. It informs  
    drivers of certain types ...,  
    box: [33,268,287,716],  
    category_name: traffic_sign  
},  
2: {description and explanation: This object  
    is a bus that is currently on the road,  
    actively being operational in traffic ...,  
    box: [804,261,974,497],  
    category_name: bus  
}
```



Task3: Driving Suggestions

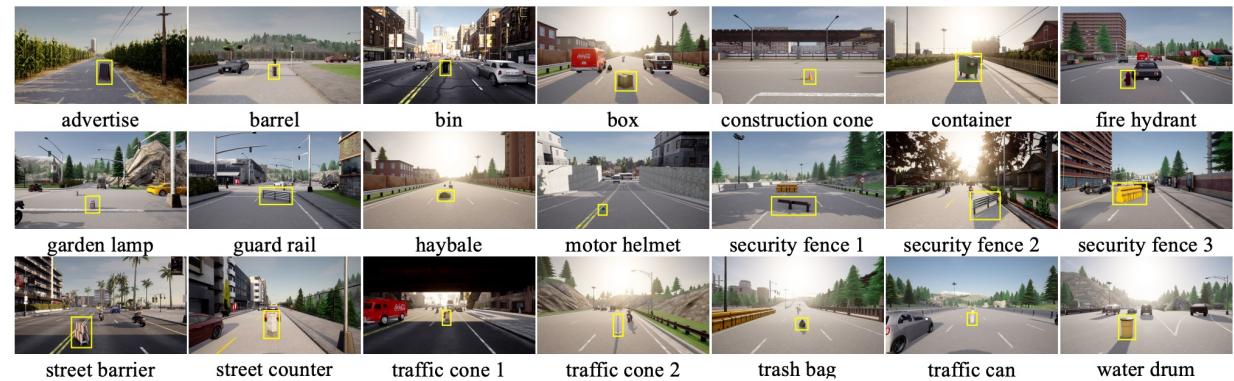
Maintain a safe following distance from the bus ahead, and be prepared to adapt speed or stop if necessary. Stay alert for potential maneuvers from vehicles in the adjacent lanes and maintain a constant check on rear-view mirrors for situational awareness. The road is narrowed by barriers on the right side, so ensure safe lane positioning away from them. The 'No Entry' sign for buses may not be applicable to the ego car but be aware of any buses attempting to leave the lane due to this restriction.

This competition is dedicated to enhancing multimodal perception and comprehension capabilities of MLLMs for autonomous driving, focusing on the **General Perception**, **Regional Perception**, and **Driving Suggestions**.

[A] Li Yanze et al., Automated evaluation of large vision-language models on self-driving corner cases, in *arXiv preprint: 2404.10595*, 2024.



Varied Scenes



Diverse Objects



Novel class



Novel instance

Varied Scenes



Obstacles appear at different distances.



Different road surfaces.



Different lighting and weather conditions..



Anomalies can appear everywhere in the image.



Anomalies widely differ in size.



Wide variety of environments.

Small Objects

Contextual Anomaly

[A] Li Kaican et al., Coda: A real-world road corner case dataset for object detection in autonomous driving, in ECCV, 2022.

/02 Regional Perception via Vision-Language Models

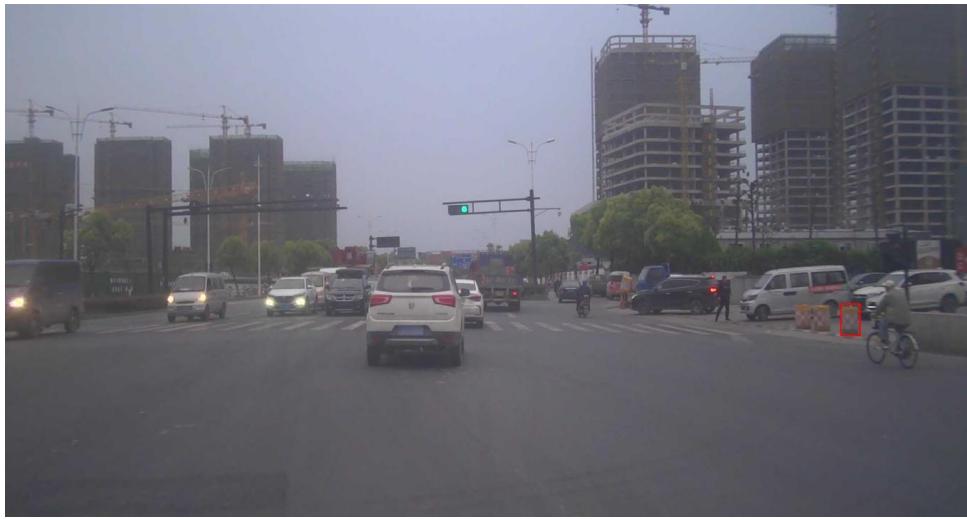
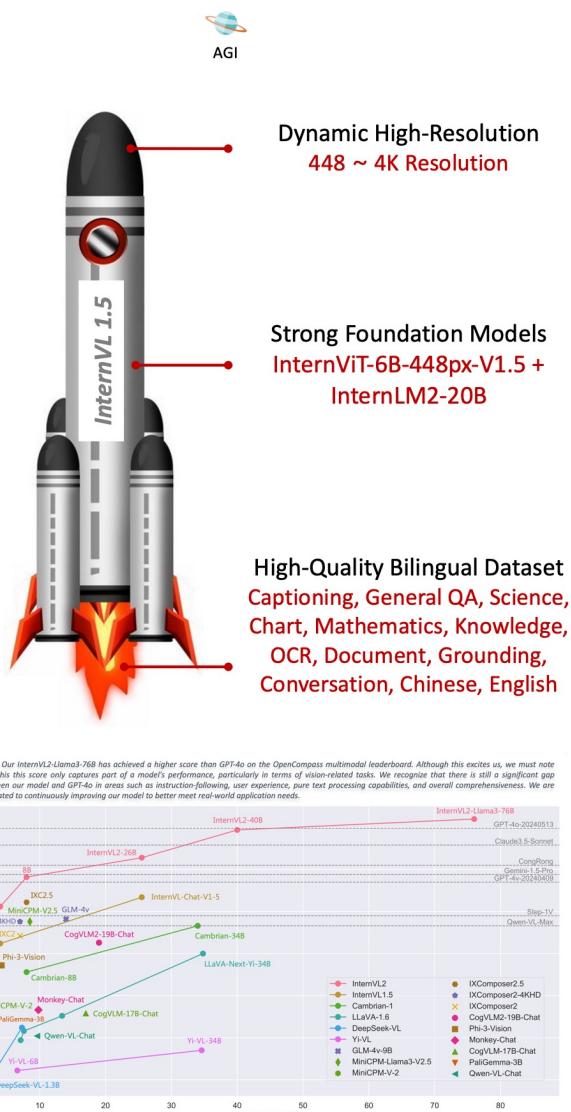
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Query: Please describe the object inside the red rectangle in the image and explain why it affects ego car driving.

Answer: A barrier with orange and white stripes, indicating a temporary obstruction or hazard. The ego car must remain vigilant for any changes in the driving lane or potential rerouting due to this obstruction. It could indicate construction, a road closure, or an accident ahead, and drivers should be prepared to slow down or follow detour signs.

The object inside the red rectangle in the image is a cyclist. This individual appears to be riding on or near an intersection, which could impact how vehicles navigate through that area.

Description of Object:

- Location:** The cyclist seems positioned close to where cars might turn right.
- Direction and Movement:** It's unclear whether they are actively moving into traffic lanes or waiting at the side but their presence poses potential risks due to unpredictable movements typical among cyclists navigating city streets.

How it Affects Ego Car Driving:

1. Potential Risk for Collision

- If the cyclist decides to move suddenly across the path of your car while turning right, there's a risk of collision unless you remain alert and prepared with defensive driving maneuvers such as slowing down and maintaining visibility checks around blind spots common during turns.

2. Safety Concerns During Turning Maneuver

- When making a turn (left/right), drivers must always check surroundings carefully before executing any maneuver because bikes can often appear unexpectedly from behind parked cars or crosswalk areas adjacent roads.

3. Impact on Speed Management

- Presence of bicycles necessitates more cautious speed control particularly when approaching intersections since sudden braking by cyclists isn't uncommon if startled or reacting quickly towards other road hazards like pedestrians jumping onto paths unannouncedly.

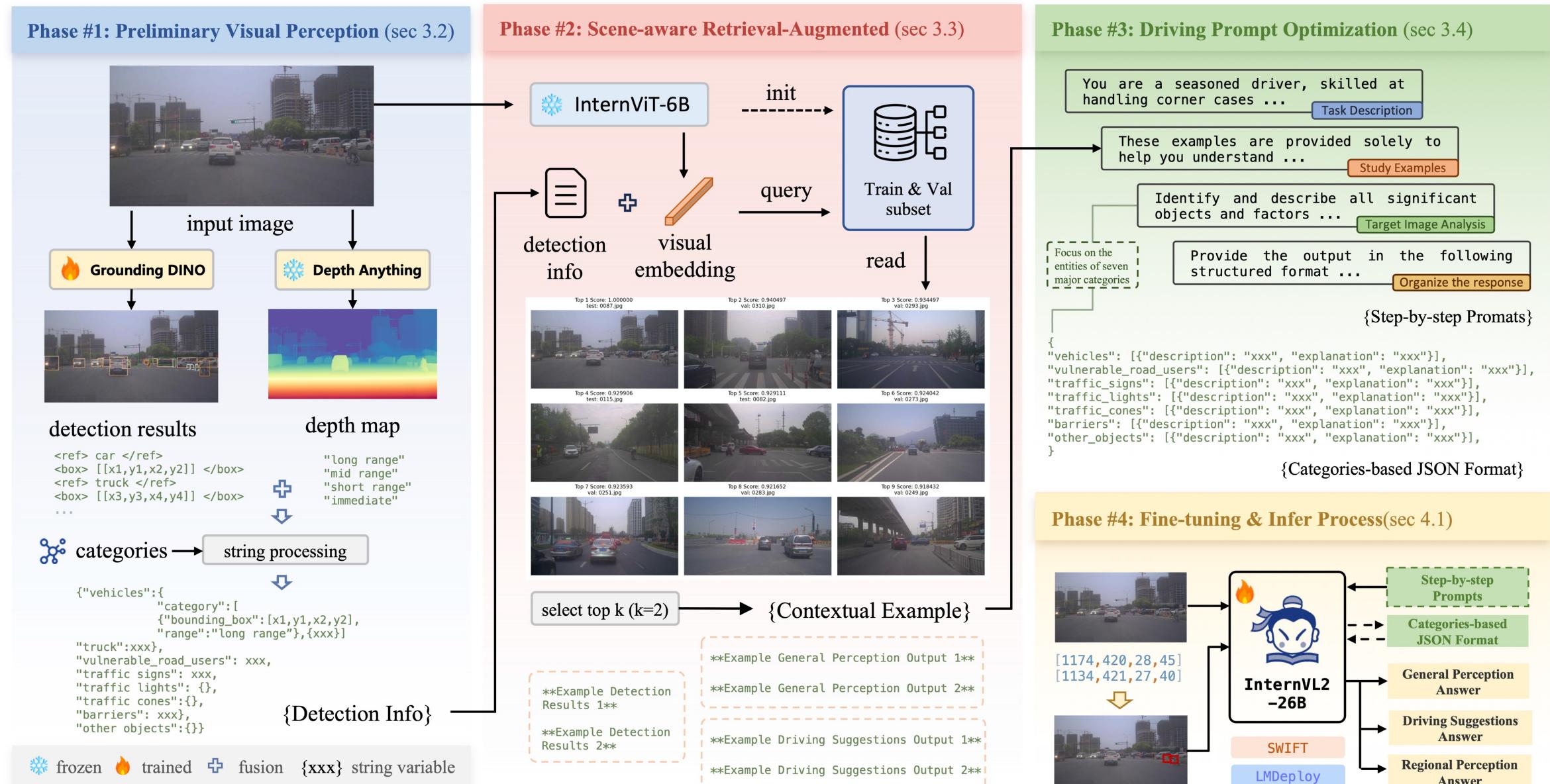
4. Visibility Hazard

- Cyclists pose challenges especially under poor weather conditions given m.

In conclusion, this cyclist significantly affects ego vehicle operation primarily through increasing the unpredictability factor influencing safe navigation within urban settings characterized prominently via higher likelihood encounters involving vulnerable road users requiring constant situational awareness & adaptive behavior adjustments whilst ensuring adherence to all safety protocols including regular scan patterns over surrounding environment even post initial observations confirming apparent emptiness visually discerned initially.

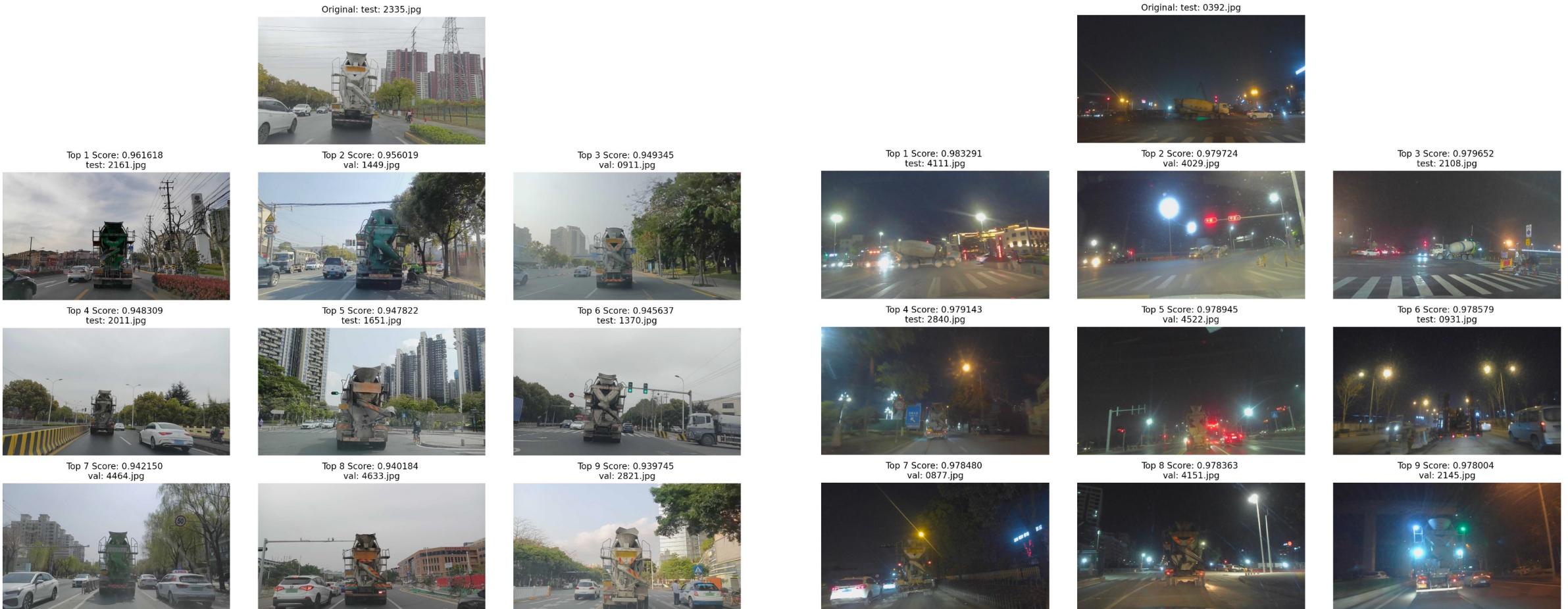
[A] Chen Zhe et al., Internvl: Scaling up vision foundation models and aligning for generic visual-linguistic task, in CVPR, 2024.

/03 Overview of the proposed NexusAD framework



/04 Visualization

Introduction Challenges Method Analysis Results



Our method focuses on scene similarity, not just image similarity, allowing retrieval of the most relevant reference samples for the current driving scenario.

6.1. Detection and Depth Information

```
{"vehicles":{  
    "category1":{  
        "bounding_box": [x1,y1,x2,y2],  
        "range": "long range"}, {xxx}],  
    "category2": [{xxx}, {xxx}]],  
    "vulnerable_road_users": [{xxx}, {xxx}],  
    "traffic_signs": xxx,  
    "traffic_lights": {},  
    "traffic_cones": {},  
    "barriers": {xxx}},  
    "other_objects": {}}}.
```

6.2. Category-based Perceptual Description

```
{"vehicles": [{}  
    {"description": xxx, "explanation": xxx}],  
    "vulnerable_road_users": [{}  
    {"description": xxx, "explanation": xxx}],  
    "traffic_signs": [{}  
    {"description": xxx, "explanation": xxx}],  
    "traffic_lights": [{}  
    {"description": xxx, "explanation": xxx}],  
    "traffic_cones": [{}  
    {"description": xxx, "explanation": xxx}],  
    "barriers": [{}  
    {"description": xxx, "explanation": xxx}],  
    "other_objects": [{}  
    {"description": xxx, "explanation": xxx}]}].
```

Based on the analysis of these topics, I have the following suggestions to further optimize your VLM prompts:

1. Enhance specificity: Ensure that the prompt asks the model to provide precise and detailed operational suggestions, reducing vague or overly broad language. For example, in sections like "Speed Adjustments" and "Lane Positioning and Maneuvers," ask the model not only to indicate when speed adjustments or lane changes are necessary but also to explain how to perform these actions in detail.

2. Emphasize critical traffic elements: Make sure the model consistently focuses on key traffic elements, such as traffic lights, red lights, and important road signs. Consider adding a step in the prompt that directs the model to pay special attention to these critical elements and provide specific response strategies.

3. Avoid overgeneralization: Encourage the model to concentrate on the unique aspects of the current situation, avoiding overly generalized advice. You could include a section in the prompt reminding the model that each scenario is unique and requires a tailored response based on the specific elements detected.

4. Incorporate a feedback mechanism: If possible, implement a mechanism that allows the model to recheck and adjust its recommendations after generating an initial suggestion. This can help reduce low-quality responses caused by omissions or misunderstandings.

5. Minimize the influence of examples: If the examples are causing hallucinations, consider providing only strategic advice from the examples without including specific detection results. This approach can guide the model to focus on structure and depth rather than the specific details of the example.

These suggestions can be integrated into your current prompt version to better align with the characteristics of VLMs, improving the overall scoring of the final predictions.

Leaderboard (Best of All Rounds)

We have removed team submissions violating the competition rules.

Team Name	Date	Final Score	General Perception	Region Perception	Driving Suggestion
Ilmforad	08-15	72.12	58.70	83.41	74.26
OpenDriver	08-09	69.72	54.41	83.00	71.76
NexusAD	08-15	68.97	57.58	84.31	65.02
123	08-02	68.79	52.98	83.07	70.32
LLMAnything	08-15	68.43	56.24	82.66	66.38
NTHUCVLab	08-15	67.85	55.16	82.88	65.50
Swift Unity Expedition	08-15	67.68	57.38	84.37	61.30
GY	07-26	66.79	46.32	84.50	69.54

Method	FS	GP	RP	DS
GPT-4V	59.02	57.50	56.26	63.30
CODA-VLM	63.62	55.04	77.68	58.14
InternVL-2.0-26B	52.11	43.39	64.91	48.04
NexusAD (Ours)	68.97	57.58	84.31	65.02

Table 2. Comparison of scores between directly inputting depth maps and using linguistic forms to provide depth information

Depth Map	Language	Score
✗	✗	4.10
✗	✓	4.36
✓	✗	4.58

Table 3. Score comparison between coherent text and structured json formats.

Coherent Text	Structured JSON	Score
✓	✗	5.98
✗	✓	6.40 (+0.42)



Thanks for your listening and attention !

References:



GitHub Link

- [1] Li, Yanze, et al. "Automated evaluation of large vision-language models on self-driving corner cases." arXiv preprint arXiv:2404.10595 (2024).
- [2] Chen, Zhe, et al. "Internvl: Scaling up vision foundation models and aligning for generic visual-linguistic tasks." Proceedings of the IEEE/CVF Conference on Computer Vision and Pattern Recognition. 2024.
- [3] Li, Kaican, et al. "Coda: A real-world road corner case dataset for object detection in autonomous driving." *European Conference on Computer Vision*. Cham: Springer Nature Switzerland, 2022.
- [4] Liu, Shilong, et al. "Grounding dino: Marrying dino with grounded pre-training for open-set object detection." *European Conference on Computer Vision*. Cham: Springer Nature Switzerland, 2024.
- [5] Yang, Lihe, et al. "Depth anything: Unleashing the power of large-scale unlabeled data." Proceedings of the IEEE/CVF Conference on Computer Vision and Pattern Recognition. 2024.