

Provide one safety-critical scenario.

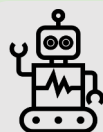
The ego is driving on a straight road, and the car in front brakes suddenly when the ego approaches.

(Few-Shot examples) +
Now extract the adversarial behavior of the surrounding agent, road geometry and the relative spawn positions between the ego and the adversarial agent.

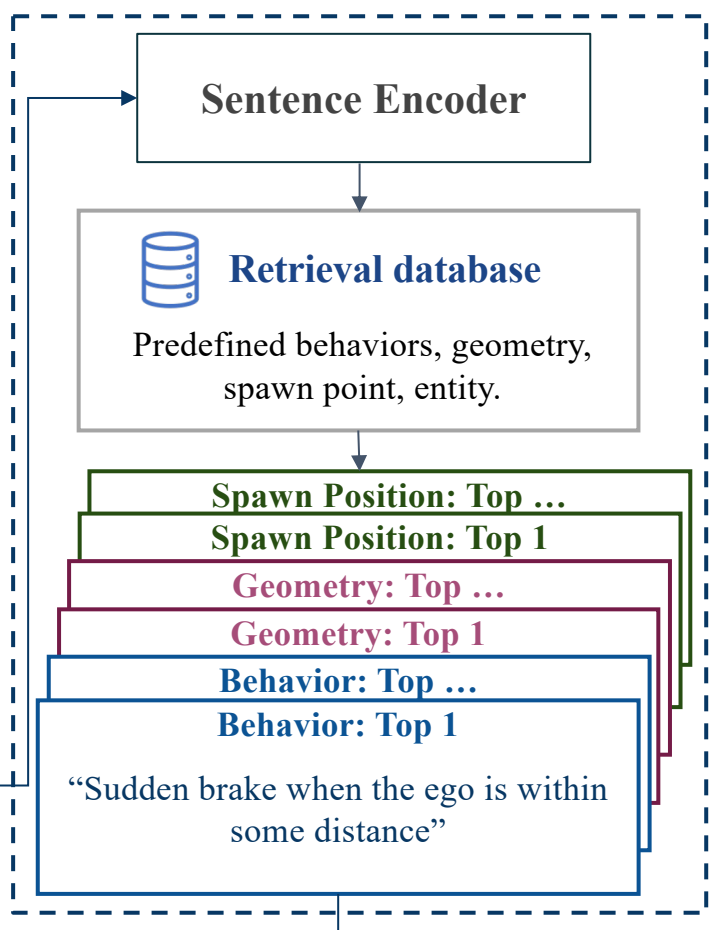
Behavior: the adversarial car suddenly breaks when the ego approaches.

Geometry: a straight road.

Spawn Position: the adversarial car is in front of the ego.



(a) Instruct an LLM agent



(b) Retrieval Process

Scenic code:

Default Setting

...

```
model scenic.simulators.carla.model
EGO_MODEL = "vehicle.lincoln.mkz_2017"
```

BEHAVIORS

```
behavior EgoBehavior():
    do FollowLaneBehavior(EgoSpeed)
```

```
behavior AdvBehavior(AdvSpeed):
    try:
        do FollowLaneBehavior(AdvSpeed)
        interrupt when withinDistanceToAnyObjs
            (self, AdvBreakingThreshold):
            take SetBrakeAction(1.0)
```

GEOMETRY

```
lane = Uniform(*network.lanes)
```

SPAWN POSITIONS

```
SpawnPt = OrientedPoint on lane.centerline
...
```

(c) Assemble Scenic Snippet



(d) Render Simulation in CARLA