## Scenario Adv. Car Guided Diffusion $au_K$ **Guidance Functions** JAdv $au_k$ $J_{Reg}$ $J_{Adv}$ Adv Jcoll **J**Control $J_{gc}$ *J*<sub>Route</sub> Denoising Guidances J **Process** Ego Gaussian Relative Lane Collision Time to Margin Distance Speed Collision Distance $\tau_{k-1}$ Non-Adv $J_{Reg}$ $au_0$