

SUPPLEMENTARY MATERIAL: VADv2: END-TO-END AUTONOMOUS DRIVING VIA PROBABILISTIC PLANNING

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1 VISUALIZATION ON CARLA AND REAL-WORLD DEPLOYMENT

We provide supplementary videos within the submitted ZIP archive, including `carla.mp4`, which visualizes the closed-loop performance of the VADv2 model on selected challenging segments of the Town05 Long Benchmark within the CARLA Dosovitskiy et al. (2017) simulation environment. Due to file size constraints, the video focuses on complex scenarios to illustrate the model’s behavior under demanding conditions.

Additionally, we include `real_world.mp4`, a real-world closed-loop demonstration video showcasing the deployment of the VADv2 model in an actual vehicle. This video highlights the model’s robustness and adaptability in real-world driving scenarios.

Together, these videos serve as a visual complement to the quantitative results presented in the main manuscript, providing further evidence of the VADv2 model’s performance in both simulated and real-world environments.

Table 1: More details on the training configurations for the CARLA benchmark.

Config	Value
Optimizer	AdamW
Optimizer Hyper-Parameter	$\beta_1, \beta_2, \epsilon = 0.9, 0.999, 1e-8$
Weight Decay	0.01
Learning Rate	1e-4
Learning Rate Scheduler	Cosine Annealing
Warm-up Iteration	500
Image Resolution	416×320
GPUs	$16 \times \text{RTX } 4090$
Batch Size per GPU	4
Training Epochs	2

2 MORE TRAINING DETAILS ON THE CARLA BENCHMARK

To better demonstrate the training details of VADv2 on the CARLA benchmark, we provide additional training configurations in Tab. 1, including optimizer, learning rate, GPUs, and other key settings.

REFERENCES

Alexey Dosovitskiy, German Ros, Felipe Codevilla, Antonio Lopez, and Vladlen Koltun. Carla: An open urban driving simulator. In *CoRL*, 2017.