1 Appendix

1.1 Proof

Proposition 1.1. *For any probability functions p and q of training distribution and testing distribution, diversity shift $D_{diversity}$ and attribute shift $D_{attribute}$ are inclusively bounded between 0 and 1.*

Proof. Obviously, both $D_{\text{diversity}}$ and $D_{\text{attribute}}$ are positive. Then, we prove the upper bound by the triangle inequality as followed:

$$D_{\text{diversity}} = \frac{1}{2}\int_{\mathbf{S}} \mid p(z) - q(z) \mid dz \leq \frac{1}{2}\int_{\mathbf{S}} [p(z) + q(z)]dz \leq 1 \tag{1}$$

Similarly, we have the following inequality:

$$\begin{aligned} D_{\text{attribute}} &= \frac{1}{2}\int_{\mathbf{T}} \sqrt{p(z)\cdot q(z)} \sum_{y_1,y_2} \mid p(y_1,y_2|z) - q(y_1,y_2|z) \mid dz \\ &\leq \frac{1}{2}\int_{\mathbf{T}} \sqrt{p(z)\cdot q(z)} \sum_{y_1,y_2} [p(y_1,y_2|z) + q(y_1,y_2|z)]dz \\ &= \frac{1}{2}\int_{\mathbf{T}} 2\sqrt{p(z)\cdot q(z)}dz = \int_{\mathbf{T}} \sqrt{p(z)\cdot q(z)}dz \leq 1 \end{aligned} \tag{2}$$

The second inequality is due to triangle inequality. □

1.2 Datasets

BDD100K The original BDD100K [26] contains 80,000 labeled images (70,000 for training and 10,000 for validation) with ten annotated object categories, including bike, bus, car, motor, person, rider, traffic light, traffic sign, train and truck. Each image has three attribute labels which indicate the condition, including the weather, scene and time for data collection. We remove the images with an undefined attribute label and separate the rest into three OOD environments.

Sim10K Sim10k [10] is a synthetic dataset containing 10,000 images (8,000 for training, 1,000 for validating and 1,000 for testing) with bounding box annotations for cars, which is rendered with the Grand Theft Auto V (GTA5) game engine. On DetectBench, we use the training and validating data to construct Sim2real benchmark.

Cityscapes Cityscapes [5] is a large-scale database which focuses on urban street scenes. The dataset consists of around 5000 fine annotated images (2975 for training, 500 for validating and the rest for testing) with eight annotated instance categories. On DetectBench, we consider the car recognition task to construct Sim2real benchmark for simplicity and without loss of generality.

CtrlShift CtrlShift is a synthetic dataset to analyze the two-dimension shift on OOD object detection. It provides an API to generate the training set and the testing set with specific choices of $\rho_{diversity}$ and $\rho_{attribute}$.

1.3 Implementation Details

To evaluate the object detection algorithms, we use the models and the pre-trained weights provided by mmdetection [4].

For domain generalization algorithms on OOD object detection, we derive the implementations using Faster R-CNN [19] with ResNet-50 FPN backbone [8] from torchvision. The whole network is optimized by Stochastic Gradient Descent with learning rate 0.02, momentum 0.9 and weight decay 0.0005.

1.4 Further Results

Task complexity. To analyse the IID condition on CtrlShift, which indicates both $D_{\text{attribute}}$ and $D_{\text{diversity}}$ equal zero, we propose a hyper-parameter task complexity α to measure the difficulty of the

Table 1: Illustration of the two setting on Sim2real. $\text{sim}_{\text{train}}$ and sim_{val} indicate the training set and validating set from original Sim10K [10] while $\text{city}_{\text{train}}$ and city_{val} are from original Cityscapes [5]. **Quantity** indicates the number of image. **Total** counts the total number of training and testing domains respectively.

Setting	Split	Train	Test	Quantity	Total
part-sim-part-real	$\text{sim}_{\text{train}}$	√		8000	8500
	sim_{val}		√	1000	
	$\text{city}_{\text{train}}$		√	2975	3975
	city_{val}	√		500	
all-sim-all-real	$\text{sim}_{\text{train}}$	√		8000	9000
	sim_{val}	√		1000	
	$\text{city}_{\text{train}}$		√	2975	3475
	city_{val}		√	500	

Table 2: The experimental results of object detection algorithms on the all-sim-all-real of Sim2real. Mem (GB)† and Inf time (fps)† are from mmdetection [4].

Detector	Backbone	Mem†	fps†	AP
Faster R-CNN [19]	X-101	10.3	9.4	35.6
RetinaNet [15]	X-101	10.0	8.7	38.0
Mask R-CNN [7]	X-101	10.7	8.0	36.7
CornetNet [13]	Hourglass104	13.9	4.2	21.6
YOLOv3 [18]	DarkNet-53	7.4	48.1	28.2
FCOS [23]	X-101	10.0	9.7	37.9
Cascade R-CNN [3]	X-101	10.7	-	40.5
MS R-CNN [9]	R-X101	11.0	8.0	35.7
Libra R-CNN [16]	X-101	10.8	8.5	35.3
DH R-CNN [25]	R-50	6.8	9.5	33.8
VarifocalNet [27]	X-101	-	-	42.3
Sparse R-CNN [22]	R-101	-	-	40.3
Deformable [28]	R-50	-	-	37.4
YOLOX [6]	YOLOX-x	28.1	-	36.4

task. The difficulty is adjusted by using $1 - \alpha$ percent novel data in the testing set in addition to the original training data. The experimental results are shown in Figure 1. The generalization ability of each algorithm drops with the increase of task complexity.

Sim2real benchmark. The training set of the Sim2real results reported in the main manuscript comprises of the training data from Sim10K [10] and the validating data from Cityscapes [5], while the testing set comprises of the training data from Cityscapes [5] and the validating data from Sim10K [10] (noted by part-sim-part-real, more details can be found in Table 1.4). We reported the experimental results on all-sim-all-real in Table 2 and Table 3.

Table 3: The experimental results of domain generalization algorithms on the all-sim-all-real of Sim2real.

Algorithm	hyper-parameters	AP
ERM [24]	-	32.8
IB-ERM [1]	$\lambda_{ib} = 100$	18.3
IRM [2]	$\lambda_{irm} = 1$	32.7
MMD [14]	$\gamma_{mmd} = 1$	33.2
CORAL [21]	$\gamma_{mmd} = 1$	32.5
VREx [12]	$\lambda_{vrex} = 1$	32.4
GS [17]	$\lambda_{reg} = 0.1$	31.4
IGA [11]	$\lambda_{penalty} = 1000$	33.4
GroupDRO [20]	$\eta_{groupdro} = 0.01$	31.9

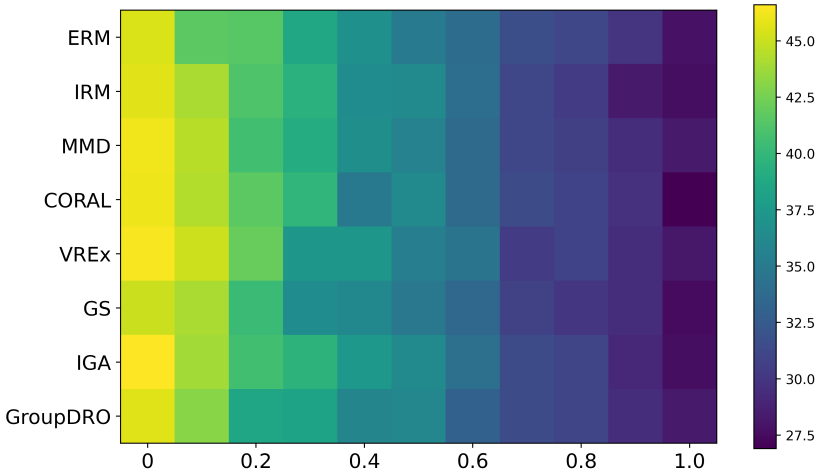

Figure 1: X-axis is task complexity α. Each block indicates the AP(%).

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