

## Background & Ideas

### Context

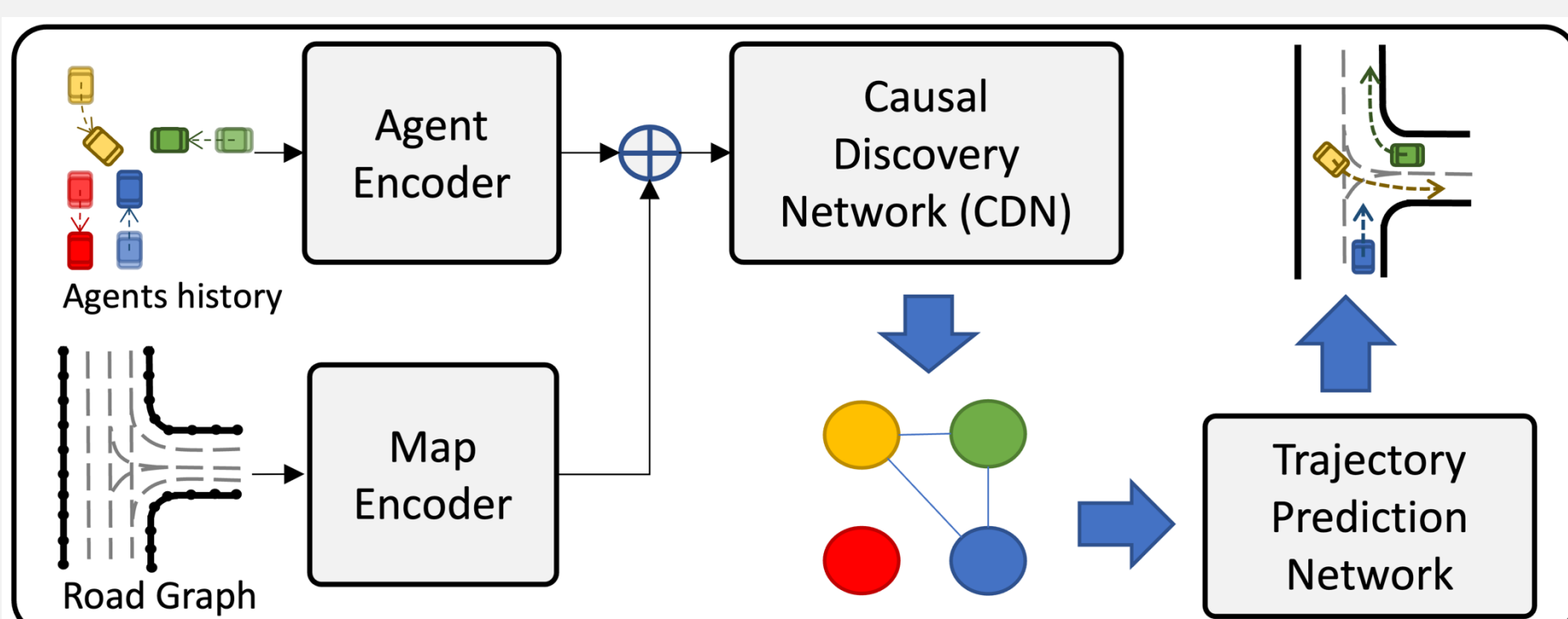
- Autonomous vehicles must robustly predict other agents' trajectories under **distribution shifts** and avoid relying on **spurious correlations**.
- State-of-the-art models suffer large performance drops if non-causal agents are removed.
- We have causal agent labels annotated by humans.

### Key Challenge

- How to **identify** and **attend only** to truly causal agents?

### Our Goal

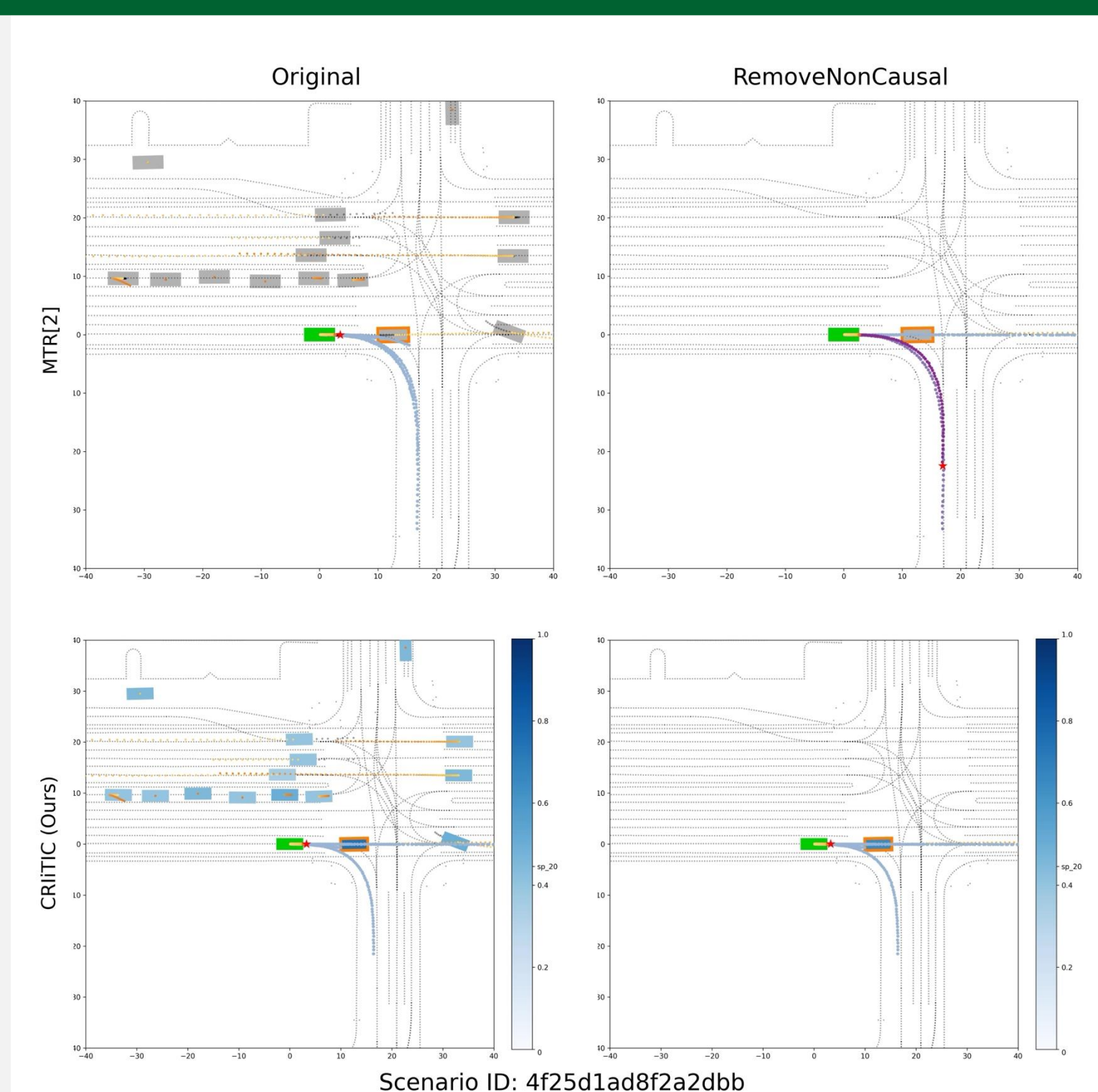
- Improve **robustness** and **generalization** by integrating explicit causal structure into prediction model's attention layers.



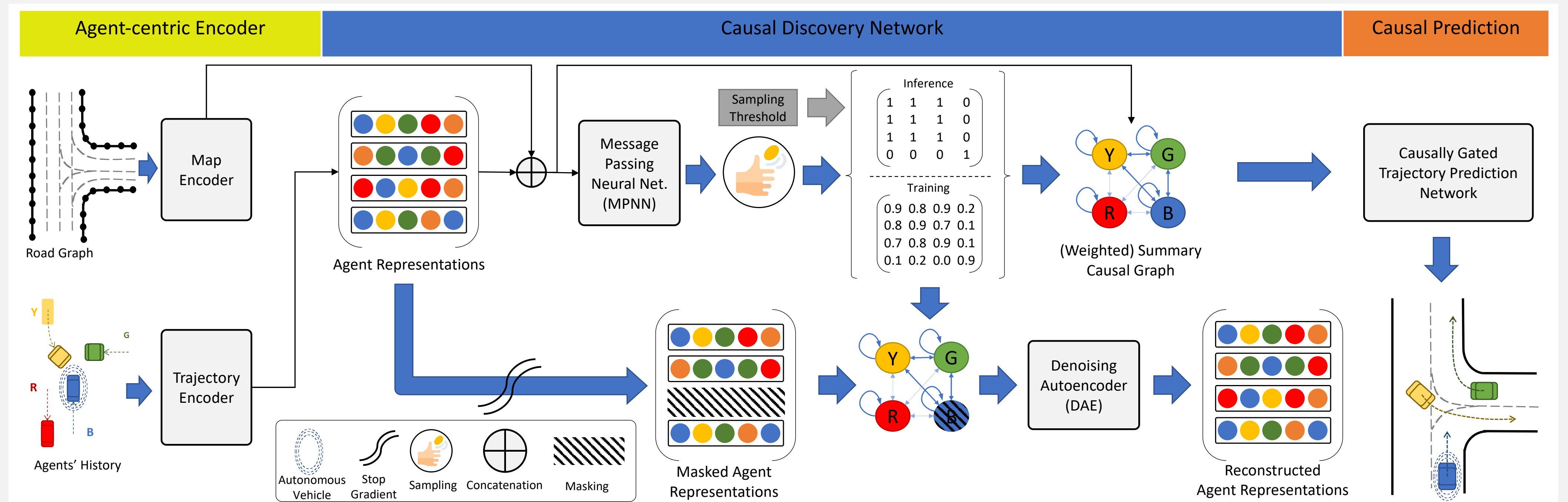
## Contributions

- CRITIC**: an agent-centric causal trajectory predictor.
- Causal Discovery Network (CDN)**: learns a sparse inter-agent causal graph via an information-bottleneck regularization + self-supervised denoising autoencoder.
- Causal Attention Gating (CAG)**: injects the learned graph into the Transformer's attention, suppressing non-causal inputs.
- Empirical Gains**: up to **54 %** robustness improvement under RemoveNonCausal perturbation and **29 %** cross-domain gains.

## Causal Robustness Qualitative Samples



The **AV** is shown in **green**. The **orange** borderline indicates the causal agents. The **ground truth**, and **predictions** are shown in **orange**, and **purple** colors. Star shows the predicted most confident mode. The color saturation indicates the estimated probability of an agent being causal.



Causal Discovery Network receives the agent representations and generates a causality adjacency matrix. The matrix is used by a Transformer-based prediction backbone to shape the attention toward the causal agents.

## Model Overview

### 1-Inputs:

- Agent Encoder**: encodes each agent + map into disentangled embeddings.

### 2-Causal Discovery Network:

- MPNN** produces soft adjacency  $A$  via a BinConcrete relaxation.
- Sparsity** loss (KL to Bernoulli( $p$ )) enforces an information bottleneck.
- Auxiliary GCN** denoising autoencoder to further assist causal discovery network's training

### 3-Transformer-based Prediction Backbone

- Causal Attention Gating (CAG)** to apply the discovered causal adjacency matrix in the attention layers of the backbone network

## Causal Attention Gating and Information Bottleneck

We apply a learned soft adjacency  $A$  to the standard self-attention weights and down non-causal links in noise.

$$\text{Let } \Phi = \text{softmax}\left(\frac{QK^T}{\sqrt{d_k}}\right)$$

then

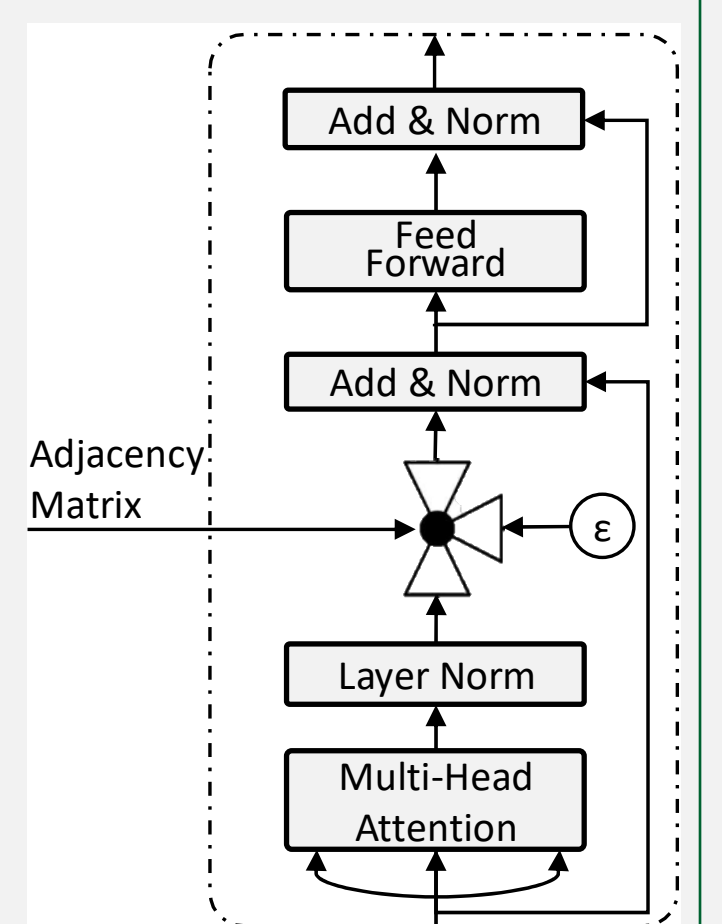
$$\text{CausalAttn}(Q, K, V; A) = (\Phi \odot A) V + \alpha (\Phi \odot (1 - A)) \mathcal{N}(0, I)$$

where the second term is a noise term creating the attention bottleneck.

$A$  is generated by the causal discovery network,  $\alpha=0$  at inference time.

A regularization loss term is used to encourage sparse causal adj. matrices.

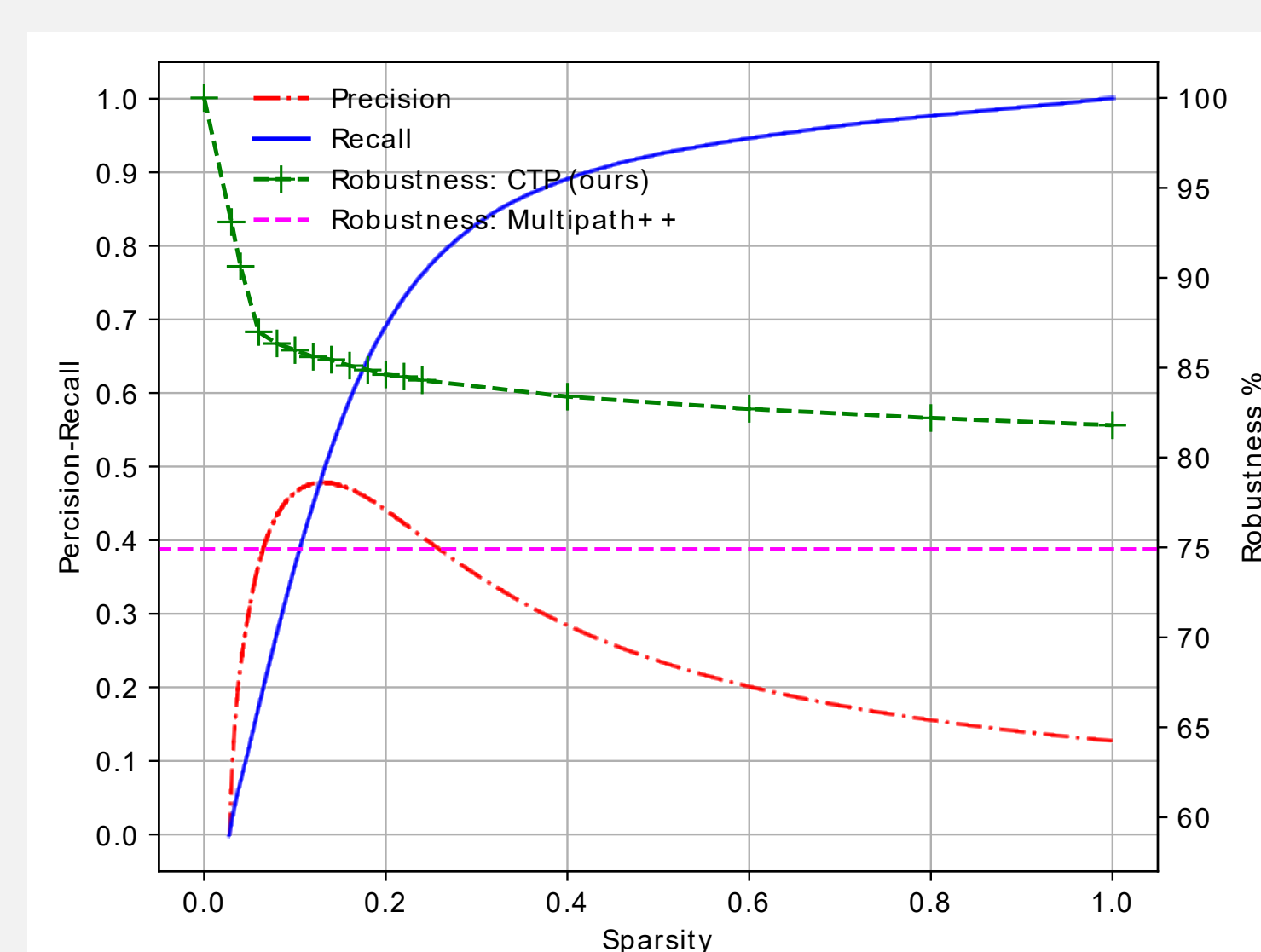
$$L_{\text{sparsity}} = \sum_{i \neq j} \text{KL}(\text{Bern}(e_{ij}) \parallel \text{Bern}(p))$$



## Robustness to Non-causal Agent Removal

- Causal robustness**: The Prediction accuracy change caused by removing non-causal agents ( $\Delta \text{minADE} / \text{minADE} (\%)$ )
- Here we show that our model at sparsity value of 4% outperforms the baselines significantly from the perspective of causal robustness.
- Sparsity is defined based on the number connections in the discovered causal relation graph from the perspective of autonomous vehicle.

Model	$\Delta \text{minADE} / \text{minADE} (\%) \downarrow$
MultiPath++	37.5 %
SceneTransformer	26.8 %
Wayformer	25.7 %
MTR	21.5 %
<b>CRITIC_SP4 (Ours)</b>	<b>9.9 %</b>



- The relation between the sparsity of the identified causal graph, the precision and recall values for the causal agent identification, and the causal robustness measure.
- We argue that causal robustness should be reported along with the sparsity values.

## Conclusion

### Takeaways

- Explicit causal structure leads to dramatically improved robustness and cross-domain performance.
- Causal gating imposes an effective information bottleneck.

### Next Steps

- Incorporate **agent-map** causal edges (e.g., traffic lights).
- Model unobserved **confounders**.

## Contact

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