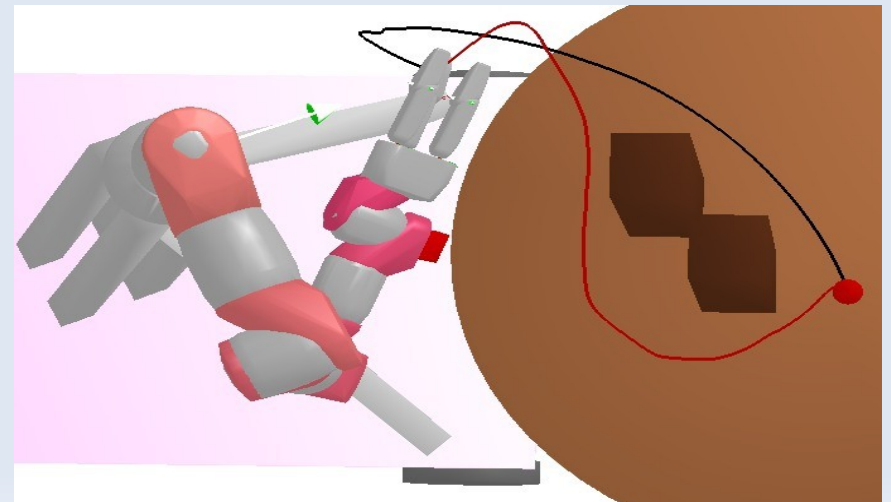# Nikolay Jetchev

- PhD Student at TU Berlin,

  Prof. Dr. Marc Toussaint

- Patterns and representations in motions and situations

- Learning by Demonstration and quick trajectory generation

# Trajectory Prediction

- Data: random reach/avoid scenarios, optimal trajectories

- Situation descriptors (state)

- Trajectory set (action)

- Learn mapping

- Initialize local planners (iLQG, DDP, AICO)

  - Fast

  - Better optima
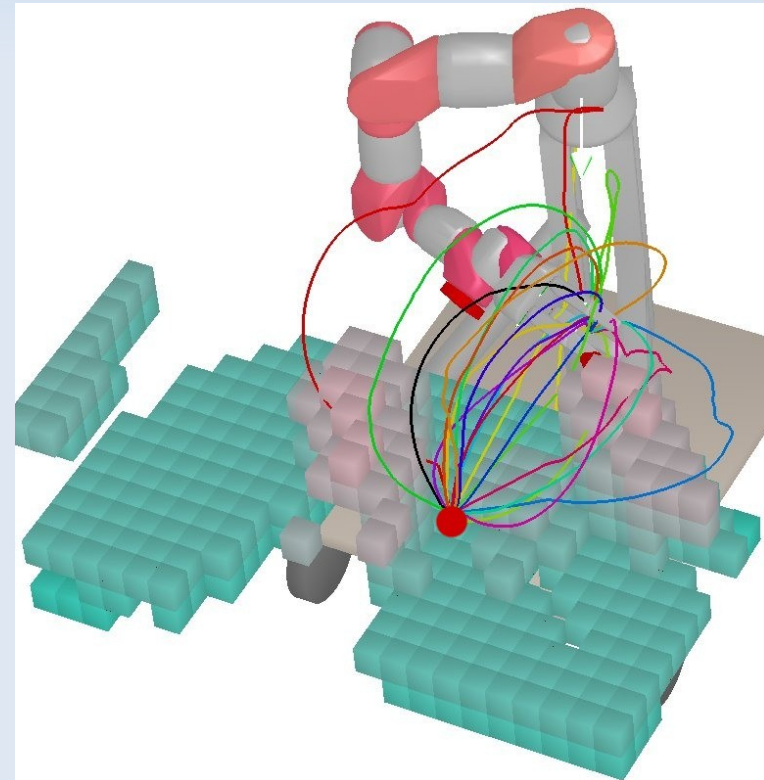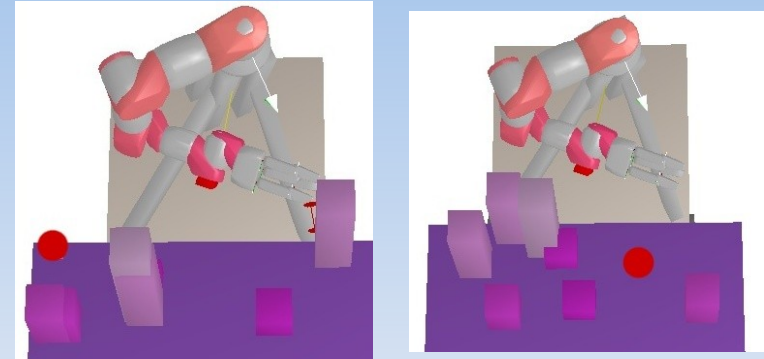
# Structured Prediction

- Joint representations of situation and motion

- Only raw data(landmarks), no explicit cost function and motion representation

- Learn Energy function from demonstrations

- Infer motions with low cost for a new situation