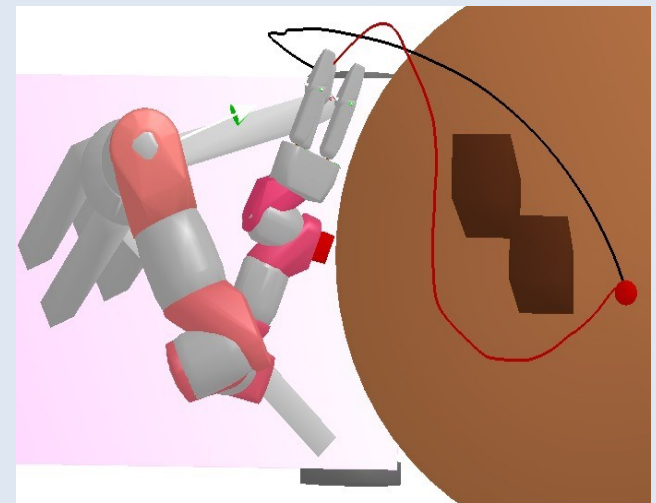# Nikolay Jetchev

- 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 scenarios, optimized offline motions

- Situation descriptors (state)

- Trajectory set(action)

- Learn mapping

- Initialize local planners (iLQG) and speed them up
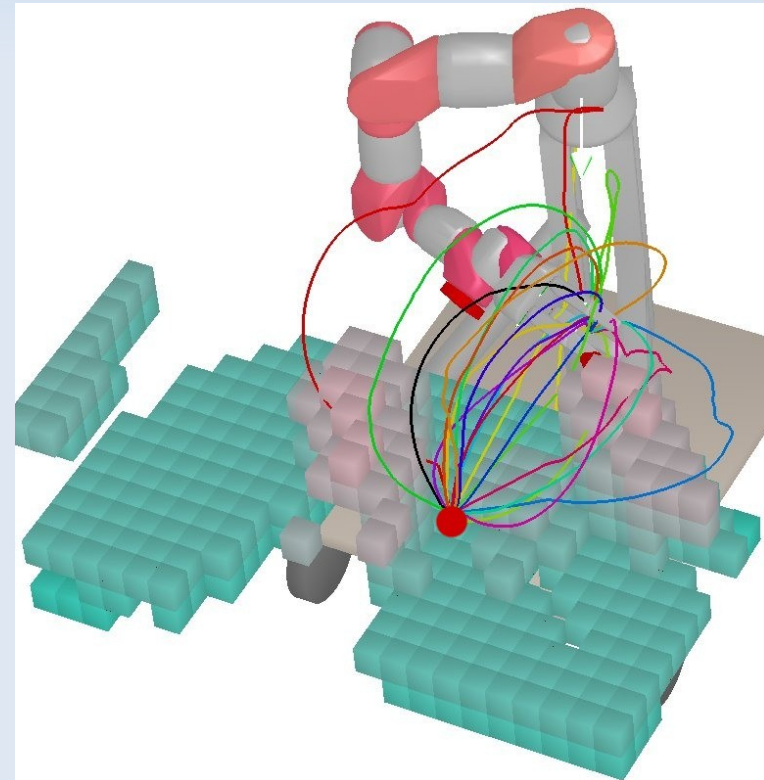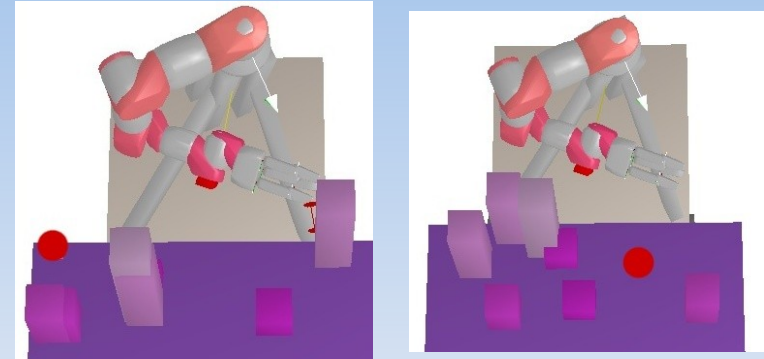
Structured Prediction

- Joint representations of situation and motion

- Learn Energy function from demonstrations

- Infer motions with low cost for a new situation

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