



Cost

- (1) Distance from other car w^1
- (2) Boundary violation w^2
- (3) Lateral jerk. w^3

Input:
(Scene, Human Plan)

Output:
(Human Plan)

$$\text{Cost} = w^1 \cdot (1) + \dots$$

$$L(w) = \text{Cost}_w(\Sigma^h) - \text{Cost}_w(\Sigma^*)$$

$$w_{\text{new}} = w_{\text{old}} - \eta \left[\nabla_w \text{Cost}_w(\Sigma^h) - \nabla_w \text{Cost}_w(\Sigma^*) \right]$$



MAX MAXON
PLANNER

$$\Sigma^* = \underset{\Sigma}{\operatorname{argmin}} C(\Sigma)$$

MAXIMUM ENTROPY IOC

$$w_{\text{new}} = w_{\text{old}} - \eta \left[\nabla_w \text{Cost}_w(\Sigma^h) - \nabla_w \text{Cost}_w(\Sigma^*) \right]$$

$$\Sigma^* \sim \exp(-C(\Sigma))$$

