bootstrapping

bootstrapping/agents	*Agents and tasks*	
\agSp	Agents	
\agSpYU	$\mathsf{Agents}(\mathcal{Y};\mathcal{U})$	All agents with given formats.
\agA	$\mathcal{A}$	An agent
\agExp	expl	Agent's exploration phase
\agLearn	learn	Agent's learning phase
\agAct	act	Agent's action phase
\agAexp	$\mathsf{expl}_{\mathcal{A}}$	Exploration phase for agent $\mathcal{A}$.
\agAact	$\mathsf{act}_{\mathcal{A}}$	Action phase for agent $\mathcal{A}$.
\agAwtor	$\mathsf{WtoR}_{\mathcal{A}}$	Map from the world to the result for t
\agAwtob	$\mathsf{WtoB}_{\mathcal{A}}$	
\agAintermediate	$\mathsf{intermediate}_{\mathcal{A}}$	
\agSucAG	$\mathsf{success}^{\mathcal{G}}_{\mathcal{A}}$	Success set for the agent $\mathcal{A}$ and goal $\mathcal{G}$
\agRep	$\boldsymbol{m}$	Agent representation
\agRepSp	$\mathcal{M}$	Agent's model space
\agNuis	$\mathrm{G}_{\mathcal{A}}$	
\agNuisComp	$\mathrm{G}^{\perp}_{\mathcal{A}}$	Complement of $\mathrm{G}_{\mathcal{A}}$.
\agNuisObs	$\mathrm{G}^{\mathcal{Y}}_{\mathcal{A}}$	
\agNuisCmd	$\mathrm{G}^{\mathcal{U}}_{\mathcal{A}}$	
\agbbClass	$C_{\mathcal{A}}$	
\agbbClCore	$C^0_{\mathcal{A}}$	
\agGoal	$\mathcal{G}$	The agent's goal (a subset of $\mathsf{StocProce}$

articles

articles/bds	*BDS report*	
\BDSnk	$\mathsf{BDS}(n;k)$	
\BDSSk	$\mathsf{CBDS}(\mathcal{S};k)$	
\bgBDSfamily	BDS	Family of BDS sensors
\bgCBDSfamily	CBDS	Family of BDS sensors
\bds	BDS	Bilinear dynamics system
\BDS	BDS	
\cbds	CBDS	Continuous-space bilinear dynamics sy
\CBDS	CBDS	
\omsum{...}		omitted sum
\omsumb{...,...}		omitted sum (two arguments)
\TT	$\mathbf{T}$	Learned tensor
\TTe	T	?
\TP	$\mathbf{P}$	
\TPe	P	
\TU	$\mathbf{U}$	Learned tensor
\TUe	U	Learned tensor
\TM	$\mathbf{M}$	Bilinear tensor in BDS dynamics
\TMe	M	Bilinear tensor in BDS dynamics
\TN	$\mathbf{N}$	Bilinear tensor in BDS dynamics
\TNe	N	Bilinear tensor in BDS dynamics
\Tcov	$\mathbf{P}$	Covariance of $\boldsymbol{y}$.
\Tcove	P	Covariance of $\boldsymbol{y}$.

\Tucov	$\mathbf{Q}$	Covariance of $\boldsymbol{y}$.
\Tucove	Q	Covariance of $\boldsymbol{y}$.
\discInt	T	Discretization interval
\nearavg	$\overline{\mu}$	Average nearness

articles/bgds	*BGDS report*	
\bgds	BGDS	Bilinear gradient dynamics system
\BGDS	BGDS	
\bgCmd	$\boldsymbol{u}$	commands
\bgCmdH	$\boldsymbol{u}^{\mathbb{T}}$	commands history
\bgCmdSp	$\mathcal{U}$	commands space
\bgWorld	W	World
\bgWorldSp	$\mathcal{W}$	World space

		$\mathsf{W} \in \mathcal{D}(\mathbb{T}, \mathcal{U}, \mathcal{Y})$
		`$\bgWorld \in \bgRSSp(\bgTime, \bgCm`
		`\bgObsSp)$`

\bgAgent	agent	Agent
\bgAgentEx	learn	Agent exploration
\bgAgentAc	act	Agent action
\bgAgentRep	$\boldsymbol{r}$	Agent representation
\bgAgentRepSp	$\mathcal{R}$	Agent representation space
\bgAgentSp	Agents	Agent action
\bgCmdTr	$\boldsymbol{g}$	Transformation of the commands
\bgCmdTrSp	$\mathrm{G}^{\mathcal{U}}$	
\bgObsTr	$\boldsymbol{h}$	Transformation of the observations
\bgObsTrSp	$\mathrm{G}^{\mathcal{Y}}$	
\bgSamplingGroup	Sampling	Groups of sampling operations
\bgCalibration	Calib	Calibration operation
\bgBDSagent	A_{BDS}	The BDS agent
\bgBGDSagent	A_{BGDS}	The BGDS agent
\bgPopCode	pop	Popoulation code
\bgRankCode	rankcode	Rank code
\bgRangeFamily	RF	Family of range-finders models
\bgFields	C	
\bgCmdConstraints	$\Omega_{\boldsymbol{u}}$	
\bgPopK	ψ	

articles/bgds/old	*BGDS report*	
\state	$\boldsymbol{x}$	Generic underlying state.
\stateSp	$\mathcal{X}$	Generic underlying state space.
\detecte	d	Detector
\submean{...}		Quantity with mean normalized.
\dist	σ	Distance to obstacle
\distn	σ^*	Distance to obstacle, mean normalized
\rfnl	β	Nonlinear function in range-finder tens
\near	μ	Nearness
\lum	y	Luminance
\lumn	y^*	Luminance, mean normalized
\sptran	$\boldsymbol{\ell}$	Sensor pose (translation)
\sprot	ℓ_θ	Sensor pose (rotation)
\slvel	$\boldsymbol{v}^{\boldsymbol{s}}$	Sensor linear velocity (when off axis)

\savel	$\boldsymbol{\omega^s}$	Sensor angular velocity (when off axis)
\TX	$\mathbf{X}$	Generic metric
\TXe	X	Generic metric
\OS	S	$S = s \times \nabla$
\convf	f_*	Indicates the convolution with a kernel
\my	m	Metric on the tangent space of $y(s)$.
\ip{...}		
\bgBGDSfamily	BGDS	Family of BGDS sensors
\BGDSsk	$\mathsf{BGDS}(\mathcal{S}; k)$	
\focal	F	Pinhole camera focal length.
\traindist	p_{T}	Training distribution.
\trainsym	$\mathsf{Sym}(p_{\mathrm{T}})$	Symmetry group of p_{T}.

articles/bgds/logical	*Gradient dynamics*	
\obslsp	$\mathcal{Z}$	Observation logical space
\obsl	$\boldsymbol{z}$	Observations in logical space
\obsle	z	Observation logical space element
\xtos	φ	Mapping between $\mathcal{S}$ and $\mathcal{Z}$.
\jac	$\mathbf{J}$	Jacobian of φ
\jace	J	An element of the Jacobian of φ.
\mz	μ	Metric on the tangent space of $z(x)$.
\mmu	M	Metric for the commands u.

articles/bgds/logical/grads	*Gradient dynamics*	
\Tzgd	$\mathbf{L}$	$\boldsymbol{z}$ gradient dynamics
\Tzgde	L	$\boldsymbol{z}$ gradient dynamics (element)
\Tzgl	$\mathbf{M}$	$\boldsymbol{z}$ gradient learned tensor
\Tzgle	M	$\boldsymbol{z}$ gradient learned tensor (element)
\Tzgcov	$\mathbf{S}$	$\boldsymbol{z}$ gradient covariance
\Tzgcove	S	$\boldsymbol{z}$ gradient covariance (element)
\Tzad	$\mathbf{E}$	Affine part of dynamics.
\Tzade	E	Affine part of dynamics (element)
\Tzal	$\mathbf{F}$	Learned affine part of dynamics.
\Tzale	F	Learned affine part of dynamics (eleme

articles/bgds/tensors	*BGDS report*	
\Tygd	$\mathbf{G}$	$\boldsymbol{y}$ gradient dynamics
\Tygde	G	$\boldsymbol{y}$ gradient dynamics (element)
\Tygl	$\mathbf{H}$	$\boldsymbol{y}$ gradient learned tensor
\Tygle	H	$\boldsymbol{y}$ gradient learned tensor (element)
\Tygcov	$\mathbf{R}$	$\boldsymbol{y}$ gradient covariance
\Tygcove	R	$\boldsymbol{y}$ gradient covariance (element)
\Tyad	$\mathbf{B}$	Affine part of dynamics.
\Tyade	B	Affine part of dynamics (element)
\Tyal	$\mathbf{C}$	Learned affine part of dynamics.
\Tyale	C	Learned affine part of dynamics (eleme

articles/bgds/models/deprecated	*Definition of random models*	
\bgTime	$\mathbb{T}$	Time axis
\bgRS	$\boldsymbol{D}$	Random model
\bgRSSp	$\mathcal{D}$	All models

\bgRSinput	$\boldsymbol{a}$	Input signal
\bgRSinputSp	$\mathcal{A}$	
\bgRSinputH	$\boldsymbol{a}^{\mathbb{T}}$	History of input signal
\bgRSoutput	$\boldsymbol{b}$	
\bgRSoutputH	$\boldsymbol{b}^{\mathbb{T}}$	History of output signal
\bgRSoutputSp	$\mathcal{B}$	
\bgRSinputTr	$\boldsymbol{g}$	
\bgRSinputTrSp	$\mathrm{G}^{\mathcal{A}}$	
\bgRSoutputTr	$\boldsymbol{h}$	
\bgRSoutputTrSp	$\mathrm{G}^{\mathcal{B}}$	
\bgObs	$\boldsymbol{y}$	observations
\bgObsH	$\boldsymbol{y}^{\mathbb{T}}$	observations history
\bgObsSp	$\mathcal{Y}$	observation space

articles/camera	*Camera paper*	
\rank	order	
\place	place	
\ff	f	Distance to similarity function
\Sany	$\mathcal{M}$	Generic hypersphere
\targetSp	$\mathcal{M}$	Target manifold
\Ssubset	M	A subset of $\mathcal{M}$ XXX
\infr	infr	Informative radius
\ffr	infr(f)	Informative radius of f
\distradius	rad	Radius of a distribution
\distdiam	diam	Diameter of a distribution
\hausdorff	hausdorff	Hausdorff distance
\kimberley	kim	Kimberley value
\errproc	e_{pr}	Procrustes score
\isoError	e_{iso}	
\symError	e_{sym}	
\relError	e_{r}	
\scaledRelError	e_{sr}	
\angcorr	ρ_θ	
\spearperf	ρ_{sp}	Spearman performance measure
\spearperfn	ρ^*_{sp}	Normalized Spearman performance me
\dirset	$\mathcal{S}$	Set of directions
\dirmat	$\mathbf{S}$	Directions stacked in a matrix
\matX	$\mathbf{X}$	
\matI	$\mathbf{I}$	
\arot	$\mathbf{X}$	
\cosmat	$\mathbf{C}$	
\cosmatij	C_{ij}	
\distmat	$\mathbf{D}$	
\distmatij	D_{ij}	
\simmat	$\mathbf{Y}$	Similarity matrix
\simmatij	Y_{ij}	
\simmatii	Y_{ii}	
\simmatkl	Y_{kl}	
\algorparam	γ	
\shannon	H	
\fov	FOV	field of view

\SKalgo	SK	Shepard-Kruscall algorithm
\SBSEw	$SKv + w$	An extension to the SK algorithm
\SBSE	SKv	An extension to the SK algorithm (wit

articles/dds	*DDS report*	
\ddsres	ρ	Resolution of the sensor in a DDS.
\ddsarea	$\lvert\mathcal{S}\rvert$	Area of the manifold $\mathcal{S}$.
\ddsbound	$d_{\max}$	Bound on the maximum diffeomorphis
\DDS	DDS	
\dds	DDS	
\ddsl	DDSL	
\DDSsu	$\mathsf{DDS}(\mathcal{S};\mathcal{U})$	
\DDSLsvu	$\mathsf{DDSL}(\mathcal{S},\mathcal{V};\mathcal{U})$	
\bgDDSfamily	DDS	
\bgDDSLfamily	DDSL	
\diffeoURL	*???*	Model
\cmdAlphabet	$\mathcal{U}$	
\ncmdwords	$\lvert\mathcal{U}\rvert$	Number of commands words.
\obsspD	$d^{\mathcal{S}}$	Metric on $\mathcal{S}$.
\diffId	$\mathsf{Id}_{\mathcal{S}}$	Identity diffeomorphisms.
\diffU	Γ	Uncertainty of estimated diffeomorphis
\diffDist	d^{Diff}	Distance between two diffeomorphism.
\cmdDist	$\mathcal{D}_{\text{cmd}}$	Distance between two commands.
\cmdADist	$\mathcal{A}_{\text{cmd}}$	Anti-distance between two commands.
\images	$\mathbb{F}(\mathcal{S})$	
\obspsV	$\mathcal{V}$	viewport
\ddsfov	$\mathcal{V}$	viewport
\obspsVunpred	$\mathcal{V}^{\overline{\text{pr}}}$	undpredictable part
\obspsVpred	$\mathcal{V}^{\text{pr}}$	predictable part
\obspsVunpredt	$\mathcal{V}_t^{\overline{\text{pr}}}$	undpredictable part at time t
\obspsVpredt	$\mathcal{V}_t^{\text{pr}}$	predictable part at time t
\ddsctod	C_TO_DIFF	
\ddsste	x	State of a DDS (element)
\ddsst	$\boldsymbol{x}$	State of a DDS

articles/deepdyn	*Learning of latent/deep dynamics*	
\ldmap	γ	Map from latent state to instantaneous
\hclass	$\mathcal{H}$	Hidden class
\iclass	$\mathcal{M}$	Instantnaeous class

articles/despl	*Parallel learning paper*	
\atype{...}		
\mycode{...}		
\desplStats	**Stats**	
\desplIStats	**IStats**	
\desplData	**Data**	
\desplIData	**IData**	
\desplModels	**Models**	
\desplIModels	**IModels**	
\desplllearn	learn	
\desplilearn	ilearn	

\desplfilter	filter	
\desplfmodel	fm	
\desplistats	istats	
\desplglue	glue	
\desplmglue	mglue	
\desplstats	stats	
\desplmerge	merge	
\desplInter	$\mathbf{I}$	Interval
\patternA	$Slice - Stats - Merge$	
\patternB	$Split - Stats - Glue$	
\patternC	$Filter - Learn - Glue$	
\patternD	$Recursive - Learn$	
\proto	$A2$	
\slicelen	`slicelen`	
\njobslearn	n_{learn}	
\njobsmerge	n_{merge}	
\njobstotal	n_{jobs}	

articles/compmake	*Compmake*
\Compmake	*Compmake*
\parmake	`parmake`
\sgemake	`sgemake`

articles/dptr1	*Technical report for diffeoplanning*

articles/dptr1/spaces	*spaces*	
\SetImages	Im	
\SetUImages	UIm	
\genericdist{...,...}		
\genericudist{...,...}		
\obsstart	$\boldsymbol{y}_{\text{start}}$	
\obsgoal	$\boldsymbol{y}_\circ$	
\SetPlans	Plans	
\planSp	Plans	
\redplans	RedPlans	reduced plans
\plan	p	a generic plan
\plang	$p_\circ$	true plan
\planf	$p^\star$	The solution found
\zeroplan	$\emptyset$	
\obsu	$\boldsymbol{z}$	Scalar uncertainty
\obsue	z	Scalar uncertainty
\sarea	A	area around pixel s
\dd	$\boldsymbol{\varphi}$	Generic diffeomorphisms
\dde	φ	Generic diffeomorphisms
\ddu	$\boldsymbol{\gamma}$	its uncertaint
\ddue	γ	its uncertaint
\udiffSp	UDiff	

articles/dptr1/structure	*Diffeo structure*
\dscommute	commute
\dsinverse	inverse

\dssame	same	
\dsvoid	void	
\SOtwo	$\mathrm{SO}(2)$	
articles/dptr1/simplification	*plan reduce*	
\plantodiff	p_to_d	
\ptod	p_to_d	
\pd	p_to_d	
\planreduce	PlanReduce	
\noutoforder	noutoforder	TODO
articles/dptr1/distances	*Distances*	
\dDiffLone	$d_{L_1}^{\mathsf{Diff}(\mathcal{S})}$	
\dUDiffLone	$\overline{d}_{L_1}^{\mathsf{UDiff}(\mathcal{S})}$	
\dobsps	$d^{\mathcal{S}}$	
\dImL{...}		
\dImLone	$d_{L_1}^{\mathsf{Im}}$	
\dImLtwo	$d_{L_2}^{\mathsf{Im}}$	
\dImN{...}		
\dImD{...}		
\cmdOrd	$\prec$	
\algoname{...}		
\gnbc	GNB	
\bnbc	BNB	
\bngc	BNG	
\bntc	BNT	
\gebc	GEB	
\bebc	BEB	
\begc	BEG	
\betc	BET	
\betcb	BETc	
\plansarea	P_{near}	
\algocover	cover	
\algoplanreduce	planreduce	
\algobidirectional	bidirectional-search	
\dubinsys	$Dubin's car$	
\orbitsys	$Orbit camera$	
\markit{...}		
\markA	†	
\markB	‡	
\markC	§	
\distthres	c	
\btrue	true	
\bfalse	false	
\botherwise	otherwise	
\cmdleft	$\boldsymbol{u}_{left}$	
\cmdright	$\boldsymbol{u}_{right}$	
\cmdup	$\boldsymbol{u}_{top}$	
\cmddown	$\boldsymbol{u}_{down}$	
\imvis	vis	Visibility
\minvis	v_0	

\maxdis	d_g	goal threshold
\impred	pred	Image prediction
\plA	$RLrl$	

articles/neucontrol	*neuromorphic control*	
\clip{...}		Clip up to some boundary
\maxu	b	
\clipu	sat_b	
\gain	κ	
\settime	$\mathbb{T}$	
\controllerLast	C1	Uses last event
\controllerTI	C2	Time integrale
\controllerTS	C3	time smoothed
\controllerTN	C4	Time neural

articles/optcam	*optimal sensor*	
\ds	Δ_s	Spatial sampling
\dt	Δ_t	Temporal sampling
\db	Δ_b	Brightness threshold
\dvsth	Δ_b	Threshold
\camexp	EX	Exposure
\mseps	$\mathrm{MSE}_{\mathrm{ps}}$	periodic sampling
\mseeb	$\mathrm{MSE}_{\mathrm{eb}}$	MSE event based
\bwps	$\mathrm{BW}_{\mathrm{ps}}$	bandwidth periodic sampling
\bweb	$\mathrm{BW}_{\mathrm{eb}}$	bandwidth event based
\ori	α	

articles/estgroups	*Estimation with symmetries*

articles/estgroups/state	*State*	
\esSt	$\boldsymbol{x}$	State
\esStDim	n	Dimension of state space
\esStSp	$\mathcal{X}$	State space
\esStDist	$\mu_{\boldsymbol{x}}^{\mathcal{X}}$	Prior for state

articles/estgroups/observations	*Observations*	
\esObs	$\boldsymbol{y}$	Observations
\esObsDim	m	Observations dimensions
\esObsSp	$\mathcal{Y}$	Observations space
\esObsMap	h	Observation map
		$\boldsymbol{y} = \boldsymbol{n}h(\boldsymbol{x})$
		`$\esObs = \esNuis \esObsMap(\esSt)$`

articles/estgroups/nuisances	*Nuisances*	
\esNuis	$\boldsymbol{n}$	Nuisance
\esNuisSp	N	Nuisance group
\esNuisDist	$\mu_{\boldsymbol{n}}^{\mathrm{N}}$	Nuisance distribution

articles/estgroups/estimators	*Estimators, risks and performances*	
\esEst	m	Estimator
\esEstSp	$\mathcal{M}$	Estimator set

\esEstSpOpt	$\mathcal{M}^\star$	Optimal subset of estimators
\esRisk	e	Risk function
\esRiskSp	$\mathcal{E}$	Risk space
\esRiskDist{...}		Risk distribution for given estimator
\esRiskDistPO	$\preceq$	Partial order defining preference on dis
\esProb	$\mathcal{P}$	Estimation problem

articles/estgroups/symmetries	*Symmetries in the problem*	
\esStAb	$\boldsymbol{\alpha}$	Abstract state
\esStAbSp	$\mathcal{A}$	Abstract space
\esRep	φ	Representation
	$\varphi : \boldsymbol{x} \mapsto \boldsymbol{\alpha}$.	
	\$\esRep: \esSt \mapsto \esStAb\$.	
\esStSym	A	Group of symmetries of the state
\esObsSym	B	Group of symmetries of the observatio
\esRiskSym	C	Group of symmetries of the risk functi
\esPOSym	D	Group of symmetries acting on the par
\esProbSym	$\mathcal{S}$	Tuple of symmetries

articles/groupspectral	*Group spectral properties*	
\gsHom	HomMaps	Induced homomorphisms.
\gsImage	Image	
\gsEqs	EqSet	Fixed points of a function.
\gsGA	GrAct	If the function is the action of a group.
\gsGAsym	$\|\|$	Used to specify that a function can be
\gsSym	Sym	Set of symmetries
\gsStrongCan	SCan	Strong canonization operator
\gsWeakCan	WCan	Weak canonization operator
\gsEquiCan	BCan	Bold canonization operator
\gsEndoCan	MCan	Mild canonization operator
\gsUnCan	UCan	Unstructured canonization operator
\gsNuis	Sample	
\regular	regular	
\unstr	$\sim$	Unstructured symbol.
\jokFunc	$\star$	Joker function
\zerFunc	0	Zero function

articles/groupspectral/defs	*Group spectral properties*	
\gsdContravariant	$\xrightarrow{-1}$	Contravariance
\gsdInvariant	$\xrightarrow{0}$	Invariance
\gsdEquivariant	$\xrightarrow{\mathsf{Id}}$	Equivariance
\gsdIntroduces	$\xrightarrow{\star}$	Nuisance introduced
\gsdUnstructured	$\xrightarrow{\sim}$	Unstructured result

articles/invariances	*Invariances*	
\rndual{...}		Dual of a representation nuisance
\brel	$\leq_B$	Simulation partial order
\bsim	$\sim_B$	Simulation relation

articles/jbds	*Symbols introduced in JBDS*

\veh	B	A vehicle body
\vehBody	B	A vehicle body
\vehKin	K	Vehicle kinematics
\vehSensPos	$\boldsymbol{r}$	Sensor relative pose
\vehSensFun	ψ	Function that defines an exteroceptive
\env	e	Environment
\envSp	$\mathcal{E}$	Environment space
\envo	$\mathcal{O}$	Obstacles in the environment
\envt	$\mathcal{T}$	Texture (function on $\partial\mathcal{O}$)
\envf	$\mathcal{F}$	Field sensed by field sampler
\envob	$\partial\mathcal{O}$	Obstacles boundaries
\obspsDiff	$\mathcal{S}^{\mathrm{dif}}$	
\obspsNotDiff	$\mathcal{S}^{\overline{\mathrm{dif}}}$	
\sic	VS	ideal camera
\sir	RF	ideal range finder
\sif	FS	ideal field sampler
\sicV	VS($\mathcal{V}$)	ideal camera with viewport
\sirV	RF($\mathcal{V}$)	ideal range finder with viewport
\sifV	FS($\mathcal{V}$)	ideal field sampler with viewport
\zoh{...}		Zero order hold
articles/jbds/misc	*Used in proofs for JBDS*	
\ygneig	N	A neighborhoood of $\boldsymbol{y}_\circ$.
articles/jbds/robots		
\allrobots	Robots	The set of all robots
\vehRob	ISV	Idealized Simple Vehicles
\vehRobNuis	$\tilde{\mathsf{ISV}}$	Vehicle robots with nuisances
\robVeh	ISV	
articles/optbody	*Optimal design of body and mind*	
\MA	$\mathbf{A}$	
\MB	$\mathbf{B}$	
\MC	$\mathbf{C}$	
\MG	$\mathbf{G}$	
\MH	$\mathbf{H}$	
\ML	$\mathbf{L}$	
\MQ	$\mathbf{Q}$	
\MP	$\mathbf{P}$	
\MS	$\mathbf{S}$	
\MSigma	$\mathbf{\Sigma}$	
\MV	$\mathbf{V}$	
\MW	$\mathbf{W}$	
\SP	P_{s}	Sensing power
\AP	P_{a}	Actuation power
\SE	E	Stored energy
\ER	r	Trajectory efficiency ratio
\HP	Θ	Heading precision
\np	n	Number of pixels

graphs	*Graphs*	
\paths	paths	All paths in a graph
\walks	walks	All paths in a graph
\head	head	
\tail	tail	
\nodes	nodes	nodes in a walk
\edges	edges	edges in a walk
\sources	sources	
		sources(cG) $\sources(\cG)$
\sinks	sinks	
		sinks(cG) $\sinks(\cG)$
\predecessors	predecessors	predecessors of a node
		predecessors(cn) $\predecessors(\cn)$
\successors	successors	successors of a node
		predecessors(cn) $\predecessors(\cn)$

articles/ragh	*Resource Allocation problem*	
\clatency	latency	
\cperiod	period	

articles/ragh/rgraph	*Resource Graph*	
\rN	rN	A resource graph's vertices
\rE	rE	A resource graph's edges
\rG	rG	A resource graph
\rn	rn	A resource node
\rnops	rn.capacity	A resource
\rnA	rn_1	
\rnAops	rn_1.capacity	
\rnB	rn_2	
\rnBops	rn_2.capacity	
\re	re	A resource edge
\relink	re.link	A resource
\relatency	re.latency	
\rebandwidth	re.bandwidth	
\reA	re_1	
\reB	re_2	
\reAlatency	re_1.latency	
\reAbandwidth	re_1.bandwidth	
\reBbandwidth	re_2.bandwidth	

articles/ragh/cgraph	*Computation Graph*	
\cG	cG	A computationg graph
\cN	cN	A cgraph's vertices
\cE	cE	A cgraph's edges
\cn	cn	A computation node
\cnops	cn.ops	A computation node's ops
\cnA	cn_1	

\cnB	cn_2	
\cnAops	$\mathsf{cn}_1.\mathsf{ops}$	
\cnBops	$\mathsf{cn}_2.\mathsf{ops}$	
\cce	ce	A computation edge
\ceA	ce_1	A computation edge
\ceB	ce_2	A computation edge
\cesize	ce.size	Signal size (bytes)
\ceAsize	$\mathsf{ce}_1.\mathsf{size}$	
\ceBsize	$\mathsf{ce}_2.\mathsf{size}$	

articles/ragh/links	*Physical links*	
\PL	PLinks	Physical links
\pl	pl	Physical link
\pplA	pl_1	plA conflicts
\plAlatency	$\mathsf{pl}_1.\mathsf{latency}$	
\plAbandwidth	$\mathsf{pl}_1.\mathsf{bandwidth}$	
\pllatency	pl.latency	
\plbandwidth	pl.bandwidth	

articles/ragh/allocations	*Allocations*	
\as	as	An assignment
\asm	as.m	The momomorphism
\asmn	$\mathsf{as.m}_N$	
\asme	$\mathsf{as.m}_E$	
\asmni	$\mathsf{as.m}_N^{-1}$	
\asmei	$\mathsf{as.m}_E^{-1}$	
\asmi	$\mathsf{as.m}^{-1}$	The right inverse of the momomorphis
\asla	$\mathsf{as}.\alpha$	The link allocation
\asca	$\mathsf{as}.\beta$	The computation allocation
\ctdelay	delay	Continuous-time delay
\ctsample	sample	Continuous-time sample

articles/soattotheory	*Symbols used by Soatto*	
\scene	ξ	scene
\representation	$\hat{\xi}$	representation
\minrep	$\hat{\xi}^{\vee}$	minimal representation
\feature	ϕ	feature
\maxinv	$\phi^{\wedge}$	maximal invariant feature
\suffstat	$\phi^{\vee}$	maximal invariant feature
\image	$\mathcal{I}$	image
\addnoise	n	additive noise
\imageform	h	image formation function
\groupnuis	g	nuisance which have the structure of a
\othernuis	ν	other non-invertible nuisance
\lightfield	$\mathcal{L}$	all possible images generated by a scen
\complex	H	Complexity measure
\actinfo	$\mathcal{H}$	Actionable information
\covdet	ψ	Covariant detector

articles/soattotheory/mseerep	*msee report*	
\nuddisc{...}		Domain sampling operator (subset)

\nusample{...}		Domain sampling operator (subset)
\nuvdisc{...}		Value Discretization operator (subset)
\nusmooth{...}		Smoothing operator (kernel)
\nucens{...}		Censoring operator (field of view)
\nuoccl{...}		Occlsions
\imform	I	
\contrast	f	

articles/thesis	*Special symbols for thesis*	
\labelrefinement	ref	Indicates a refinement
\pchomeoR	$\mathsf{PieceHomeo}(\mathbb{R})$	
\dianode{...}		used in properties1.dot
\dianodem{...}		
\bitZ	$\square$	
\bitO	$\boxdot$	
\infbinstrings	$\{\square, \boxdot\}^{\mathbb{N}}$	Set of infinite binary strings
\chineseClose	(nosummary)	The Chinese character corresponding t
\twosignals	y^i, y^j	
\twosignalsa	y^i	
\twosignalsb	y^j	
\twosignalscolon	$y^i; y^j$	
\semrelorder	m	Order of a generic semantic relations
\infinit	d	Infinitesimal
\genericsemrel	$\mathcal{R}$	A generic semantic relation.
\gensemrelsym	$\mathsf{Sym}(\mathcal{R})$	Symmetries of the semantic relation
\genericsimilarity	R	A generic similarity measure.
\obsecdf	c	CDF of one sensel
\cmdreverse	ρ	The map from a command to its revers
\cmdopt	$\boldsymbol{u}^\star$	The optimal command
\cmdnop	$\boldsymbol{u}^{\mathsf{nop}}$	Command corresponding to "resting".
\rew	R	Reward function
\placeneig	$\mathsf{Neighbors}$	
\genericrel	$\sim$	Generic relation
\notgenericrel	$\not\sim$	

articles/thesis/longexample	*Long example*
\CalibA	CalibA
\CalibB	CalibB
\Smoothkernel	k
\Smooth	Smooth_k
\BGDSAg	$\mathsf{BGDSagent}$
\BGDSAgS	$\mathsf{BGDSagentS}$
\DImagesU	$\mathcal{D}(\mathsf{Im}(\mathcal{S}); \mathcal{U})$
\DImagesR	$\mathcal{D}(\mathsf{Im}(\mathcal{S}); \mathbb{R}^{n_{\boldsymbol{u}}})$
\ABehavior	*behavior*
\DImagesSphU	$\mathcal{D}(\mathsf{Im}(\mathbb{S}^2); \mathcal{U})$
\hobs	$\boldsymbol{x}$
\hobse	x
\bound	M

common	*Common symbols to all papers*

common/abbreviations	*Other abbrevations*
\setA	$\mathcal{A}$
\setB	$\mathcal{B}$
\setC	$\mathcal{C}$
\setU	$\mathcal{U}$
\setM	$\mathcal{M}$
\setY	$\mathcal{Y}$
\setX	$\mathcal{X}$
\setZ	$\mathcal{Z}$
\setS	$\mathcal{S}$
\grG	G
\grH	H
\grK	K
\grN	N

common/abbreviations/invariances/abbreviations	
\sqa	$\boldsymbol{a}$
\sqae	a
\sqb	$\boldsymbol{b}$
\sqbe	b
\sqc	$\boldsymbol{c}$
\sqce	c

common/acronyms	*Acronyms*

common/algebra	*Algebra*	
\ones	$\mathbf{1}$	
\idMat	$\mathbf{I}$	Identity matrix
\matTrace	Tr	Trace of a matrix.
\angleFun	$\angle$	Angle function
\flatten	vec	Matrix-to-vector rearrangement.

common/basic	*Basic stuff*	
\setfun	$\rightrightarrows$	Symbol for set functions (one-to-many)
\algfield	field	Field.
		$\mathsf{field}(\mathcal{X}, +, \times)$ is an algebraic field. `$\algfield(\aset{X},+,\times)$ is an field.`
\wellorder	$\mathsf{wellorder}$	A well ordered set.
		$\mathsf{wellorder}(\mathcal{X}, \leq)$ is a well-ordered set. `$\wellorder(\aset{X},\leq)$ is a well set.`
\orderedfield	$\mathsf{orderedfield}$	A well ordered field.
		$\mathsf{orderedfield}(\mathcal{X}, +, \times, \leq)$ is a well-ordere `$\orderedfield(\aset{X},+,\times,\le well-ordered field.`
\powerset	$\mathsf{powerset}$	Power set of a space
\supp	supp	Support of a set
\idFunc	Id	The identity function
\invFunc	$\cdot^{-1}$	Inverse function

\funcComp	$\circ$	Function composition
\emptysequence	$\emptyset$	Empty sequence
\allFuncs	Functions	All maps from a space to the other
\D	d	Used for integrals
\sign	sgn	Sign function

common/sequences	*Sequences*	
\sequences	Sequences	Set of sequences
\contsequences	ContSequences	Set of continuous sequences
\Aut	Aut	Automorphism group
\contFuncs	Continuous	Continuous functions on some metric s
	Continuous($\mathcal{A}$) are all continuous funct $\contFuncs(\setA)$ are all continuo on $\setA$.	
\differFuncs	Differentiable	Differentiable functions
\partitions	partitions	
\mExp	mexp	Matrix exponential
\bigO	$\mathcal{O}$	Big-O notation
\smallo	o	
\metricon{...}		
\definedas	$\triangleq$	
\crossprod	$\times$	cross-product
\gsDom	Domain	
\gsCod	Codomain	
\interCC{...,...}		
\interCO{...,...}		
\interOC{...,...}		
\interOO{...,...}		
\unitInterval	$[0,1]$	

common/basic/logic	*Logic*	
\logicAnd	$\wedge$	Logic "and"
\logicOr	$\vee$	Logic "or"
\logicNot	$\neg$	Logic "not"

common/simplesets	*Simple sets*	
\reals	$\mathbb{R}$	Real numbers
\natnumbers	$\mathbb{N}$	Natural numbers
\ratnumbers	$\mathbb{Q}$	Rational numbers
\hreals	$*\mathbb{R}$	Hyper-real numbers
\nonNegReals	$\mathbb{R}_{\bullet}^{+}$	Non negative reals
\posReals	$\mathbb{R}_{\circ}^{+}$	Strictly positive reals
\nzReals	$\mathbb{R}_{\circ}$	Nonzero reals

common/blackboxes	*Black boxes*	
\abb{...}		A black box
\bbD	$\boldsymbol{D}$	
\bbinv{...}		Inverse of a black box
\bbli{...}		left inverse of a black box
\bbri{...}		right inverse of a black box
\alloutcomes	AllOutcomes	

\alloutputs	AllOutputs	All outputs of a given system
\bbDelay	Δ	The one-step delay system.
\vertblock	$\mid$	
\bbAccum	$\mid\!\mid\!\mid$	Accumulator system
\inLoop	Loop	Closes the loop around a system
\idSys	IdSys	The identity system
\bbSp	$\mathcal{D}$	Set of black boxes
		$\mathcal{D}(\mathcal{X};\mathcal{Y})$ are all the black boxes from $\mathcal{X}$
		`$\bbSp(\setX;\setY)$ are all the bla`
		`from $\setX$ to $\setY$.`
\bbFM	$\mathcal{D}_{\mathsf{fm}}$	Systems with finite memory
\bbSpInv	$\mathcal{D}^\star$	Set of invertible systems
\bbFMinv	$\mathcal{D}^\star_{\mathsf{fm}}$	Systems with finite memory and invert
\bbSpIns	$\mathcal{D}_{\text{inst}}$	Set of instantaneous systems
\bbSpDet	$\mathcal{D}_{\text{det}}$	Deterministic systems
\bbSpInvIns	$\mathcal{D}^\star_{\text{inst}}$	Set of invertible and instantaneous syst
		$\mathcal{D}^\star(\mathcal{A})$ is a subset of $\mathcal{D}(\mathcal{A};\mathcal{A})$
		`$\bbSpInv(\setA)$ is a subset of`
		`${\bbSp(\setA;\setA)}$`
\bbSpCore	$\mathcal{D}^\circ$	Systems up to representation
common/blackboxes/abbreviations		
\bbDinv	$\boldsymbol{D}^{-1}$	
\bbDri	$\boldsymbol{D}^{R}$	
\bbDli	$\boldsymbol{D}^{L}$	
\bbE	$\boldsymbol{E}$	
\bbF	$\boldsymbol{F}$	
\bbG	$\boldsymbol{G}$	
\bbH	$\boldsymbol{H}$	
\bbL	$\boldsymbol{L}$	
\bbSpBA	$\mathcal{D}(\mathcal{B};\mathcal{A})$	**to write**
\bbSpAB	$\mathcal{D}(\mathcal{A};\mathcal{B})$	**to write**
common/blackboxes/deprecated	*Deprecated*	
\bbOp	$\oplus$	Composition operation
\inSeries	Series	Series of two systems
\bbSpAny	$\mathcal{D}_*$	Any of the following
\bbSpDT{...}		Discrete time
\bbSpCT	$\mathcal{D}^{\text{c}}$	Continuous time
\bbSpEB	$\mathcal{D}^{\text{e}}$	Event-based
common/boot	*Bootstrapping symbols*	
common/boot/obscmd	*Observations and commands*	
\world	m	The "world", an element of $\mathcal{D}(\mathcal{Y};\mathcal{U})$.
\obs	$\boldsymbol{y}$	Observations vector.
\obse	y	Observations element.
\cmd	$\boldsymbol{u}$	Commands vector.
\cmde	u	Commands element.
\nobs	$n_{\boldsymbol{y}}$	Number of sensels
\ncmd	$n_{\boldsymbol{u}}$	Number of actuators

\obsSp	$\mathcal{Y}$	Observation space
\cmdSp	$\mathcal{U}$	Commands space
\cmdSph	$\overline{\mathcal{U}}$	Domain of a single actuator $\mathcal{U} = \overline{\mathcal{U}}^{n_{\boldsymbol{u}}}$.
\obsSph	$\overline{\mathcal{Y}}$	Domain of a single sensel $\mathcal{Y} = \overline{\mathcal{Y}}^{n_{\boldsymbol{y}}}$.
\obsSphd	$d^{\overline{\mathcal{Y}}}$	Metric on $d^{\overline{\mathcal{Y}}}$
\obsSpd	$d^{\mathcal{Y}}$	Metric on $d^{\mathcal{Y}}$

common/boot/spatialsensors	*Spatial sensors*	
\obssp	$\mathcal{S}$	Observation physical space.
\obsps	$\mathcal{S}$	Observation physical space.
\genimages	Im	Images on physical space $\mathcal{S}$.
\imps	$\mathsf{Im}(\mathcal{S})$	Images on physical space $\mathcal{S}$.

common/boot/servo	*Servoing*	
\obsgmark	$\circ$	
\obsg	$\boldsymbol{y}_\circ$	Goal observations.
\obsge	$y_\circ$	Goal observations (element).
\obsgl	$\boldsymbol{z}_\circ$	Goal observations (element).
\obsgle	$z_\circ$	Goal observations (element).

common/boot/abbreviations	*Abbreviations*	
\bbSpYU	$\mathcal{D}(\mathcal{Y};\mathcal{U})$	**to write**
\bbSpYXU	$\mathcal{D}(\mathcal{Y};\mathcal{X};\mathcal{U})$	**to write**
\bbSpUY	$\mathcal{D}(\mathcal{U};\mathcal{Y})$	**to write**
\bbSpInvY	$\mathcal{D}^\star(\mathcal{Y})$	Representation nuisances on command
\bbSpInvU	$\mathcal{D}^\star(\mathcal{U})$	Representation nuisances on observatio
\bbSpInvYU	$\mathcal{D}^\star(\mathcal{Y};\mathcal{U})$	Representation nuisances
\bbSpInvUY	$\mathcal{D}^\star(\mathcal{U};\mathcal{Y})$	
\bbSpCoreYU	$\mathcal{D}^\circ(\mathcal{Y};\mathcal{U})$	Systems up to representation

common/vehicles	*The Vehicles universe*	
\veEnvironments	Environments	All Vehicles environments
\veSensors	Sensors	all Vehicles sensors
\veDynamics	Dynamics	all Vehicles dynamics
\veVehicles	Vehicles	

common/vehicles/mah	*todo*	
\veSce	S	
\veVeh	V	
\veMov	M	
\veAdd	A	
\veJoi	J	
\vePar	P	Parallel composition of sensors
\veNcmd	U	
\veNobs	Y	

common/expressions	*Miscellaneous expressions*
\etal	*et al.*
\eg	*e.g.*,
\etc	*etc.*
\ie	*i.e.*,

\viceversa	*viceversa*	
\vs	*vs*	Versus
\adhoc	*ad hoc*	
\apriori	*a priori*	

common/goodformulas	*Better formulas annotations*	
\expl{...}		Explanation in formulas
\highA{...}		Highlight something in formulas (obser
\highB{...}		Highlight something in formulas (comm
\highC{...}		both observations and commands

common/yesorno	*Miscellaneous functions for document formatting*	
\ns		
\tickYes	✓	
\tickNo	7	
\NA	n/a	
\coltickNo	7	
\yes	✓	
\no	7	
\onehalf	$\frac{1}{2}$	small one half
\smPO	$+1$	Small plus one
\smMO	-1	Small minus one (e.g. in smallmatrix)

common/incomplete	*Incomplete symbols*	
\towrite	**to write**	Marker for sections to write
\placeholder{...,...}		A placeholder
\tocite{...}		
\citeboh	[*xxx*]	
\citexxx	[*xxx*]	
\xxx	*???*	
\XXX	*???*	
\notsure	**(Not sure...)**	
\dontlike	**(Don't like this)**	
\notformal	**(not formal)**	
\betterword{...}		
\boh	*???*	incomplete
\bn		bad notation, this should change later
\checkbadformat		incomplete
\prooftowritesomeday		
\myrule{...,...}		
\unitInverval	$[0,1]$	

common/geometry	*Differential geometry*	
\diff	Diff	Diffeomorphism

		Diff($\mathcal{M}$) are the diffeomeorphisms from
		`$\diff(\aset{M})$ are the diffeomeor`
		`$\aset{M}$ to itself.`

\diffPos	Diff_+	Orientation-preserving diffeomorphism
\homeoPos	Homeo_+	Orientation-preserving homeomorphism
\diffBounded{...}		Diffeomorphisms with bounded curvatu
\diffVol	$\mathsf{Diff}_{\mathrm{vol}}$	

\homeo	Homeo	Set of all homeomorphisms
\isometries	Isom	Isometries group
		Isom($\mathcal{M}$) are all the isometries of $\mathcal{M}$.
		`$\isometries(\aset{M})$ are all the of $\aset{M}$.`
\diffFix{...}		Diffeomorphisms that fix a point
\conformalFuncs	Conformal	Conformal transformations
common/geometry/manifolds	*Manifolds*	
\Sone	$\mathbb{S}^1$	Unit circle.
\Stwo	$\mathbb{S}^2$	Unit sphere.
\stwo	$\mathbb{S}^2$	Unit sphere
\hypsp	$\mathbb{H}$	
\hypspn	$\mathbb{H}^n$	
common/groups	*Group theory*	
\gIdentity	e	Identity of a group
\tgroup	group	Group set with operations
		group($\mathrm{G}, \cdot$) means G is a group under $\cdot$
		`$\tgroup(\agroup{G},\cdot)$ means $\ is a group under $\cdot$.`
\haar	haar	Haar measure
		The Haar measure on $\mathcal{X}$ is $\mathsf{haar}^{\mathcal{X}}$.
		`The Haar measure on $\aset{X}$ is ${`
common/groups/famous	*Famous groups*	
\idGroup	Id	The trivial group with identity only.
\permutations	Perm	Set of permutation
\stab{...}		Stabilizer of a set
\functionsym{...}		Symmetries of a function
\allsubgroups	AllSubgroups	
\comgroup{...}		Commutator sub group
\groupJoin	$\vee$	Group join
\groupconj{...}		Conjugation
\groupquotient	/	Group quotient
\groupsemidir	$\rtimes$	Semidirect product.
\groupisom	$\cong$	Isomorphism
\issubgroup	$\leq$	Subgroup relation.
\normalsub	$\lhd$	Normal subgroup relation
\actionsymbol	$\cdot$	Group action.
\companionFuncs{...}		Companions functions
\transversalFuncs{...}		Transversal functions
common/groups/matrix	*Matrix groups*	
\orthogroup	O	Orthogonal group.
\trangroup	T	Translation group
\segroup	SE	Special Euclidean group.
\Egroup	E	Euclidean group.
\SLgroup	SL	Special linear group
\Diaggroup	D	Diagonal matrices with non-zero eleme
\PMgroup	$\mathsf{D}_{\pm}$	Diagonal matrices with ± 1 on the diag

\Scalegroup	Sc	Multiples of the identity
\sogroup	SO	Special orthogonal group.
\soneggroup	SO^-	
\affgroup	Aff	Affine group
\affgrouppos	Aff_+	Affine group
\GL	GL	General linear group
\GLpos	GL_+	
\se	se	Special Euclidean algebra
\soalgebra	so	
\sealgebra	se	Special Euclidean algebra
\SOthree	$\mathrm{SO}(3)$	Special orthogonal group (rotation mat
\SEthree	$\mathrm{SE}(3)$	Special Euclidean group
\SEtwo	$\mathrm{SE}(2)$	Special Euclidean group
\SEthreeAlg	$\mathsf{se}(3)$	
\SEtwoAlg	$\mathsf{se}(2)$	
\SOthreeAlg	$\mathsf{se}(3)$	
\SOtwoAlg	$\mathsf{se}(2)$	
\setwo	$\mathrm{SE}(2)$	
\sethree	$\mathrm{SE}(3)$	
\sotwo	$\mathrm{SO}(2)$	
\sothree	$\mathrm{SO}(3)$	

common/groups/simple	*Very simple groups*	
\mgroup	$(\mathbb{R}_\circ, \times)$	Multiplication group
\mposgroup	$(\mathbb{R}_\circ^+, \times)$	Positive multiplication group
\mpmgroup	$(\pm 1, \times)$	+1/-1 multiplication group
\addgroup	$(\mathbb{R}, +)$	Addition group

common/groups/simple/abbreviations	*Abbreviations*	
\addgroupn	$(\mathbb{R}^n, +)$	Addition group on $\mathbb{R}^n$
\affone	$\mathsf{Aff}(\mathbb{R})$	Affine group 1D
\affonepos	$\mathsf{Aff}_+(\mathbb{R})$	Affine group 1D
\affn	$\mathsf{Aff}(\mathbb{R}^n)$	Affine group in n dimensions.
\affnpos	$\mathsf{Aff}_+(\mathbb{R}^n)$	Affine transformations preserving orien

common/probability	*Probability*	
\uniformdist	Uniform	Uniform distribution
\measuresupport	Support	Support of a probability measure
\processes	StocProcesses	Set of stochastic processes
\conditional	Conditional	Conditional distribution
		Conditional$(\mathcal{B};\mathcal{A})$ is the set of conditi tions `$\conditional(\setB;\setA)$ is the s conditional distributions`
\finaldist	Final	Stationary distribution of a stochastic
\measureSp	meas	Measure space.
		meas$(\mathcal{X}, \Sigma, \mu)$ is a measure space. `$\measureSp(\aset{X},\Sigma,\mu)$ is space.`
\probSp	prob	Probability space.

		prob$(\mathcal{X}, \Sigma, \mu)$ is a probability space. `$\probSp(\aset{X},\Sigma,\mu)$ is a space.`
`\measures`	Measures	Set of probability measures on a set.
		Try $\mu^{\mathcal{X}} \in$ Measures$(\mathcal{X})$ `Try $\mu^{\aset{X}} \in \measures(\as`
`\dirac`	δ	
`common/robotics`	*Robotics*	
`\obsip`	m	Inner product bilinear form.
`\obsosp`	$\mathcal{O}$	Observation output space.
`\dummySensel`	s	
`\pose`	$\boldsymbol{q}$	Robot pose $\boldsymbol{q} = (\boldsymbol{t}, \mathbf{R}) \in \mathcal{Q} \subset$ SE(3).
`\posesp`	$\mathcal{Q}$	Pose space, subgroup of SE(3).
`\posespAlg`	$\mathfrak{q}$	Pose space algebra.
`\confspace`	$\mathcal{Q}$	Robot configuration space
`\pos`	$\boldsymbol{t}$	Position in the world frame.
`\posEl`	t	Position in the world frame (element)
`\rotm`	$\mathbf{R}$	Rotation matrix representing orientati
`\rotme`	R	Element of rotation matrix
`\lvel`	$\boldsymbol{v}$	Linear velocity
`\lvele`	v	Linear velocity (element)
`\avel`	$\boldsymbol{\omega}$	Angular velocity (as vector)
`\avele`	ω	Angular velocity (element)
`\avels`	ω	Angular velocity in 2D (scalar)
`\avelse`	$\hat{\boldsymbol{\omega}}$	Angular velocity (as skew-symmetric m
`\njoints`	n_j	Number of joints in a robot
`\attitude`	$\mathbf{R}$	
`\position`	$\boldsymbol{t}$	
`common/robotics/fieldsmapler`	*Field samplers*	
`\field`	$\mathcal{F}$	Field sampled by the field sensor.
`\fieldpos`	$\boldsymbol{z}$	Generic position in the world.
`\fieldpose`	z	Generic position in the world.
`\worldSp`	Maps	
`common/robotics/old`	*Deprecated*	
`\wshape`	$\boldsymbol{s}$	
`\wpose`	$\boldsymbol{p}$	
`\worldsp`	Maps	
`\wshapesp`	Shapes	
`common/robotics/maps`	*New stuff*	
`\mshape`	$\boldsymbol{s}$	Map shape.
`\mpose`	$\boldsymbol{p}$	Map pose.
`\mshapesp`	Shapes	Shape space.
`\mapsp`	Maps	Maps set Maps = Shapes $\times$ SE(3).
`common/statistics`	*Misc statistics*	
`\stddev`	std	Standard deviation
`\var`	var	Variance

\ex	$\mathbb{E}$	Expected value
\corr	corr	
\cov	cov	covariance
\spearcorr	spear	Spearman correlation between two vari
\mutualinf	$\mathcal{I}$	Mutual information
\entr	$\mathcal{H}$	Entropy
\varinf	$\mathcal{V}$	Variation of information
\varinfn	$\mathcal{V}_1$	Normalized variation of information
\pushedforward{...}		Pushed forward notation
\distributedAs	$\sim$	Distributed as

common/statistics/sorting	*Sorting vectors*	
\order	order	Order (or rank) of the elements of a ve
\sorted	sorted	Sorted version of a vector
\differ	differ	
\sortedSeq	sortedSeq	
\weaksortedSeq	weaksortedSeq	

common/systems	*Dynamical systems*	
\CTI	CTI	Continuous-time time-invariant system
\DTI	DTI	Discrete-time time-invariant systems.
\DDTI	DDTI	Deterministic discrete-time time-invari
\DCTI	CDTI	Deterministic continuous-time time-inv
\DFSTI	DFSTI	Discrete-time finite-state-space time-in
\CFSTI	CFSTI	Continuous-time finite-state-space time
\DFSTIGO	DFSTIGO	Discrete-time finite-state-space time-in
\CLTI	CLTI	Continuous-time linear time-invariant s
\CLTIG	CLTIG	Continuous-time linear time-invariant s
\DLTI	DLTI	Discrete-time linear time-invariant syst
\DSMPLTI	DSMPLTI	Discrete-time stable minimum-phase li
\DLTIG	DLTIG	Discrete-time linear time-invariant syst
\laptrans	$\mathcal{L}$	Laplace transform
\impulseresp	ImpulseResp	Impulse response of a system
\transferfunc	TF	Transfer function

typography	*Basic typography*	
\myacronym{...}		All acronyms; good for text as well as

typography/tensors	*Tensors and tensor elements*	
\T{...}		Tensor
\Tel{...}		Tensor element
\Te{...}		

typography/matrices	*Matrices and matrix elements*	
\M{...}		A matrix
\Mel{...}		The elements of a matrix

typography/sets	*Sets*	
\aset{...}		A set
\agroup{...}		Fonts for a set which is a group.

A set $\mathfrak{X}$, a group X, G, …

```
A set $\aset{X}$, a group $\agroup{X
$\agroup{G}$, \dots
```

`\aseq{...}` Formatting for sequences

`\aseqe{...}` Formatting for one element in a sequen

`\dummyIndices`

`typography/misc` *Everything else*

`\aword{...}` How words should look like in formulas

Consider the operator scale, …

```
Consider the operator $\aword{scale}
```

`\vmath{...}` How words should appear in math mod