

Full Title Of Presentation

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Introduction

Examples

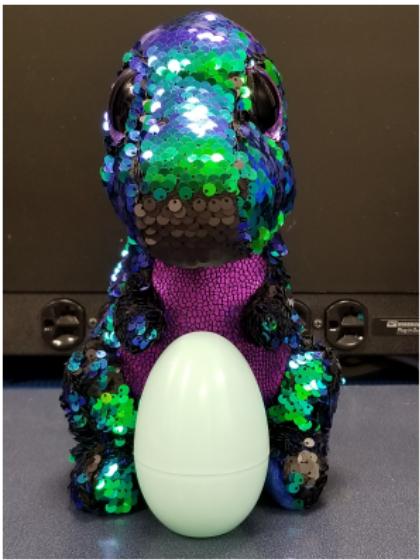


Figure 1: Rexy the PREX II
Mascot



Itemize example - A story needs at least:

- ▶ Characters
- ▶ Temporality
- ▶ And Causality
- ▶ Item 4 - An Example Table

Table 1: Example of Table - Taxonomy of human intent prediction

Human		Execution Strategy (Action)	
		Observer Knows	Observer Unknown
Objective Function	Observer Knows	All is Known (e.g. Ping Pong) where both objective and actions are clear	Human Action Model is unclear or suboptimal (e.g. chess)
	Observer Unknown	Human action model is well known, but objective is not (e.g. joy-riding in car or free running, where destination or direction is unclear)	Poor action model and objective function (e.g. Poor / good cook, no idea of final dish)

- ▶ Tables can be referenced as Table 1

Introduction (cont.)

Example of a figure, shown in Figure 2.

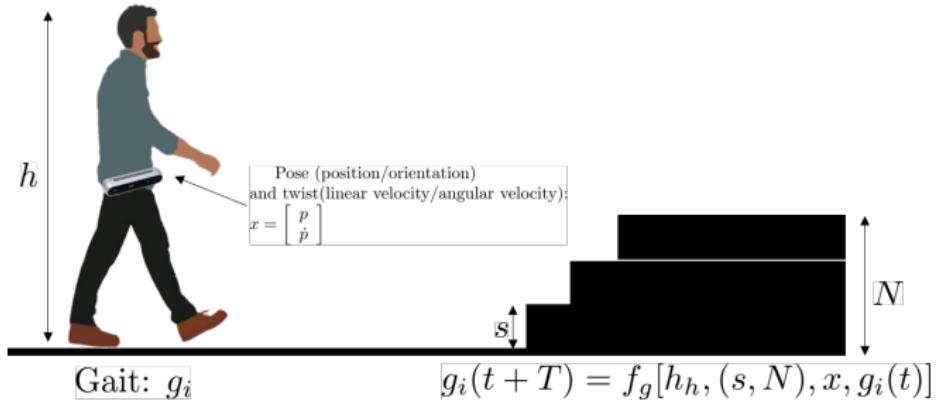


Figure 2: Example Figure

Example of Horizontal Subfigures



(a) Single Kinect setup for fall prevention in elderly residence



(b) Multiple Kinects calibration for fall prediction

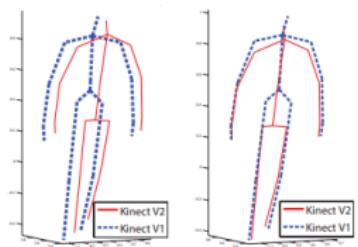


Figure 3: Examples of Horizontal Subfigures

Example of Horizontal Alignment

Example of Horizontal Alignment of a table and a figure.

Table 2: Environment limitations on data collection

	Kinect	Stereo	Kinect + Stereo
Indoor	✓	✓	✓
Outdoor	✗	✓	✓
High number of features	✓	✓	✓
Low number of features	✓	✗	✓





Example of resizable equations

$$\min \quad J = \int (a_{real} - \hat{a})^2$$

subject to

- human kinematics
- no collision
- no falling



Example of Regular Equations

$${}^A R_B(t_0) = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{bmatrix} + \sin(\theta) \begin{bmatrix} 0 & -v_3 & v_2 \\ v_3 & 0 & -y_1 \\ -v_2 & v_1 & 0 \end{bmatrix} + (1 - \cos(\theta)) \begin{bmatrix} 0 & -v_3 & v_2 \\ v_3 & 0 & -v_1 \\ -v_2 & v_1 & 0 \end{bmatrix}^2 \quad (1)$$

$${}^A R_B(t) = \Delta R {}^A R_B(t_0) \quad (2)$$

$$\Delta R = {}^A R_B(t) {}^A R_B^T(t_0) \quad (3)$$

Example of Video



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