Fisher Information based Disambiguation of Human Intent - An Experimental Evaluation

Author Names Omitted for Anonymous Review. Paper-ID [**163**]

Abstract—The abstract goes here.

I. INTRODUCTION

This demo file is intended to serve as a "starter file" for the Robotics: Science and Systems conference papers produced under LaTeX using IEEEtran.cls version 1.7a and later.

II. RELATED WORK

Section text here.

III. MATHEMATICAL FORMALISM

A. Disambiguation Schemes

1) *Fisher Information Based Metric:*
2) *Entropy-based Metric:*
3) *Heuristic-based Metric:*

B. Intent inference

1) *Dynamic Field Theory Based:*
2) *Bayesian Inference:*
3) *Confidence Functions:*

C. Shared Control

IV. EXPERIMENTAL EVALUATION

V. RSS CITATIONS

Please make sure to include `natbib.sty` and to use the `plainnat.bst` bibliography style. `natbib` provides additional citation commands, most usefully `\citet`. For example, rather than the awkward construction

```
\cite{kalman1960new} demonstrated...
```

rendered as "[1] demonstrated...," or the inconvenient

```
Kalman \cite{kalman1960new}
demonstrated...
```

rendered as "Kalman [1] demonstrated...", one can write

```
\citet{kalman1960new} demonstrated...
```

which renders as "Kalman [1] demonstrated..." and is both easy to write and much easier to read.

A. RSS Hyperlinks

This year, we would like to use the ability of PDF viewers to interpret hyperlinks, specifically to allow each reference in the bibliography to be a link to an online version of the reference. As an example, if you were to cite "Passive Dynamic Walking" [2], the entry in the bibtex would read:

```
@article{McGeer01041990,
  author = {McGeer, Tad},
  title = {\href{http://ijr.sagepub.com/content/9/2/62.a
  volume = {9},
  number = {2},
  pages = {62-82},
  year = {1990},
  doi = {10.1177/027836499000900206},
  URL = {http://ijr.sagepub.com/content/9/2/62.abstract}
  eprint = {http://ijr.sagepub.com/content/9/2/62.full.p
  journal = {The International Journal of Robotics Resea
}
```

and the entry in the compiled PDF would look like:

[1] Tad McGeer. Passive Dynamic Walking. *The International Journal of Robotics Research*, 9(2):62–82, 1990.

where the title of the article is a link that takes you to the article on IJRR's website.

Linking cited articles will not always be possible, especially for older articles. There are also often several versions of papers online: authors are free to decide what to use as the link destination yet we strongly encourage to link to archival or publisher sites (such as IEEE Xplore or Sage Journals). We encourage all authors to use this feature to the extent possible.

VI. CONCLUSION

The conclusion goes here.

ACKNOWLEDGMENTS

REFERENCES

[1] R.E. Kalman. A new approach to linear filtering and prediction problems. *Journal of Basic Engineering*, 82 (1):35–45, 1960.

[2] Tad McGeer. Passive Dynamic Walking. *The International Journal of Robotics Research*, 9(2):62–82, 1990. doi: 10. 1177/027836499000900206. URL http://ijr.sagepub.com/ content/9/2/62.abstract.