CODE BOOK

Code Book for the tidy_data file corresponding to the project to be completed during the Getting And Cleaning Data Coursera MOOC.

The features selected for this database come from the accelerometer and gyroscope 3-axial raw signals tAcc-XYZ and tGyro-XYZ. These time domain signals (prefix 't' to denote time) were captured at a constant rate of 50 Hz. Then they were filtered using a median filter and a 3rd order low pass Butterworth filter with a corner frequency of 20 Hz to remove noise. Similarly, the acceleration signal was then separated into body and gravity acceleration signals (tBodyAcc-XYZ and tGravityAcc-XYZ) using another low pass Butterworth filter with a corner frequency of 0.3 Hz.

Subsequently, the body linear acceleration and angular velocity were derived in time to obtain Jerk signals (tBodyAccJerk-XYZ and tBodyGyroJerk-XYZ). Also the magnitude of these three-dimensional signals were calculated using the Euclidean norm (tBodyAccMag, tGravityAccMag, tBodyAccJerkMag, tBodyGyroMag, tBodyGyroJerkMag).

Finally a Fast Fourier Transform (FFT) was applied to some of these signals producing fBodyAcc-XYZ, fBodyAccJerk-XYZ, fBodyGyro-XYZ, fBodyAccJerkMag, fBodyGyroMag, fBodyGyroJerkMag. (Note the 'f' to indicate frequency domain signals).

These signals were used to estimate variables of the feature vector for each pattern.

'-XYZ' is used to denote 3-axial signals in the X, Y and Z directions.

Here, the mean value (mean()) and the standard deviation (std()) are given for each of the following measures:

```
"tBodyAcc-mean()-X"
```

[&]quot;tBodyAcc-mean()-Y"

[&]quot;tBodyAcc-mean()-Z"

[&]quot;tBodyAcc-std()-X"

[&]quot;tBodyAcc-std()-Y"

[&]quot;tBodyAcc-std()-Z"

[&]quot;tGravityAcc-mean()-X"

[&]quot;tGravityAcc-mean()-Y"

[&]quot;tGravityAcc-mean()-Z"

[&]quot;tGravityAcc-std()-X"

[&]quot;tGravityAcc-std()-Y"

[&]quot;tGravityAcc-std()-Z"

[&]quot;tBodyAccJerk-mean()-X"

[&]quot;tBodyAccJerk-mean()-Y"

[&]quot;tBodyAccJerk-mean()-Z"

[&]quot;tBodyAccJerk-std()-X"

[&]quot;tBodyAccJerk-std()-Y"

[&]quot;tBodyAccJerk-std()-Z"

[&]quot;tBodyGyro-mean()-X"

[&]quot;tBodyGyro-mean()-Y"

```
"tBodyGyro-mean()-Z"
```

[&]quot;tBodyGyro-std()-X"

[&]quot;tBodyGyro-std()-Y"

[&]quot;tBodyGyro-std()-Z"

[&]quot;tBodyGyroJerk-mean()-X"

[&]quot;tBodyGyroJerk-mean()-Y"

[&]quot;tBodyGyroJerk-mean()-Z"

[&]quot;tBodyGyroJerk-std()-X"

[&]quot;tBodyGyroJerk-std()-Y"

[&]quot;tBodyGyroJerk-std()-Z"

[&]quot;tBodyAccMag-mean()"

[&]quot;tBodyAccMag-std()"

[&]quot;tGravityAccMag-mean()"

[&]quot;tGravityAccMag-std()"

[&]quot;tBodyAccJerkMag-mean()"

[&]quot;tBodyAccJerkMag-std()"

[&]quot;tBodyGyroMag-mean()"

[&]quot;tBodyGyroMag-std()"

[&]quot;tBodyGyroJerkMag-mean()"

[&]quot;tBodyGyroJerkMag-std()"

[&]quot;fBodyAcc-mean()-X"

[&]quot;fBodyAcc-mean()-Y"

[&]quot;fBodyAcc-mean()-Z"

[&]quot;fBodyAcc-std()-X"

[&]quot;fBodyAcc-std()-Y"

[&]quot;fBodyAcc-std()-Z"

[&]quot;tBodyGyroMag-sma()"

[&]quot;tBodyGyroMag-energy()"

[&]quot;tBodyGyroMag-iqr()"

[&]quot;tBodyGyroMag-entropy()"

[&]quot;tBodyGyroMag-arCoeff()1"

[&]quot;tBodyGyroMag-arCoeff()2"

[&]quot;fBodyGyro-mean()-X"

[&]quot;fBodyGyro-mean()-Y"

[&]quot;fBodyGyro-mean()-Z"

[&]quot;fBodyGyro-std()-X"

[&]quot;fBodyGyro-std()-Y"

[&]quot;fBodyGyro-std()-Z"

[&]quot;fBodyAccMag-mean()"

[&]quot;fBodyAccMag-std()"

[&]quot;fBodyBodyAccJerkMag-mean()"

[&]quot;fBodyBodyAccJerkMag-std()"

[&]quot;fBodyBodyGyroMag-mean()"

[&]quot;fBodyBodyGyroMag-std()"

[&]quot;fBodyBodyGyroJerkMag-mean()"

[&]quot;fBodyBodyGyroJerkMag-std()"