You are a MIT student although you are at KIST, and is there any reason for the affiliation?

In Korea, normally your professor can also be included in the author list. What’s your opinion?

III. Human Model,

* In robotics society, q is basically implies the joint angle in most cases, could you change it as one of r, d or p for position?  
  Is q just a length, not coordinates ?
* In figure 1, could you add joints with just small circles and legends to represent the proximal joints Ji and distal joint Jj for easy understanding?
* Equation 1 is hard to understand.  
  Is it normalized by the total mass?  
  Lij = qj – qi? Then it’s better to write it somewhere in the description for clarity.
* I corrected “…it is impossible to delineate both how much a link weighs and where the center of mass lies along the link simultaneously. There exists a null space in which a change in the mass…”
* Is there any reason that the com of hand and foot are not estimated independently? If exits, could you explain it briefly?

IV. Bayesian Inference Algorithms

* I just read this section. I’m a bad student.
* In the section, 22 parameters needed to be estimated, and it means 11 for mass and 11 for q? Again, q is a scalar not a vector?

V. Experiments and Results

* In equation (10), what is the meaning of “o.w.” ?
* Figure label (fig:com1) is not defined. You commented out the figure. Is it for Fig 2 which has a label(fig:pedestrian)?  
  Figure style is also changed.
* Tables are too big, so I changed the style. How about it? Check the values and expressions in Tables.
* Titles of the Table 1 and 3 have typos and I correct it. All variances are 0.05 in table 1, is it right?
* No information on the height of CoM? I think q is a scalar and ratio rho of links are estimated, so we know the height of CoM too.  
  But there’s no explicit description of it. It’s I think one more different properties from [11].
* In table 3, are the values of the left and right arm/leg symmetric?
* Could we describe estimation accuracy? I think it’s not easy.
* Do you have any video clip for experiments?