Activity Recognition

Assignment #1

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# Phase 1: Data Collection

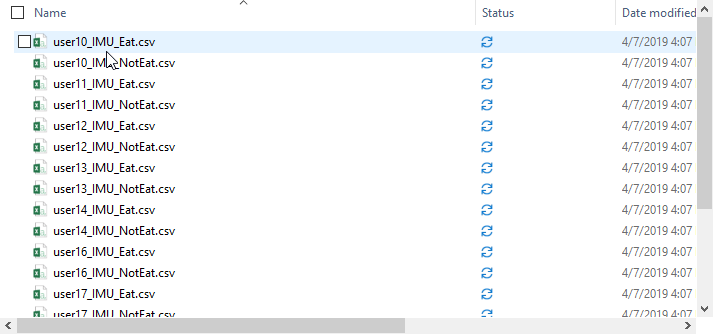
The first part of this project was to organize the raw data. The files that were given per user were one file with IMU sensor data, EMG sensor data and a file with frame numbers for either an action with a fork or spoon for a user. The file with the frame numbers (labeled {userid}.txt) contains 3 columns of data, the first column is a start frame number and the second column is the end frame number; the third column is not used. The significance of these start and end frames are that they are in relation to video taken of a user with the Myo wrist band and when they are engaging in an eating action. We will use this frame numbers in order to synchronize the IMU and EMG data and sort out which data belongs to eating actions and which data belongs to non-eating actions.

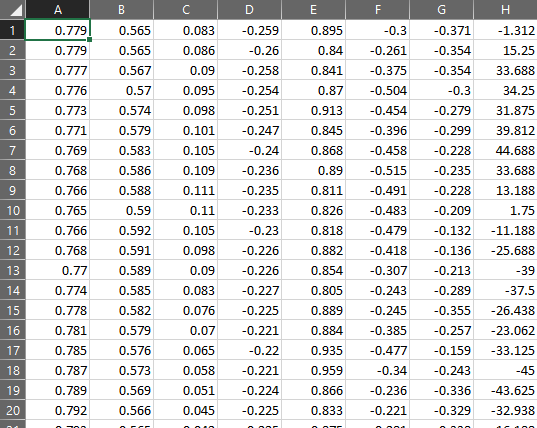
The video data will be the ground truth data used in this project. The assumed frames per second in this video is 30 fps. The sampling rate for the IMU data is 50 Hz or 50 samples per second, the sampling rate for the EMG data is 200 Hz or 200 samples per second. In order to synchronize the IMU data the start frame in the ground truth file was multiplied by (50/30) and similarly the end frame. This new start and end sampling value is used in order to retrieve the start and end row from the IMU file that correlates to the eating action frames. The same method is used for the EMG data except for the calculation is (200/30) since the sampling rate is not the same as the IMU sampling rate. Similarly, the new start and end sampling value is used to retrieve the data from the EMG file that correlates to the eating action.

The non-eating data was found using a similar method except that we use values in between a start frame and the previous end frame in order to indicate non-eating actions. For example, we iterate through the ground truth file start at *i*=2, then we apply the calculation (either for EMG or IMU) to the start frame at row *i* and the end frame at row *i-1* (the previous row). This range gives us the rows that correlate in either the IMU or EMG files for a non-eating action.

The IMU data that is provided includes sensor data for orientation, accelerometer and gyroscope. This results in ten different sensor data points (OriX, OriY, OriZ, OriW, AccX, AccY, AccZ, GyroX, GyroY, GyroZ). The EMG data was not used in this project due to poor synchronization, there were many issues synchronizing the ground truth file with the EMG data.

The IMU sensor data was stored into a matrix where all the eating actions were appended and each column signifies a particular sensor (ten columns) and this data is stored per user into a CSV file.

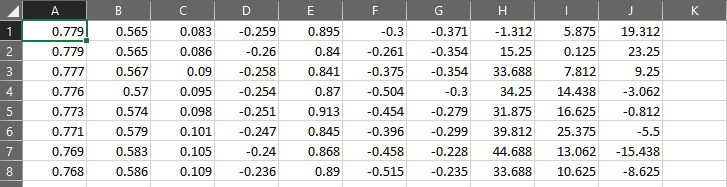




This was done for ten users for a total output of 20 csv files. The data for the non-eating actions is significantly longer than those for eating actions which provides a variation in time between eating and non-eating actions across all sensor data points.

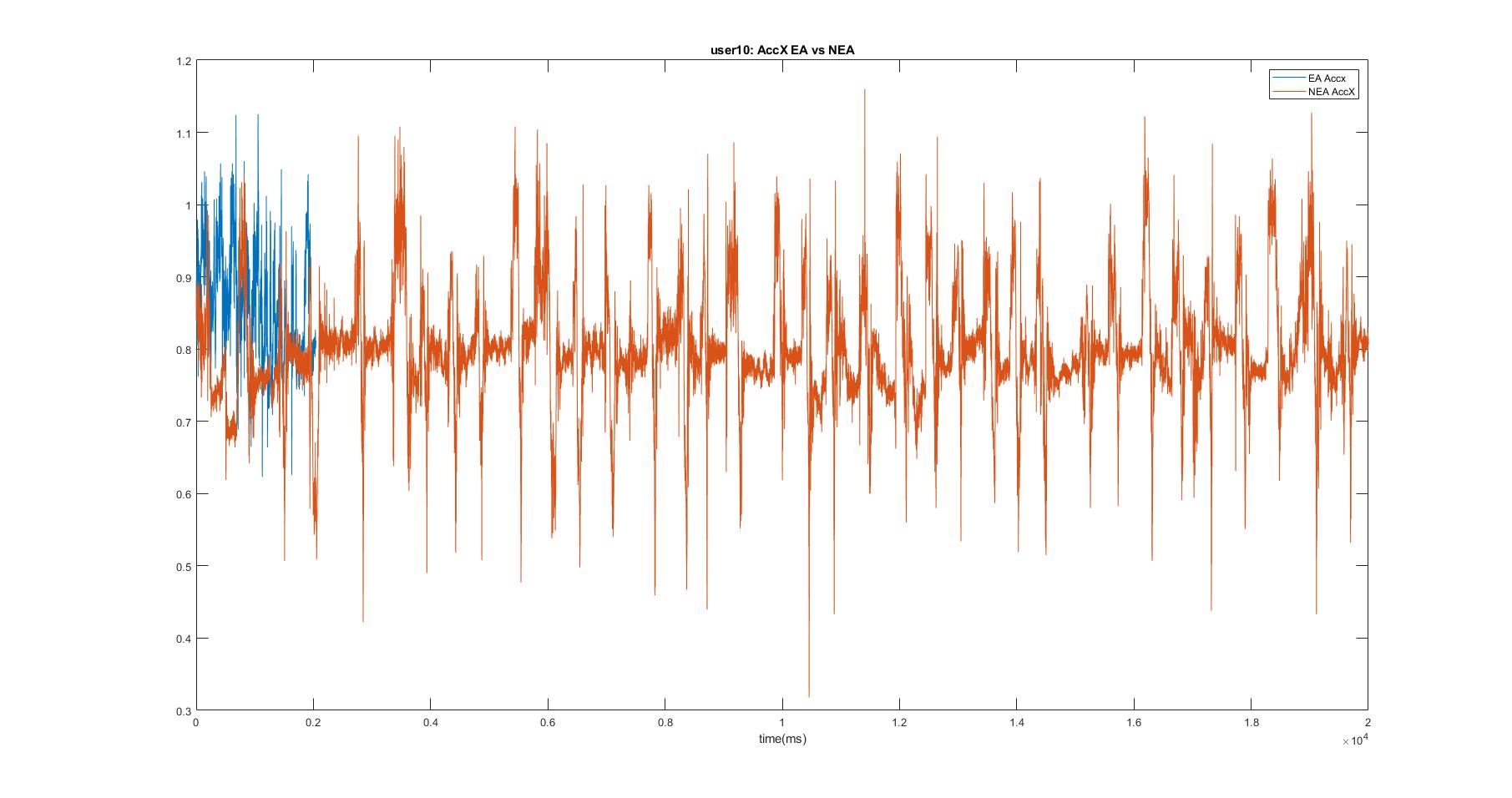
# Phase 2: Feature Extraction

The data is organized into .csv files where all eating actions are concatenated together but each sensor data point resides in it’s own column. For example:

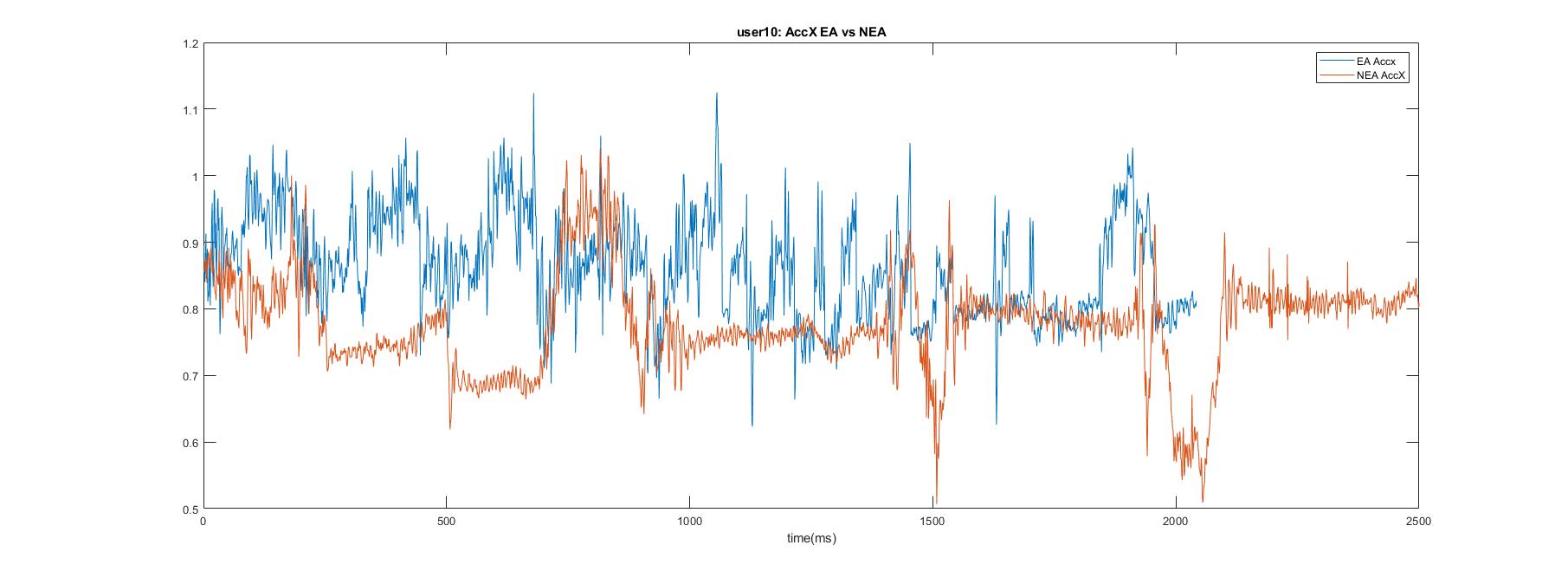


In this diagram, the columns are related to the IMU data:

* Column A: Orientation X
* Column B: Orientation Y
* Column C: Orientation Z
* Column D: Orientation W
* Column E: Acceleration X
* Column F: Acceleration Y
* Column G: Acceleration Z
* Column H: Gyroscope X
* Column I: Gyroscope Y
* Column J: Gyroscope Z

I checked various sensor data points for individual users, for example an Acceleration X for user ten comparison between Eating and Non-Eating actions.

The first thing we notice is that the length of time for the non-eating actions is significantly greater than those for eating actions. The same graph with a shortened x-axis also shows that the Acceleration X data points have a lot of variance in comparison to the non-eating data.



Variances were checked among other dimensions (sensors) to look for variation and where the following feature extraction methods could be applied to the entire sample set (ten users).

1. Mean
2. Standard Deviation
3. FFT (Fast Fourier Transformation)
4. Minimum
5. Maximum

## Mean

The mean is used in data mining with continuous data and is essentially an average of a given data set. All the values are added together and then divided by the total number of data points in the set. Mean was chosen because graphs such as the graph for Acceleration X for user10 displayed different values for Eating and Non-Eating actions. Using the mean the graphs will display the average across all the users (ten users) for Eating and Non-Eating actions.

In MATLAB the mean was taken for every sensor value for every user, these values where then normalized and saved so that they could be graphed. The normalization of a mean value indicates how many standard deviations that value is the from the mean, this is also known as the z-score.

Graphs were created for ten users displaying the mean per sensor and the results varied.

* Acceleration X showed similar data, showing a lack of variance of acceleration along the horizontal axis:
* Acceleration Y however showed a large variance not only among the users but also the vertical axis movements. Acceleration also Z showed a large variance across the Z-axis.
* The Gyroscope dimensions all showed a lot of variance from Eating and Non-Eating actions.
* The Orientation dimensions varied, where Orientation W did not show much variance and Y a little more, but X and Z were consistently different.

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## Standard Deviation

Explanation

Intiuition

Matlab code

Graphs

Discuss

## Fast Fourier Transformation

Explanation

Intiuition

FFT is used to change the raw data from a time domain to a frequency domain so that we can see how fast the data is changing.

Matlab code

Graphs

Discuss

## Minimum

Explanation

Intiuition

Matlab code

Graphs

Discuss

## Maximum

Explanation

Intiuition

Matlab code

Graphs

Discuss

# Phase 3: Feature Selection

## Arranging the Feature Matrix

## Execution of PCA

## PCA eigenvectors

## PCA results

## PCA comments