

OCCUPANT-AWARE, COGNITIVE ILLUMINATED ENVIRONMENTS



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Where I'm from



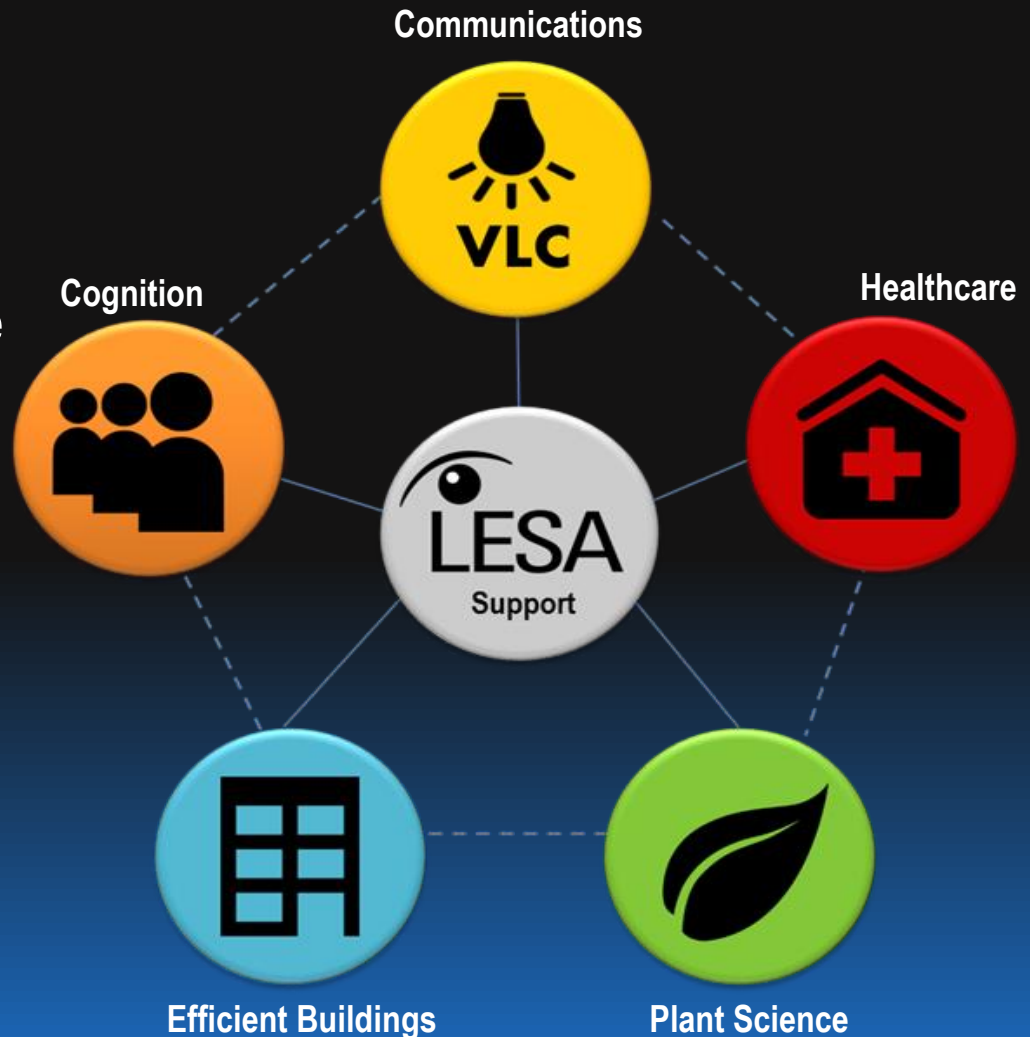
Rensselaer



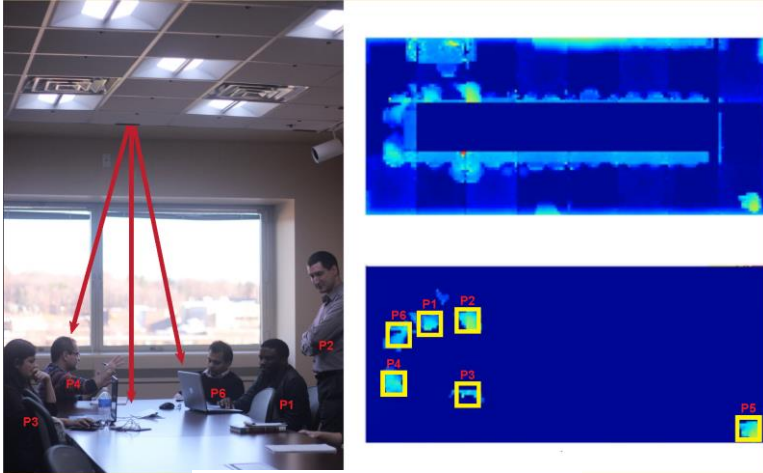
+ NYSERDA,
24 industrial
partners

LESA – Making Lighting More Useful

- Thought Leadership in advanced lighting system applications
- Deep understanding in a wide range of core and applied lighting technologies
- Eager to work collaboratively with industry to open new markets
- Leverage Federal and State funding to accelerate progress



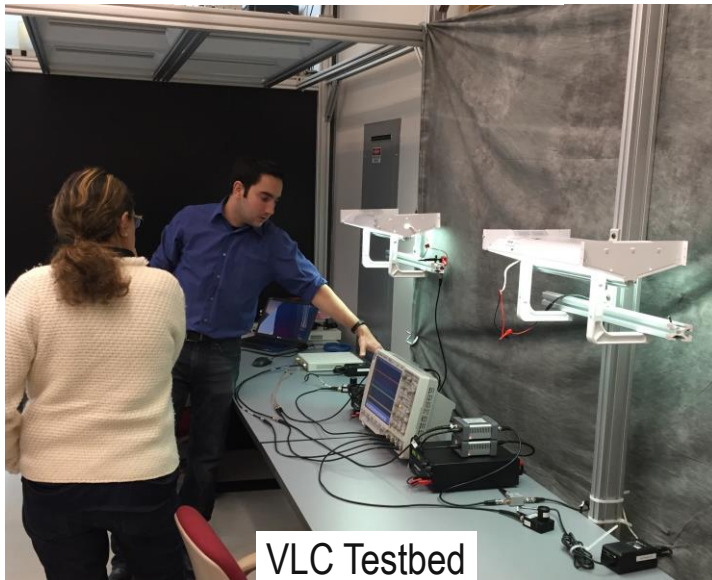
LESA systems-level testbeds



Smart Conference Room



Hospital Room Testbed



VLC Testbed



Plant Research Laboratory

The Smart Conference Room

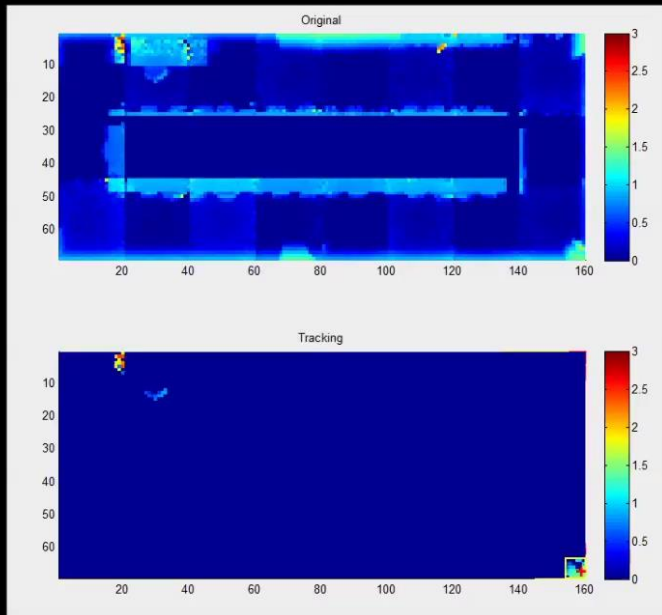


The Smart Conference Room



Afshari, Woodstock, Imam, Mishra, Sanderson, Radke, *Buidsys 2015*

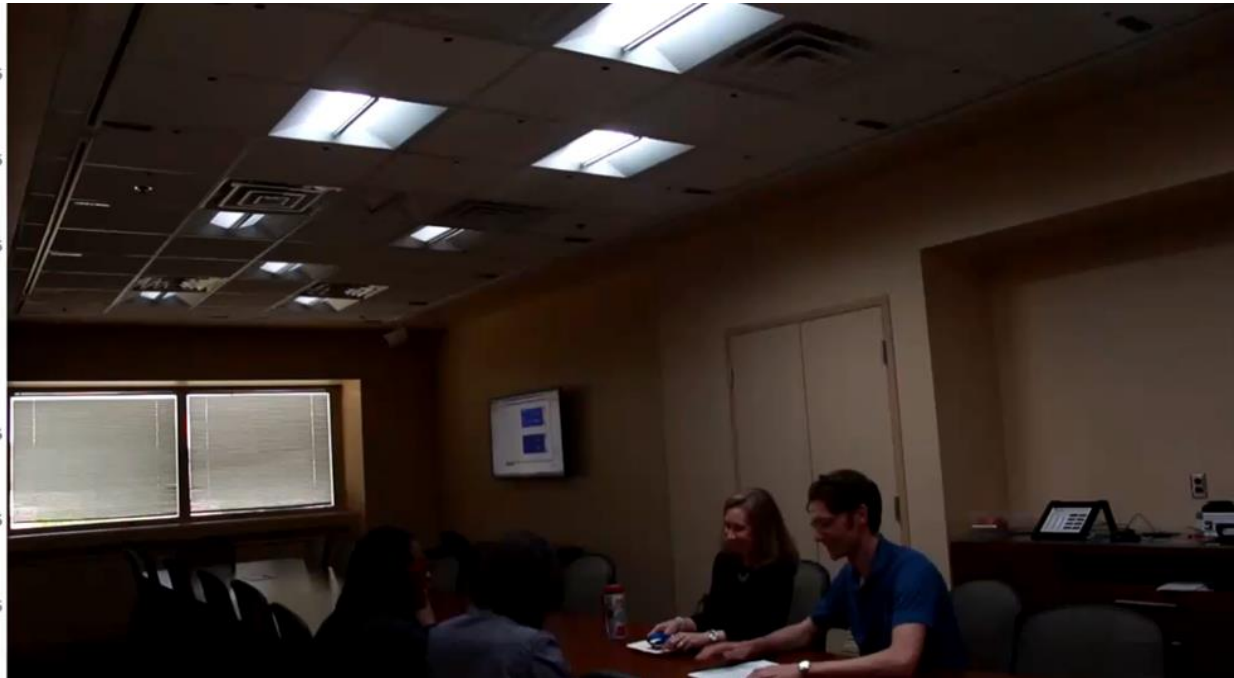
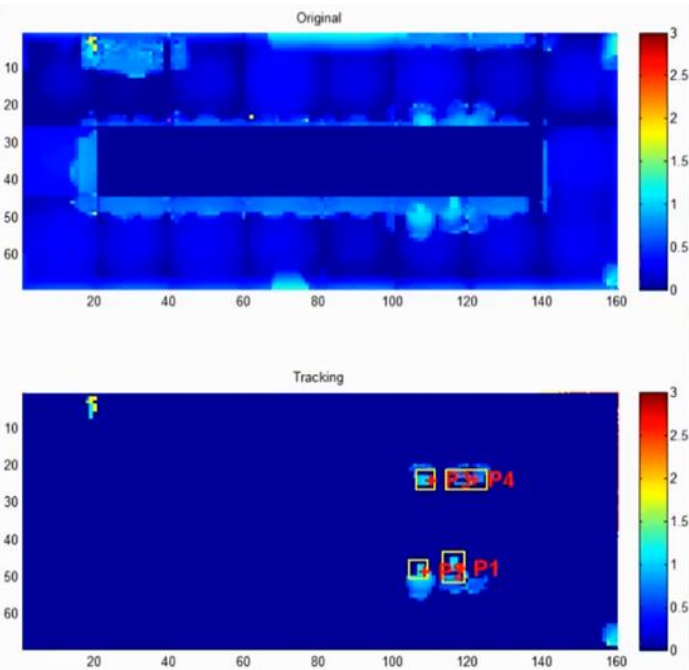
Occupancy tracking using time-of-flight sensors



Number of people: 1

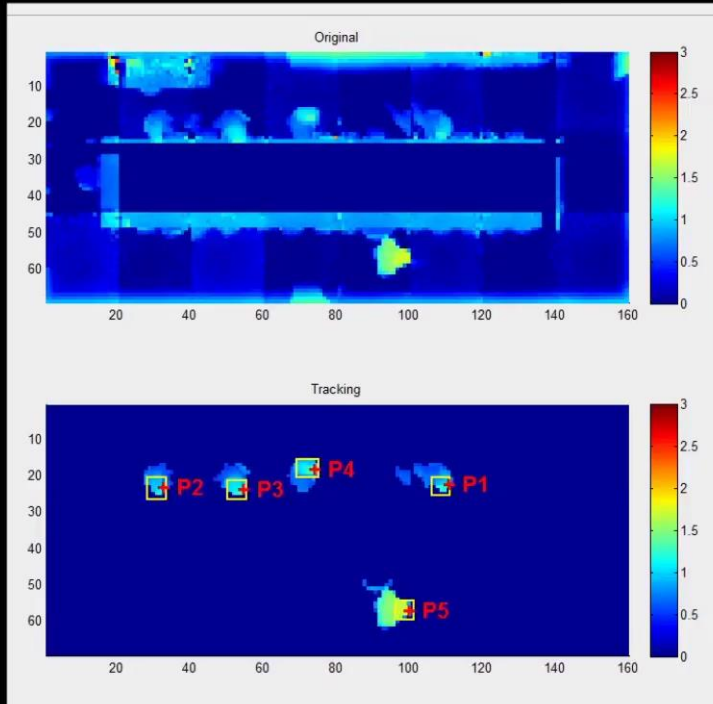
	ID	Position	Height
1	1	[158, 67]	1.52

Occupant-aware lighting using ToF tracking



Woodstock, Radke, Sanderson, *FUSION 2016*

Presentation mode



Vision: Meeting Facilitation and Summarization

ACTION ITEMS FROM LAST MEETING:



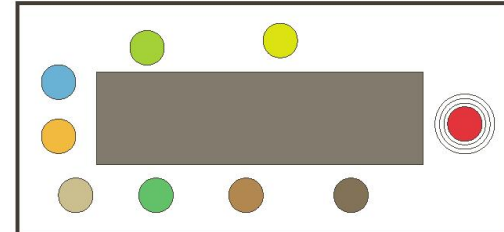
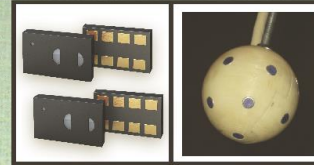
- Periodic testing requirements for sub-contractors.
- Report on 18-hour air handler test



- SVN upgrade and instructions

ACTION ITEMS FOR NEXT MEETING:

- Air inlet configuration analysis
- Plan breakout sessions for retreat
- Contact division heads for news items

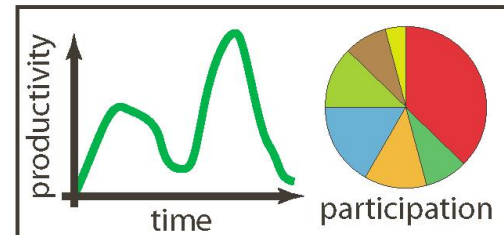


spatio-acoustic person tracking

"**Indrani**, do you have the results of **that test** yet?"

"No, I'll have it ready for **next time**."

natural language understanding



meeting analysis and facilitation

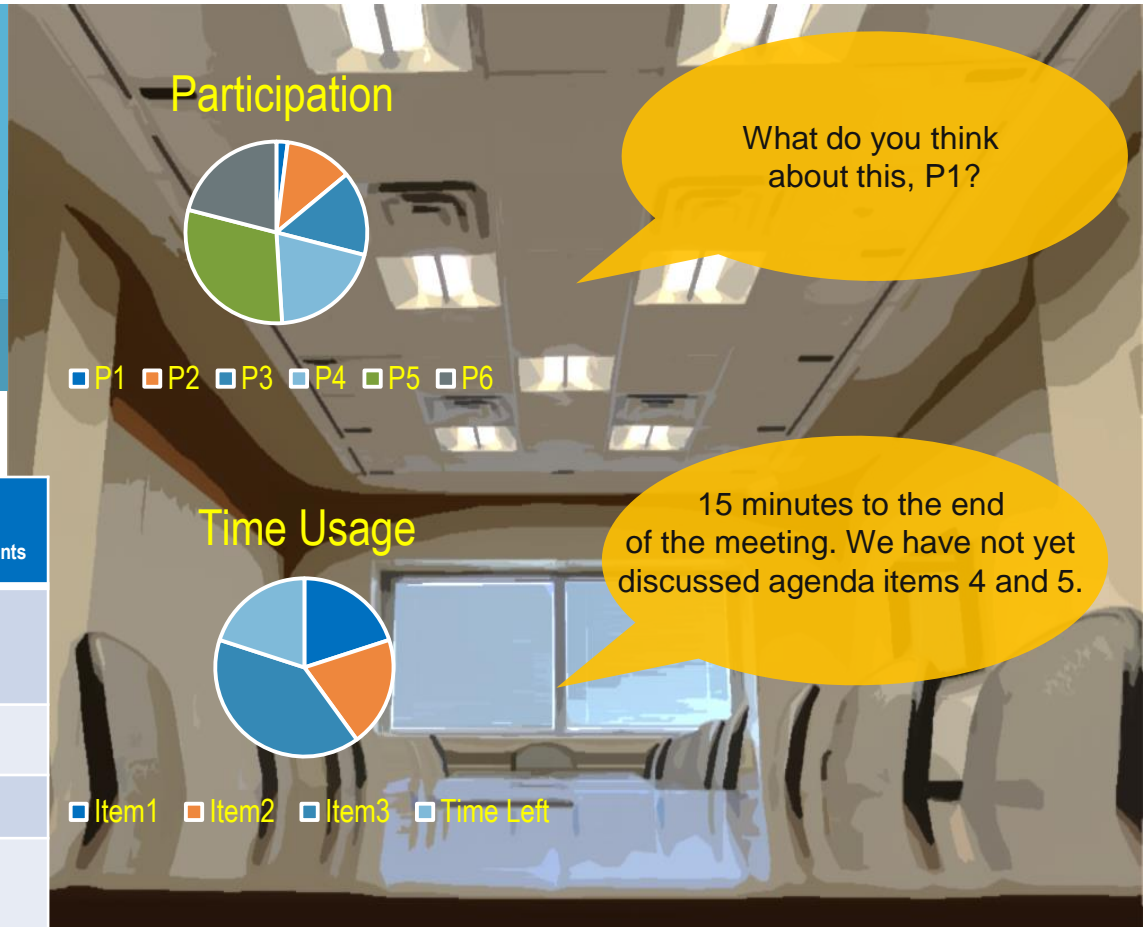
Active meeting facilitation

Smart room as active meeting participant



Active decision support

Type of Sensor	Detects	Spatially pinpoints people	Distinguishes many people	Economically feasible	Suited for sensitive environments
Passive Infrared	Changes in body temp.	No	No	Yes	Yes
Video Cameras	Image	Yes	Yes	Yes	No
Ultrasound	Motion	No	No	Yes	No
High resolution ToF	Depth map	Yes	Yes	No	No
Low resolution ToF	Sparse depth map	Yes	Yes	Yes	Yes



Framework

Integrated Smart Service System

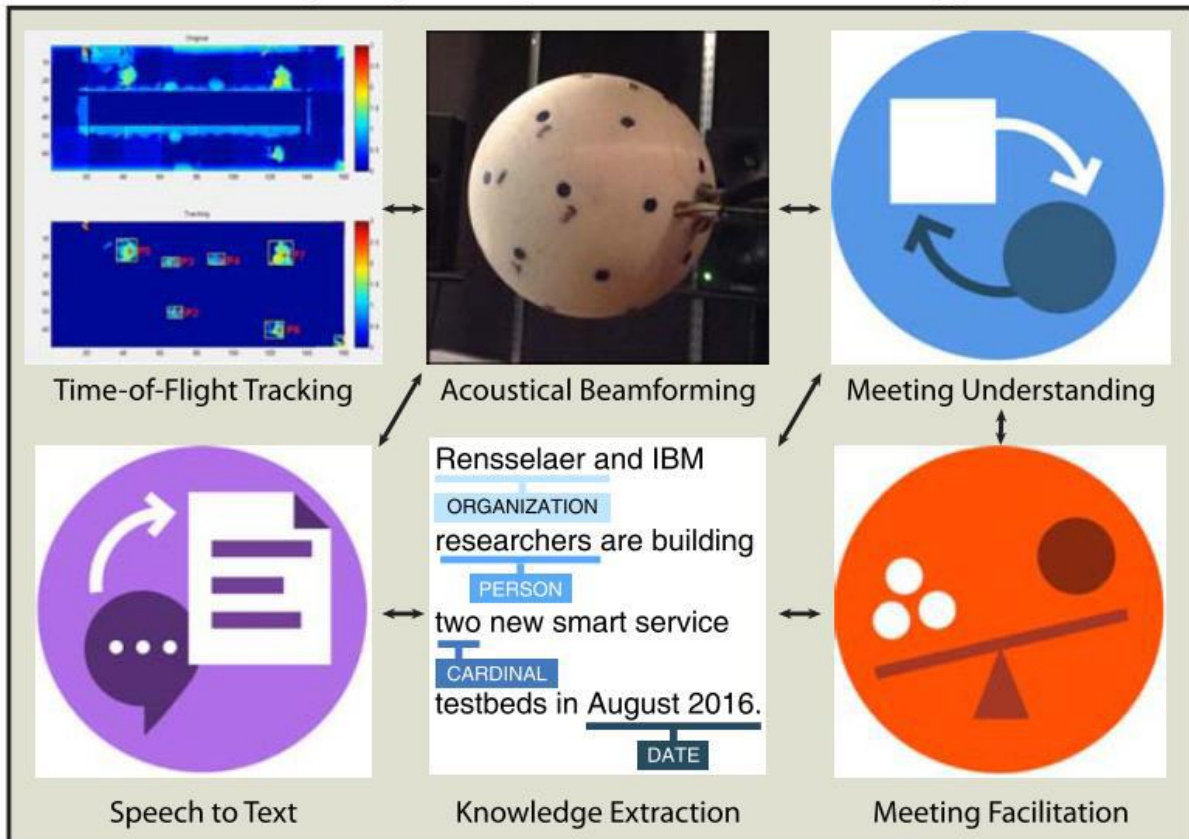


Smart Conference Room Testbed



CRAIVE-Lab Testbed

Computing, Sensing, and Information Technology



Collaborations with audio processing, natural language understanding, and social science experts from RPI and Northeastern; supported by NSF

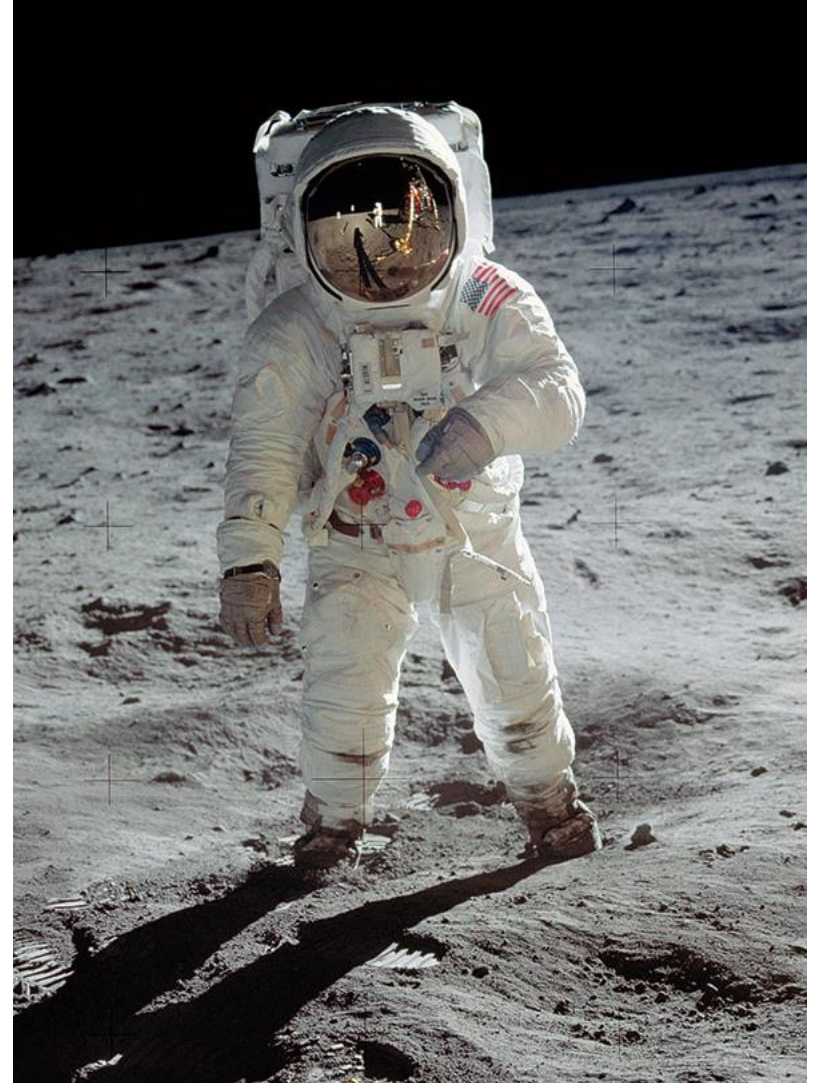
The Lunar Survival Task

Items	Step 1 (Individual Ranking)	Step 2 (Group Ranking)
Box of matches		
Food concentrate		
50 feet of nylon rope		
Parachute silk		
Portable heating unit		
Two .45 caliber pistols		
One case of dehydrated milk		
Two 100-pound tanks of oxygen		
Stellar map (of the moon's constellation)		
Life raft		
Magnetic compass		
5 gallons of water		
Signal flares		
First aid kit containing injection needles		
Solar-powered FM receiver transmitter		



The post-task questionnaire

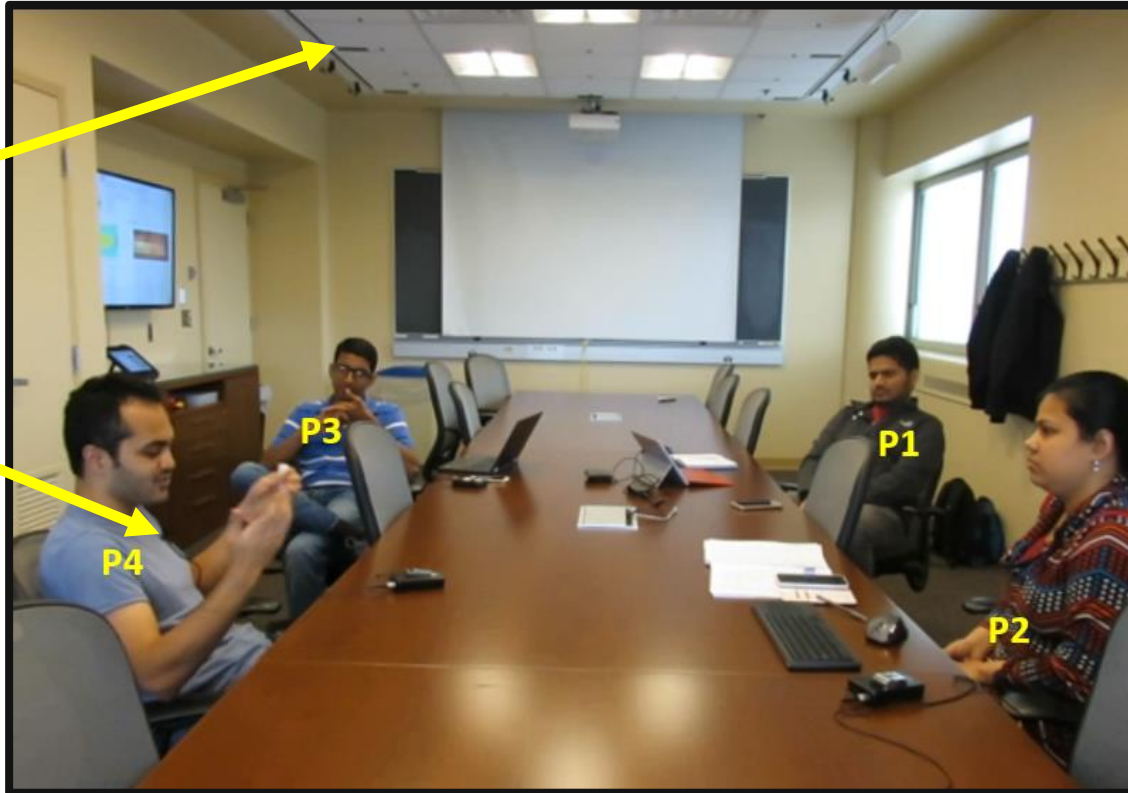
- How well did you know each of your group members before today?
- To what extent did the following group members contribute to the discussion?
- To what extent did the following group members act as a group leader?
- Was the discussion engaging/boring, comfortable/awkward, etc.?
- Age/gender



Experimental setup

Time-of-Flight sensors

Lapel microphones



Dataset : 22 lunar survival tasks, with group size varying from 3 to 5
Collected in SCR in October 2017

Multi-modal analysis of group meetings

Spatial understanding:

- Location
- Pose
- Body orientation
- Head pose
- Body posture
- Gestures

Non-verbal audio analysis:

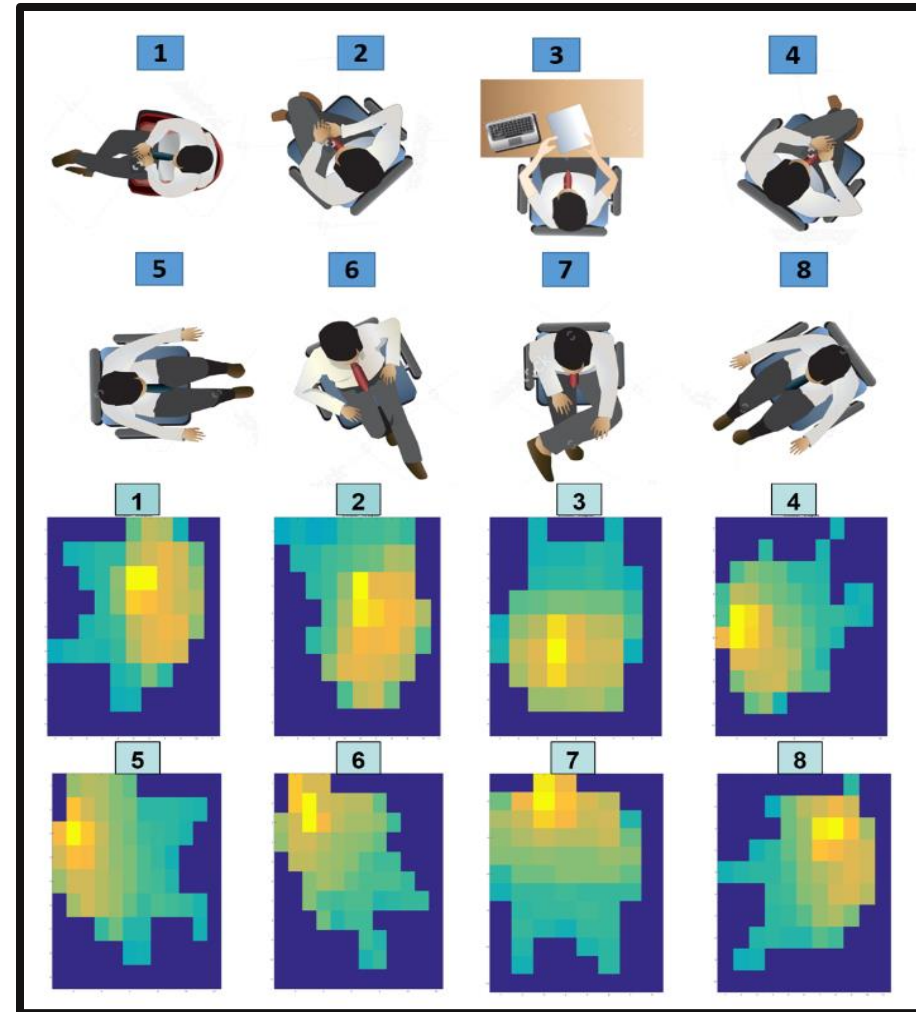
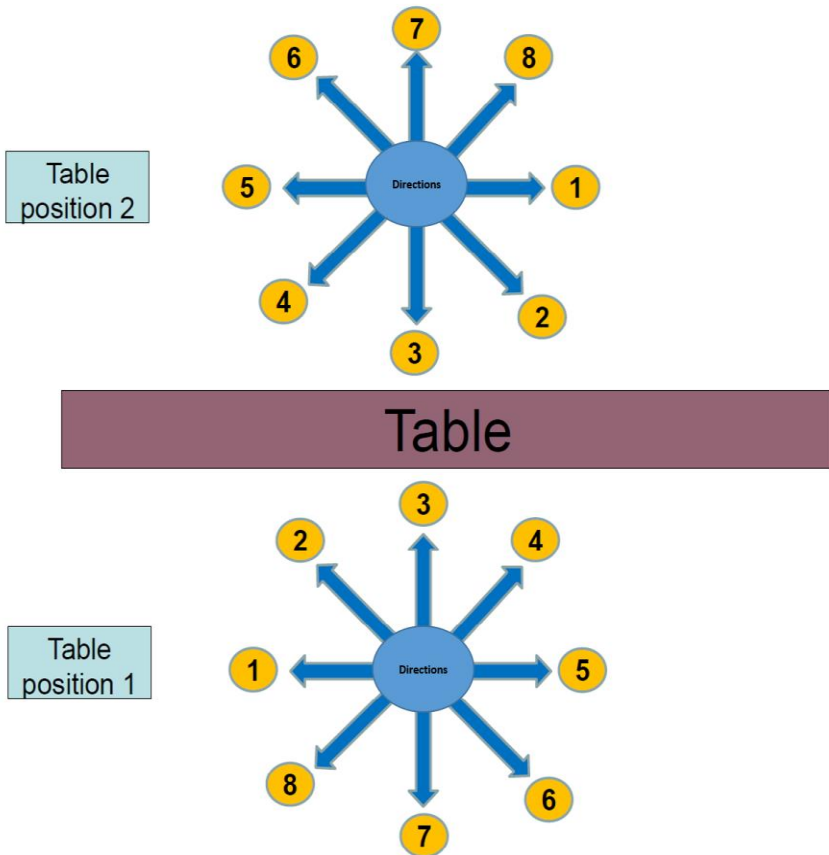
- Speaker segmentation
- Interruptions
- Speaking overlap
- Tone, prosody, laughter

Speech analysis:

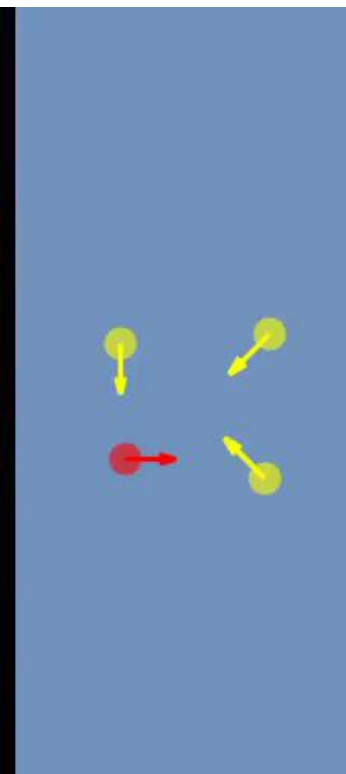
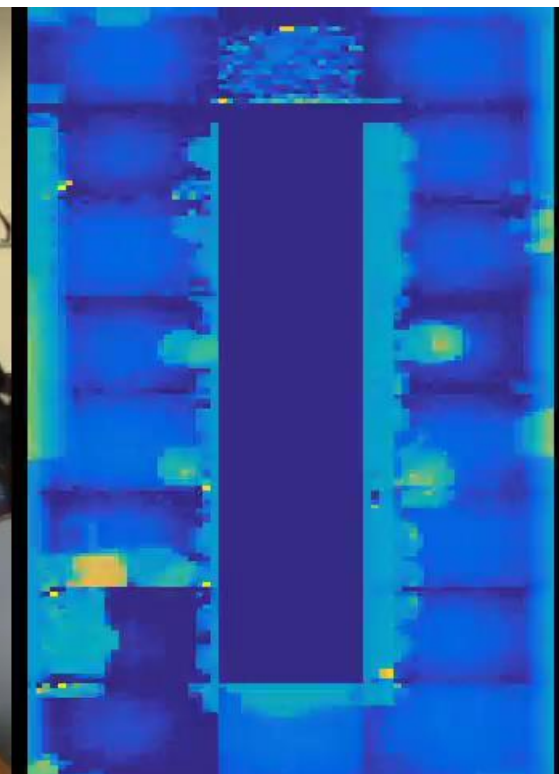
- Generate automated summaries
- What items are being talked about and how much?
- What are the different phases in the meeting?



Body orientation from sparse ToF data



Body orientation from sparse ToF data



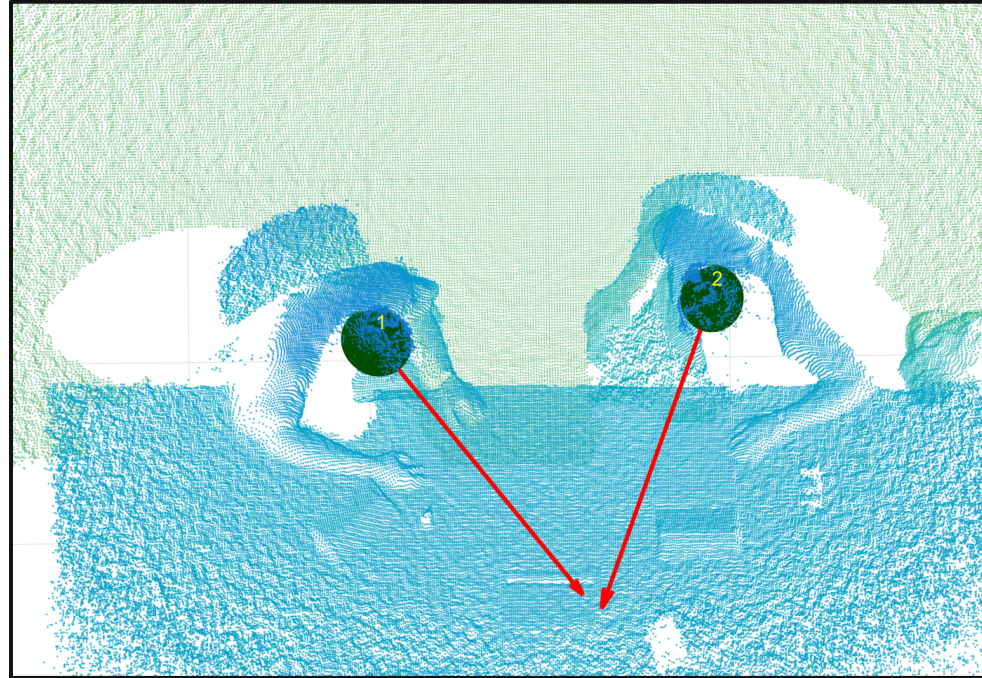
Head pose estimation from denser ToF data (Kinect)



Head pose estimation initial results

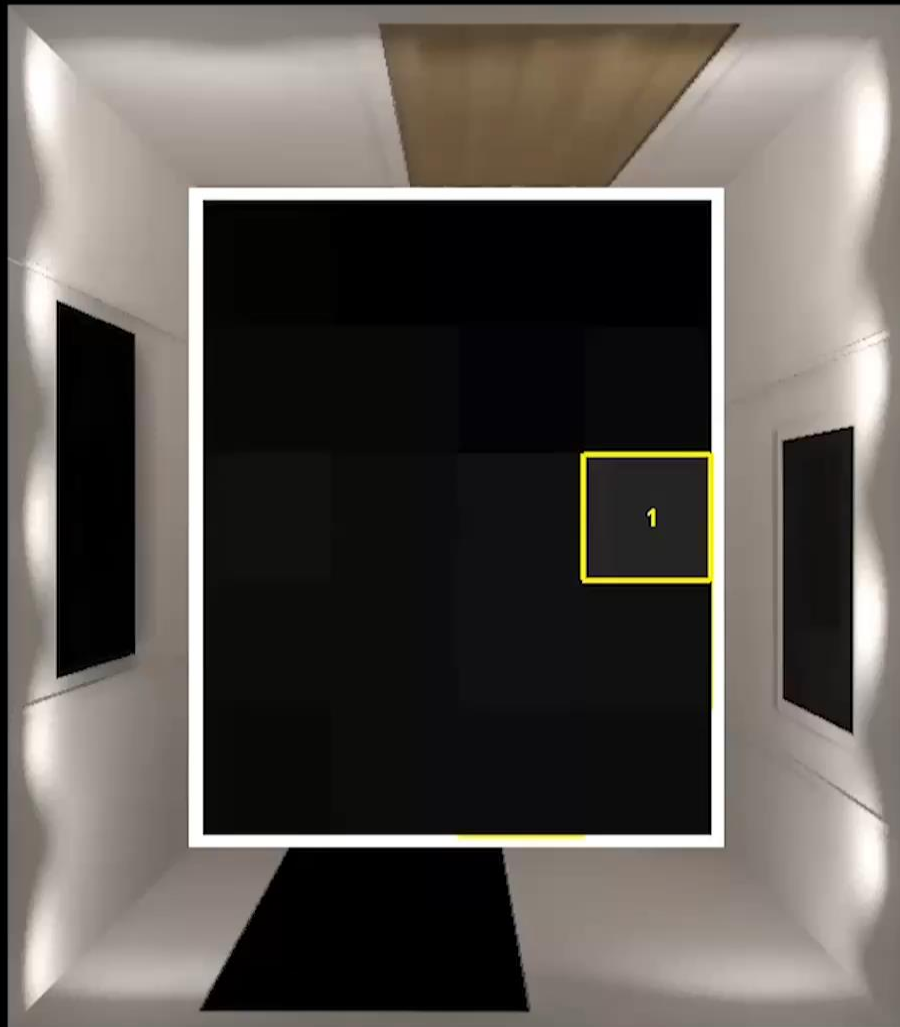


IR image from overhead Kinect

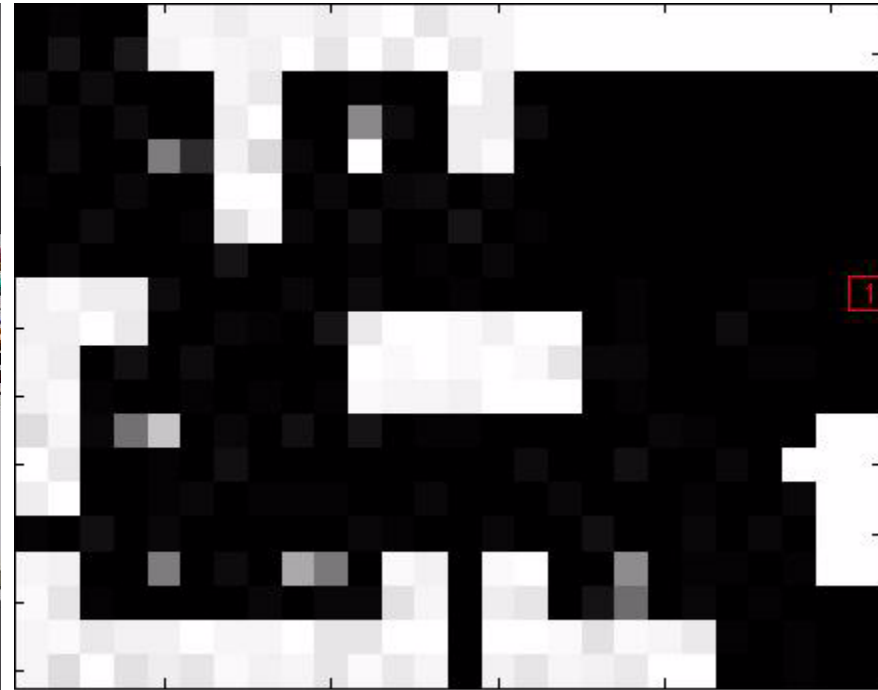
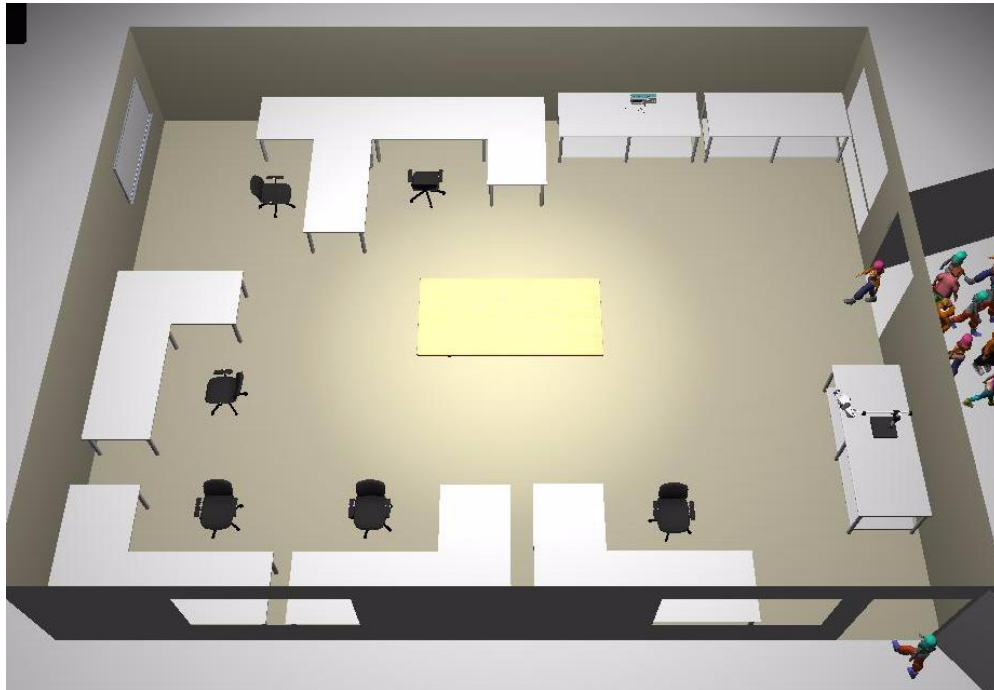


Top-down view of reconstructed 3D point cloud with fitted ellipsoid and head pose

Single-pixel ToF tracking prototype



Single-pixel ToF tracking simulation



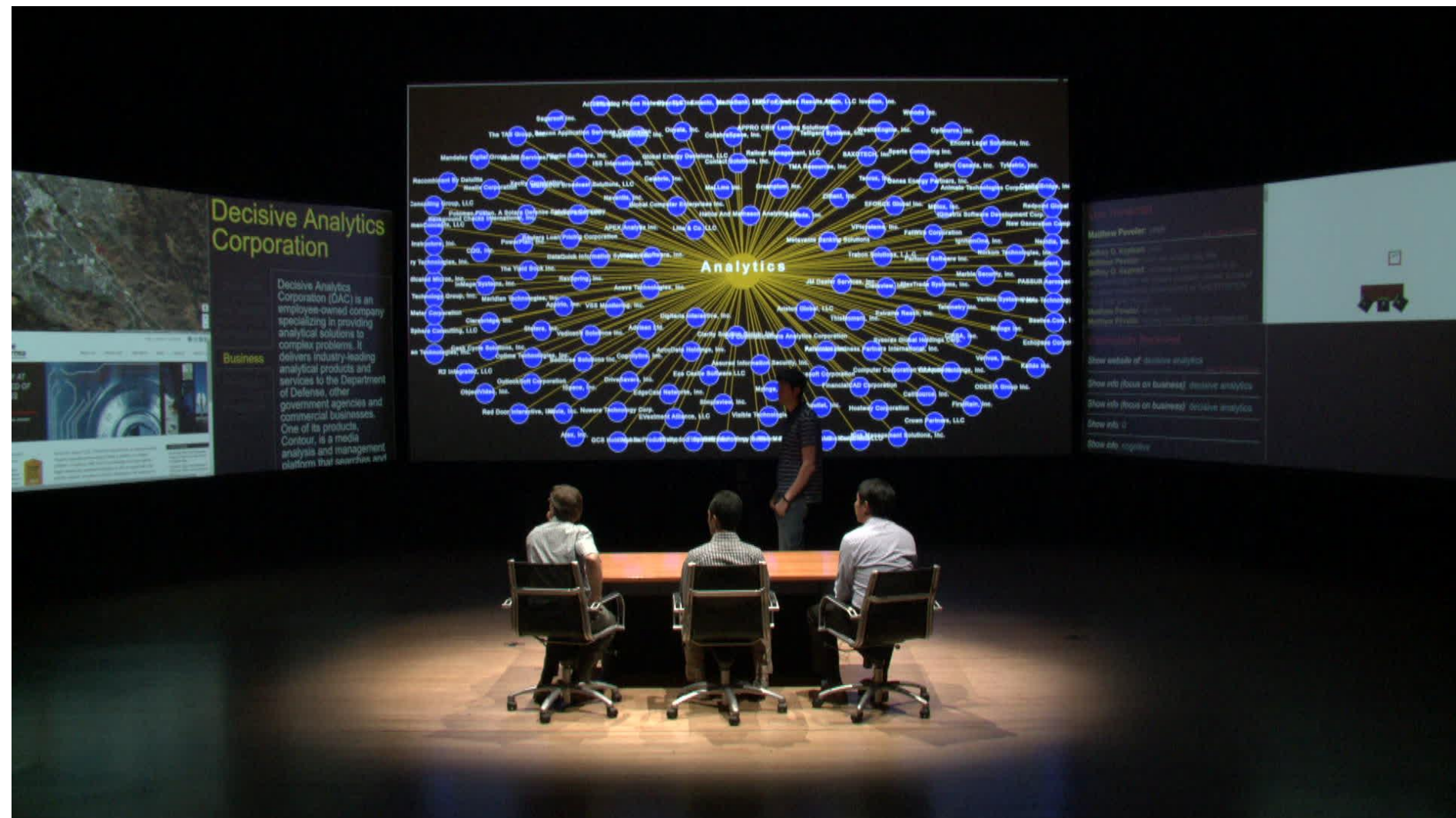
- Same 2' x 2' spacing as actual deployment in testbed
- Further investigation under ARPA-E project

The CRAIVE Lab



(Collaborative-Research Augmented Immersive Virtual Environment)

Large-scale cognitive immersive environments



Person and pose tracking



Thanks to...

- Indrani Bhattacharya (Rensselaer)
- Li Jia
- Bob Karlicek
- Sandipan Mishra
- Michelle Simkulet
- Art Sanderson
- Hui Su
- Arunas Tuzikas
- TKae Woodstock

- Brooke Foucault Welles (Northeastern University)
- Christoph Riedl
- Michael Foley



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