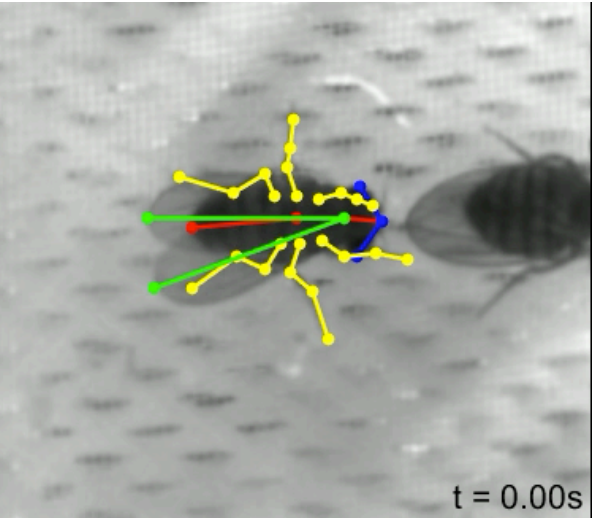


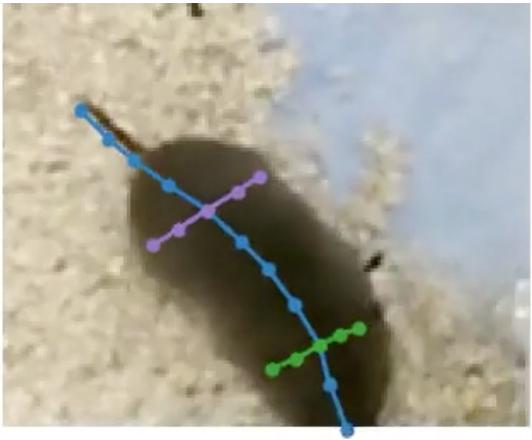
Machado et al, 2015

Mathis et al (2018)

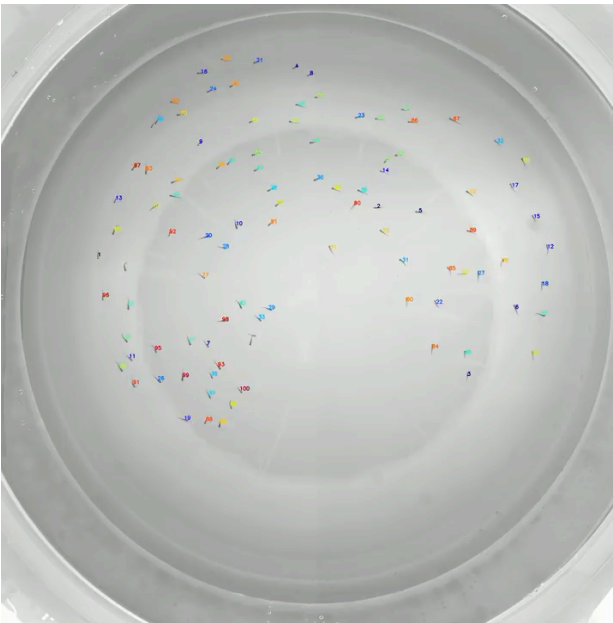


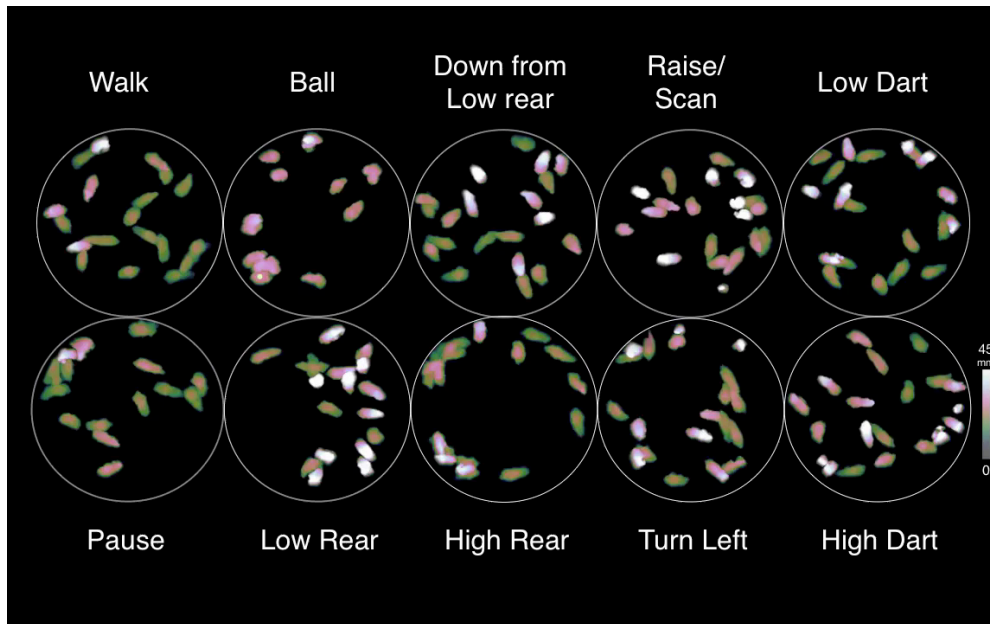
Pereira et al (2018)

Kanishk Jain

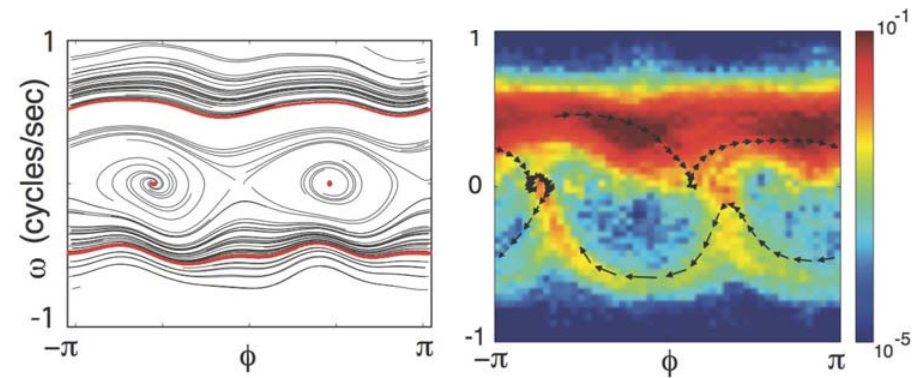


Romero-Ferrero et al, 2019



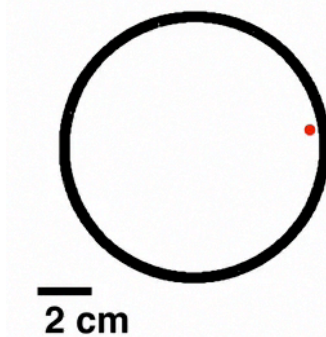


Wiltschko et al, 2015



Stephens et al, 2008

Lab Coordinates



Real Time



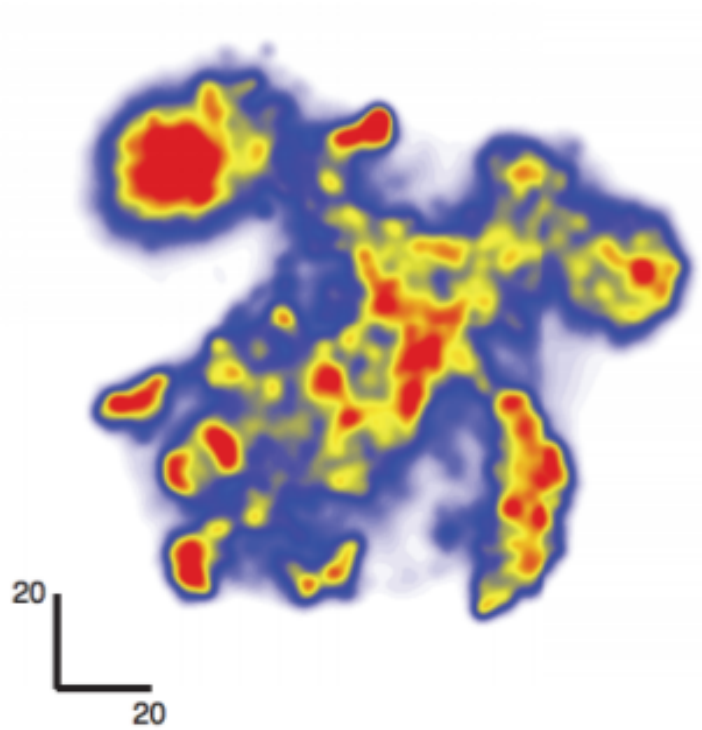
Behavioral Space



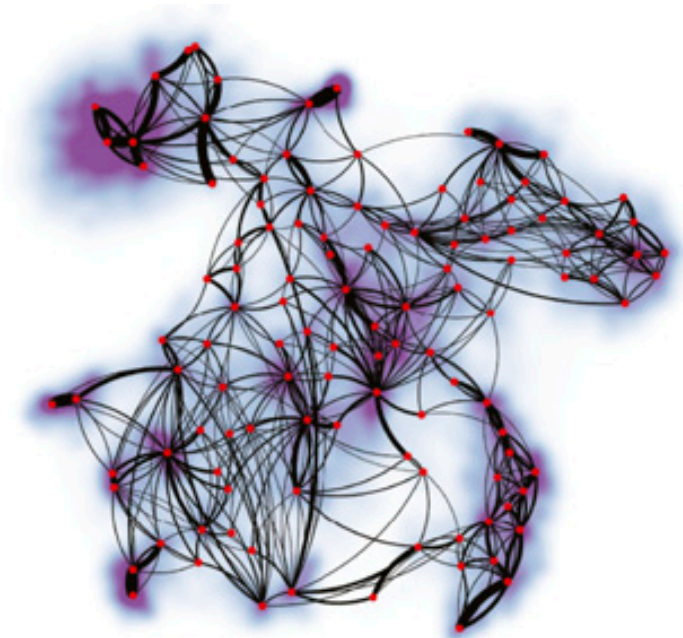
GJB et al, 2014

Fast Leg Movement #4

Individual Flies:



Individual Flies:

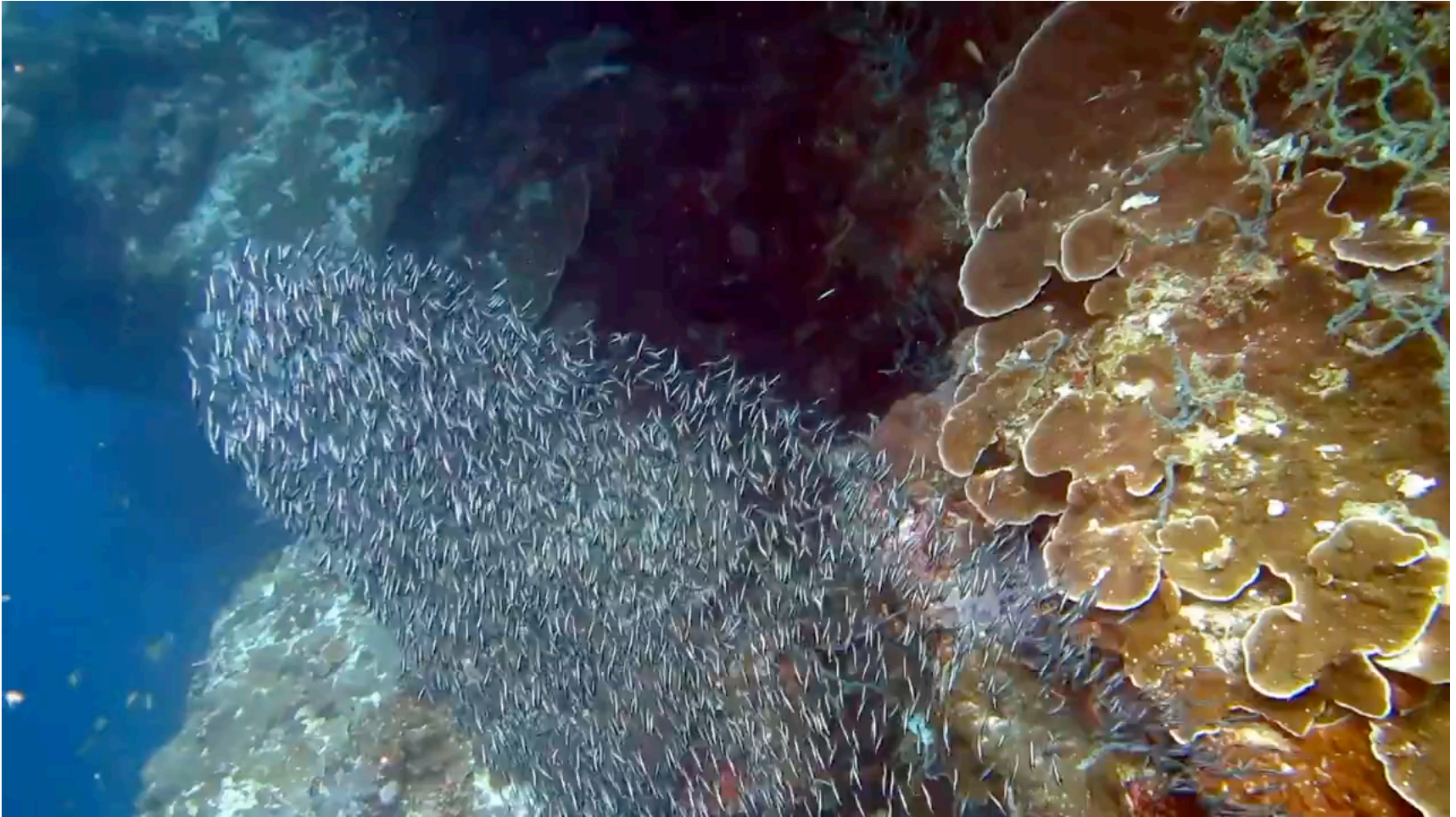


— = .5



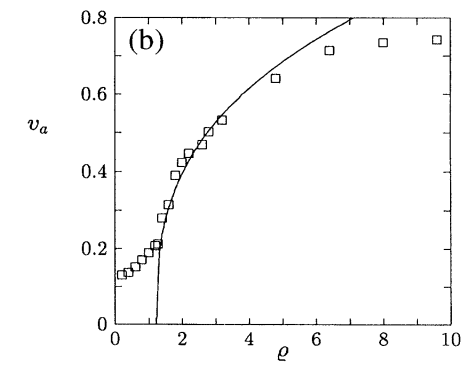
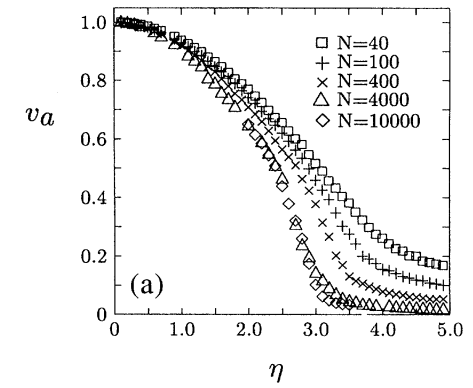
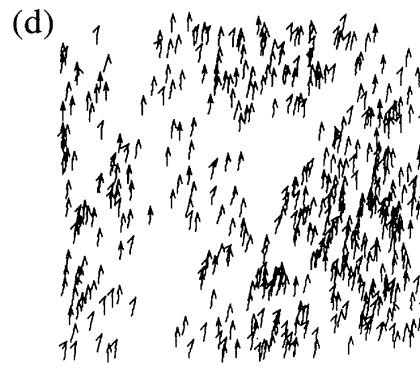
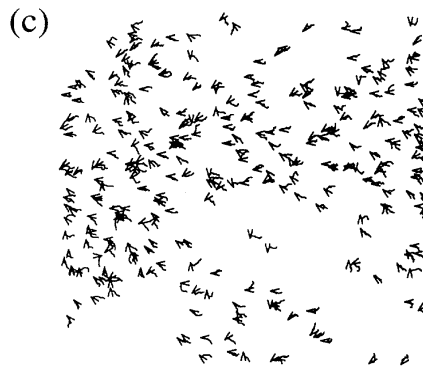
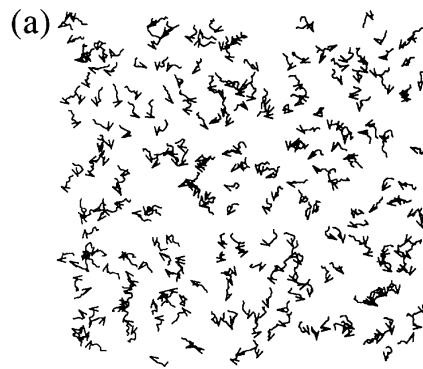


A prelude

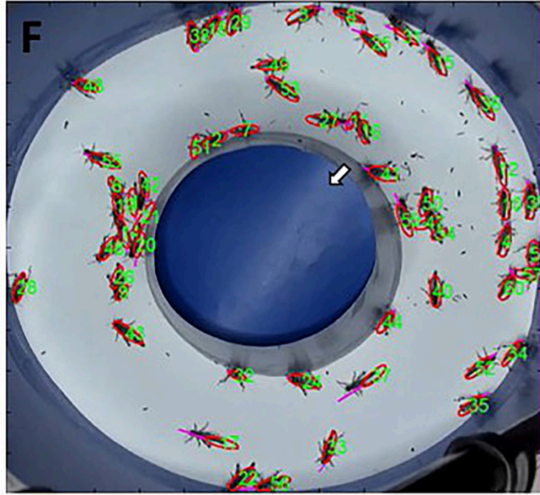


$$\mathbf{x}_i(t + 1) = \mathbf{x}_i(t) + \mathbf{v}_i(t)\Delta t$$

$$\theta(t + 1) = \langle \theta(t) \rangle_r + \Delta \theta$$

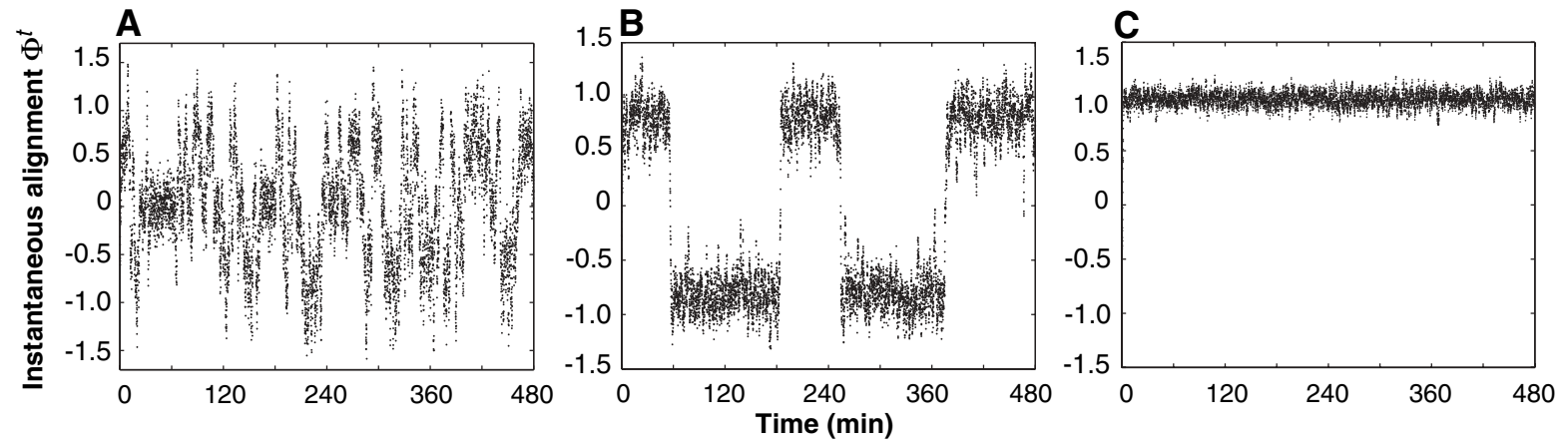


Vicsek et al, 1995

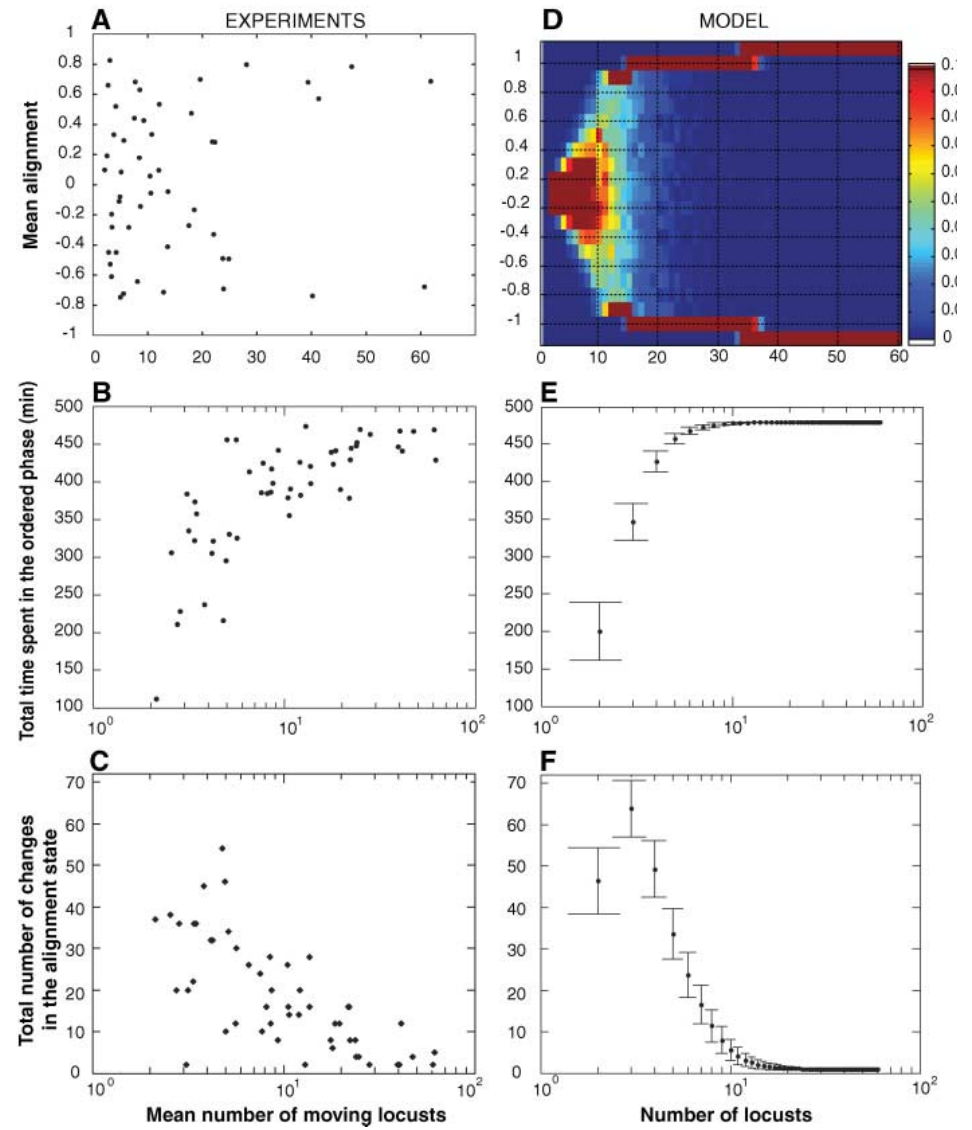
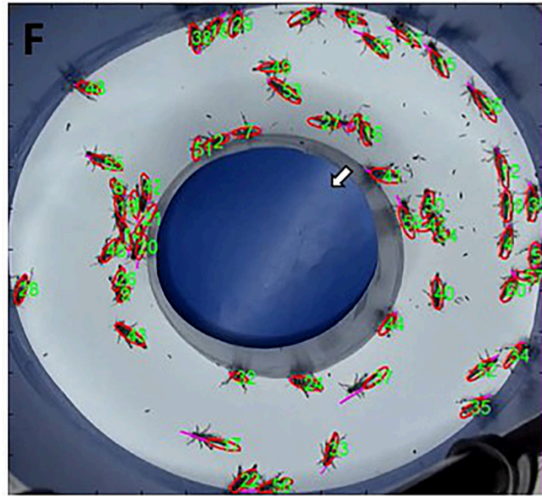


$$\chi = \arcsin[\sin(\theta - \alpha)]$$

$$\Phi^t = \frac{2}{m\pi} \sum_{i=1}^m \chi_i^t$$



Buhl et al, 2006

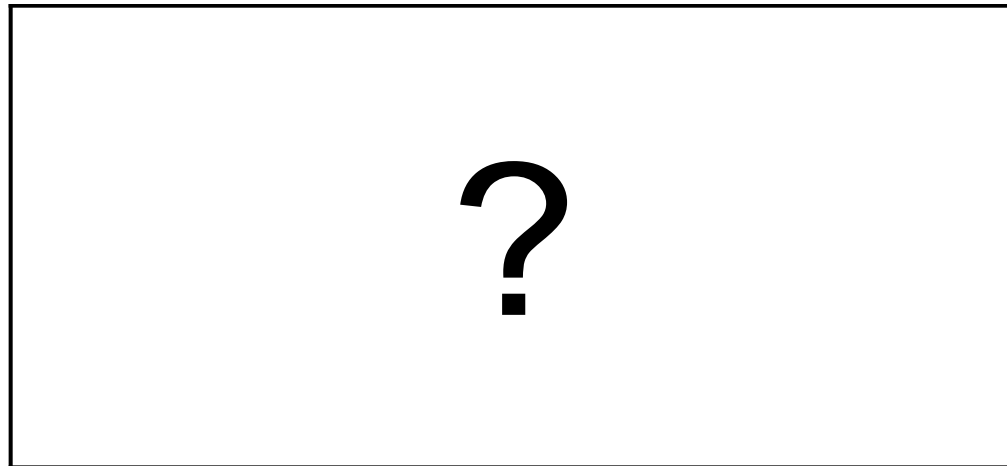
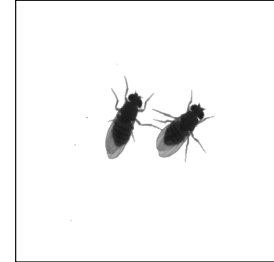
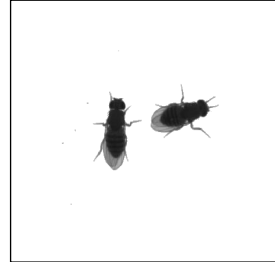




Iain Couzin

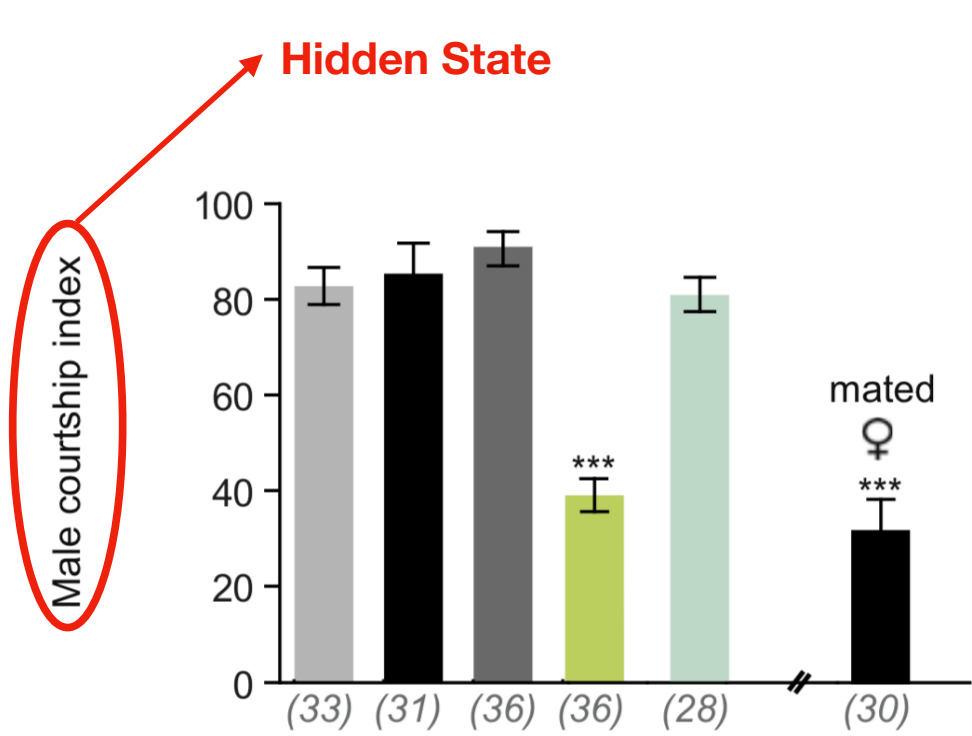


Order Parameter?

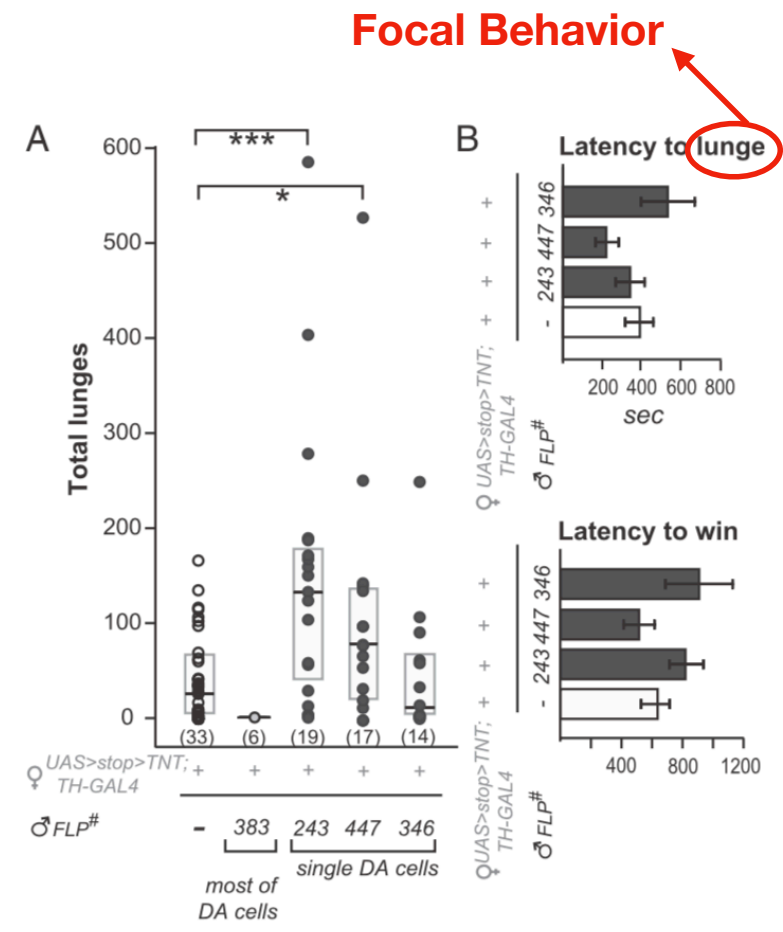


Control Parameter?

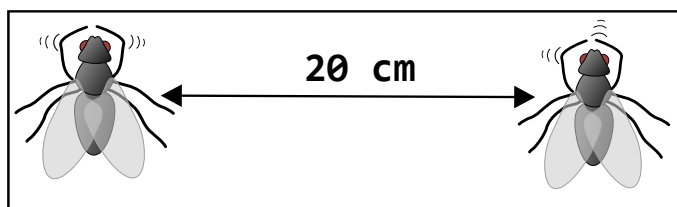
Classical Method: Indices or Representative Behaviors

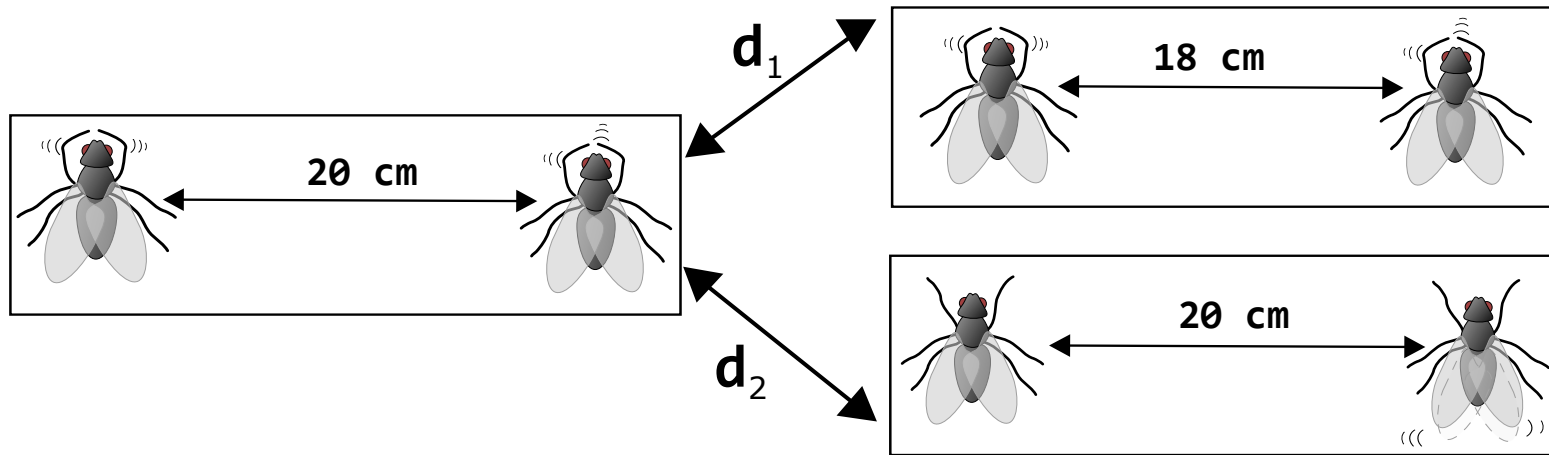


Rez  vel et al, 2012

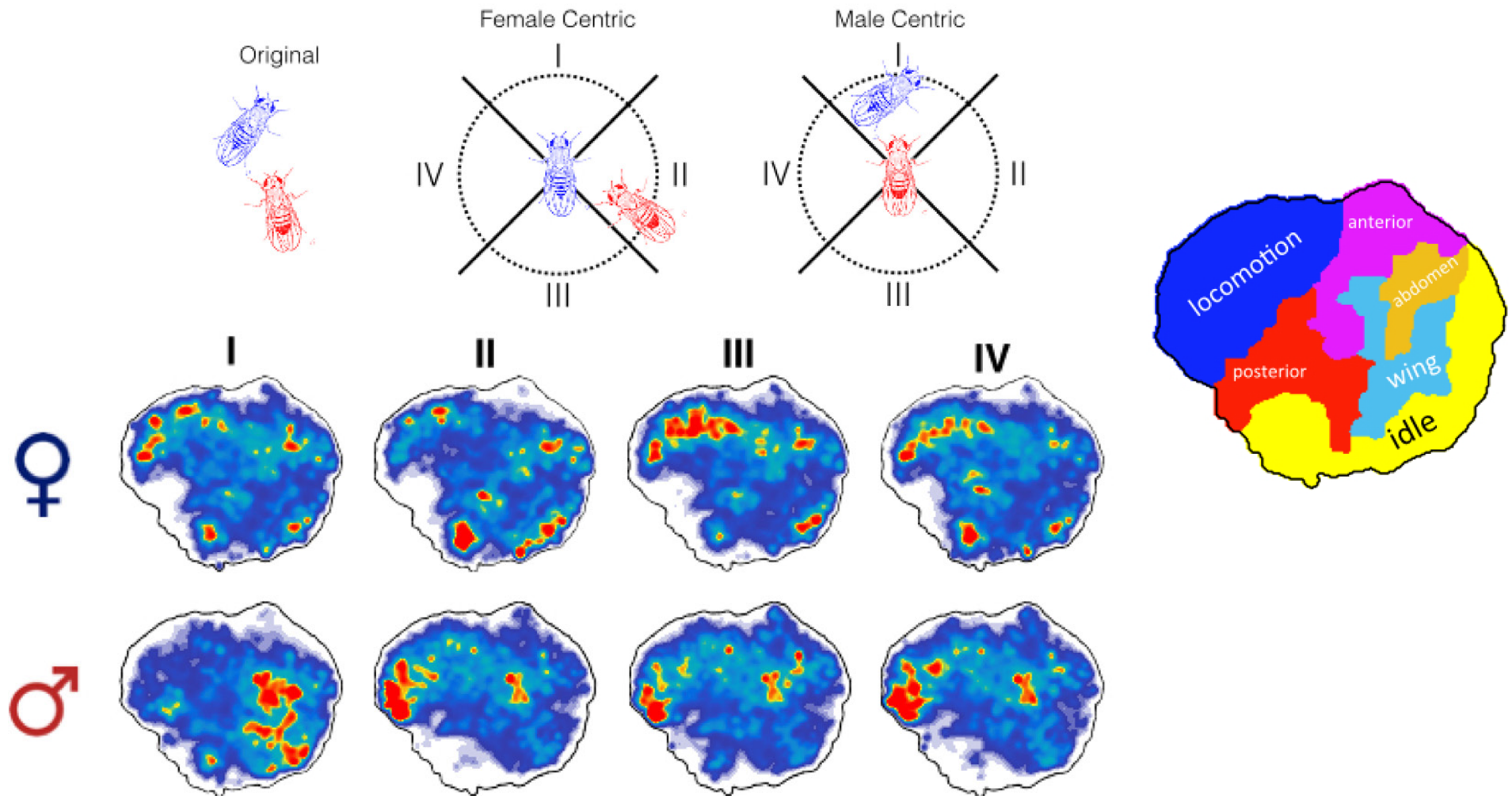


Alekseyenko et al, 2013



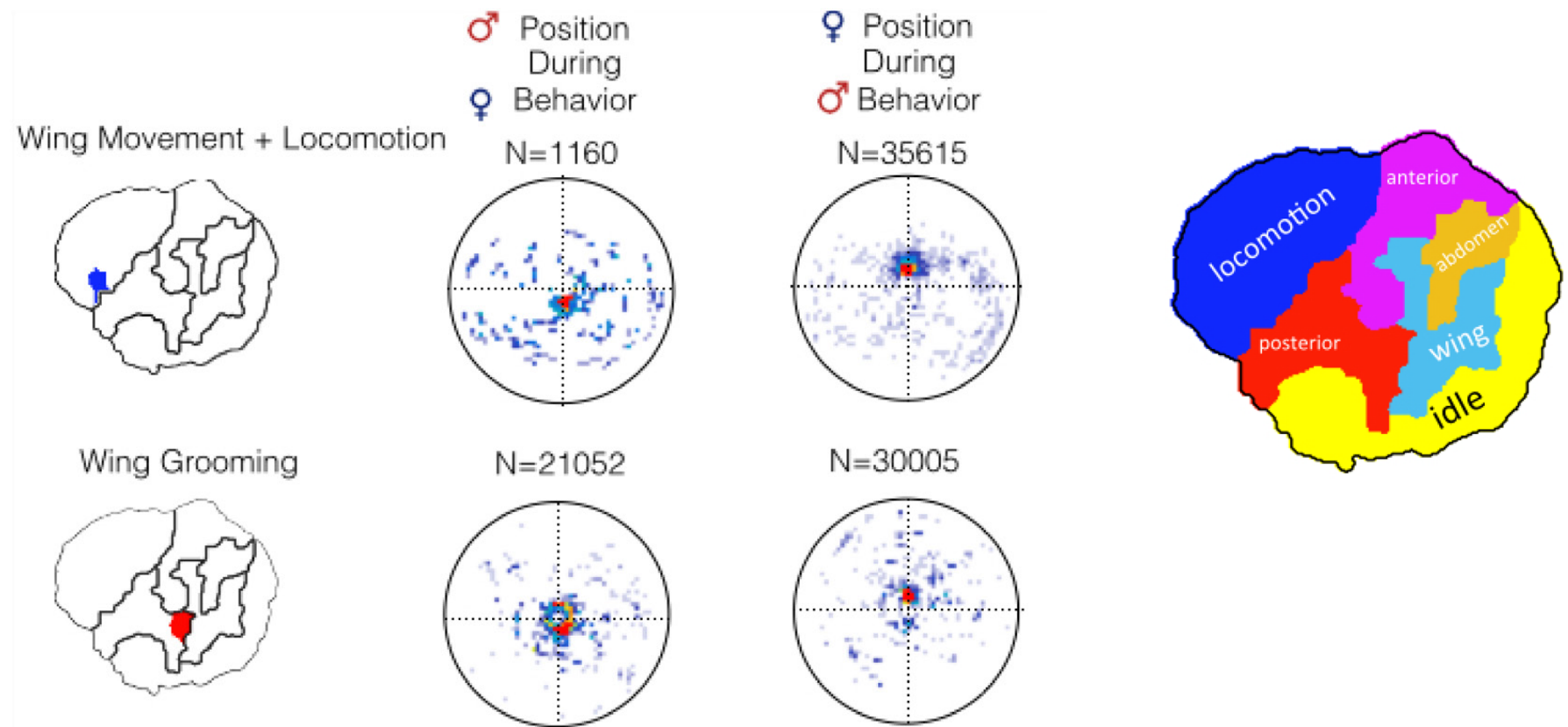


$$p(\text{Behavior}|\vec{x}_1, \vec{x}_2)$$



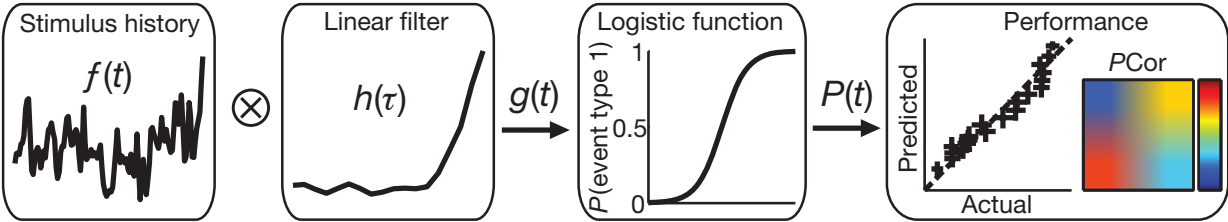
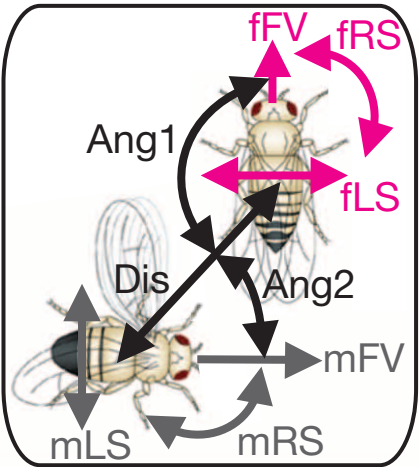
Klibaite et al, Physical Biology (2017)

$$p(\vec{x}_1, \vec{x}_2 | \text{Behavior})$$

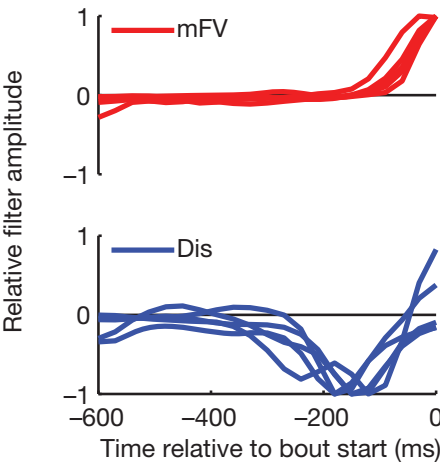


Klibaite et al, Physical Biology (2017)

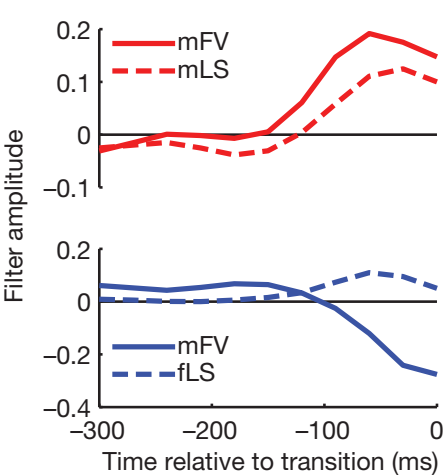
Linking individuals through regression:

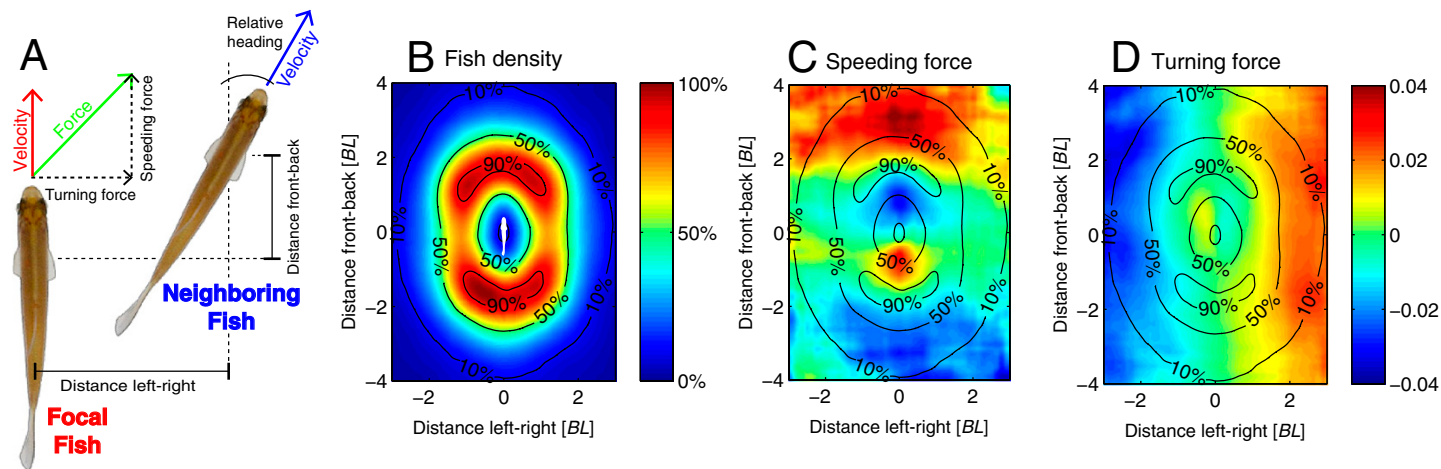


Before start of sine song:



Before sine to pulse song transitions:



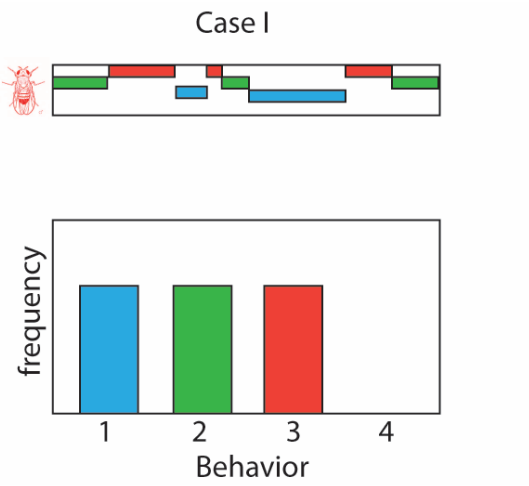


Inferring the structure and dynamics of interactions in schooling fish

Yael Katz^a, Kolbjørn Tunstrøm^a, Christos C. Ioannou^a, Cristián Huepe^b, and Iain D. Couzin^{a,1}



What is an interaction?

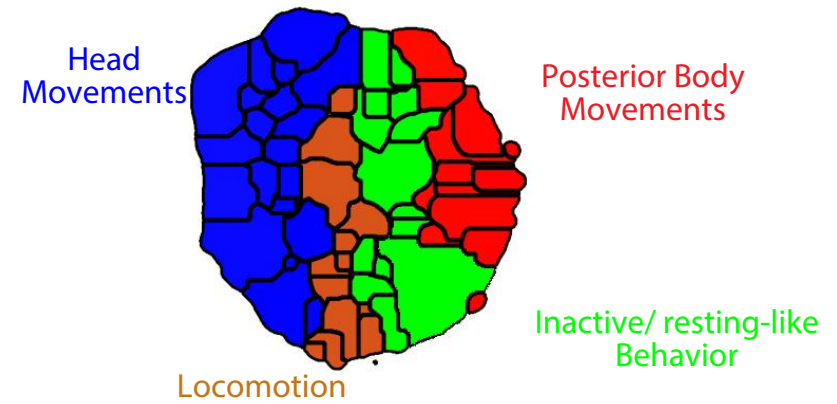


Synchronization

Similar Repertoires

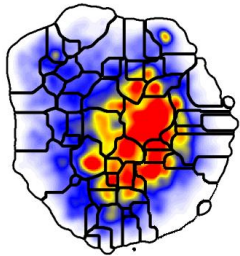
Emerging Behaviors

Or Maybe Predictability?

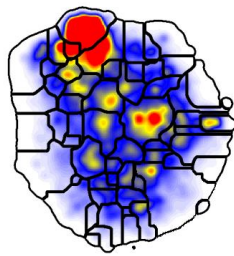


FIRST TRIAD

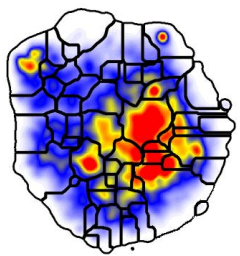
Map of Partner, with Subject



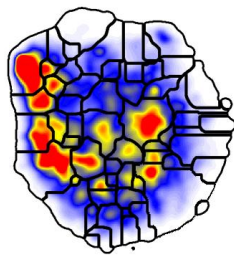
Map of Stranger, with Subject



Map of Subject, with Partner

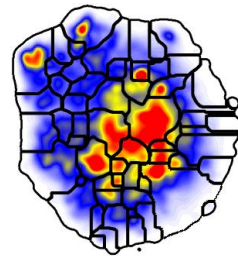


Map of Subject, with Stranger

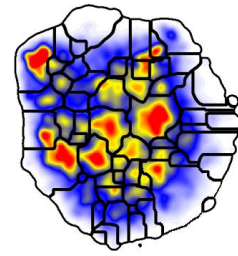


SECOND TRIAD

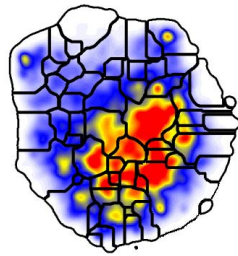
Map of Partner, with Subject



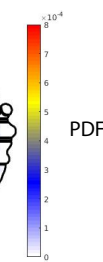
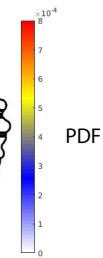
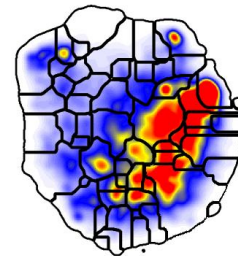
Map of Stranger, with Subject



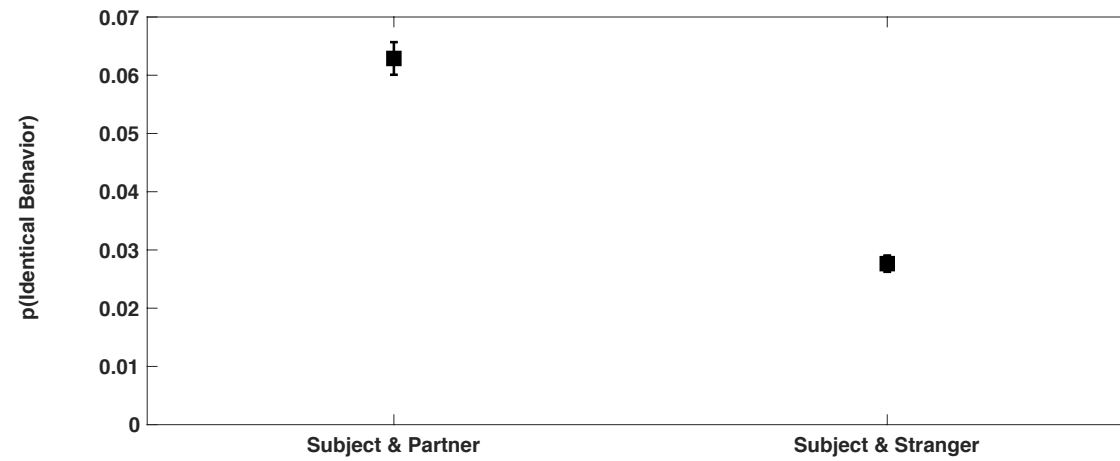
Map of Subject, with Partner



Map of Subject, with Stranger



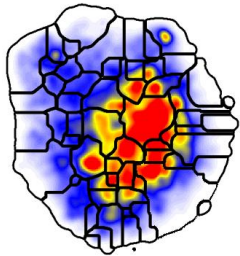
Sena Agezo
Robert Liu



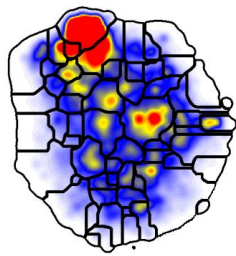
FIRST TRIAD

SECOND TRIAD

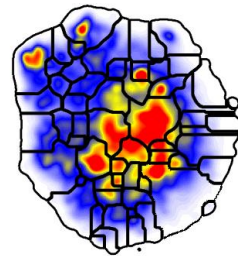
Map of Partner, with Subject



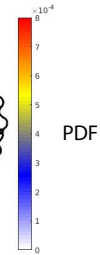
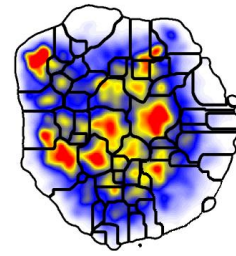
Map of Stranger, with Subject



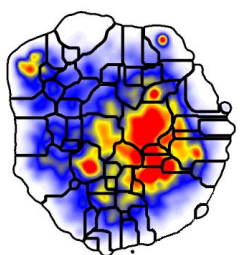
Map of Partner, with Subject



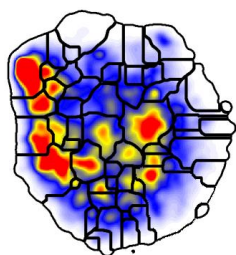
Map of Stranger, with Subject



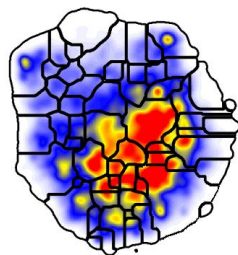
Map of Subject, with Partner



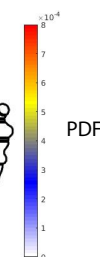
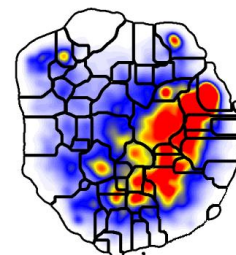
Map of Subject, with Stranger



Map of Subject, with Partner

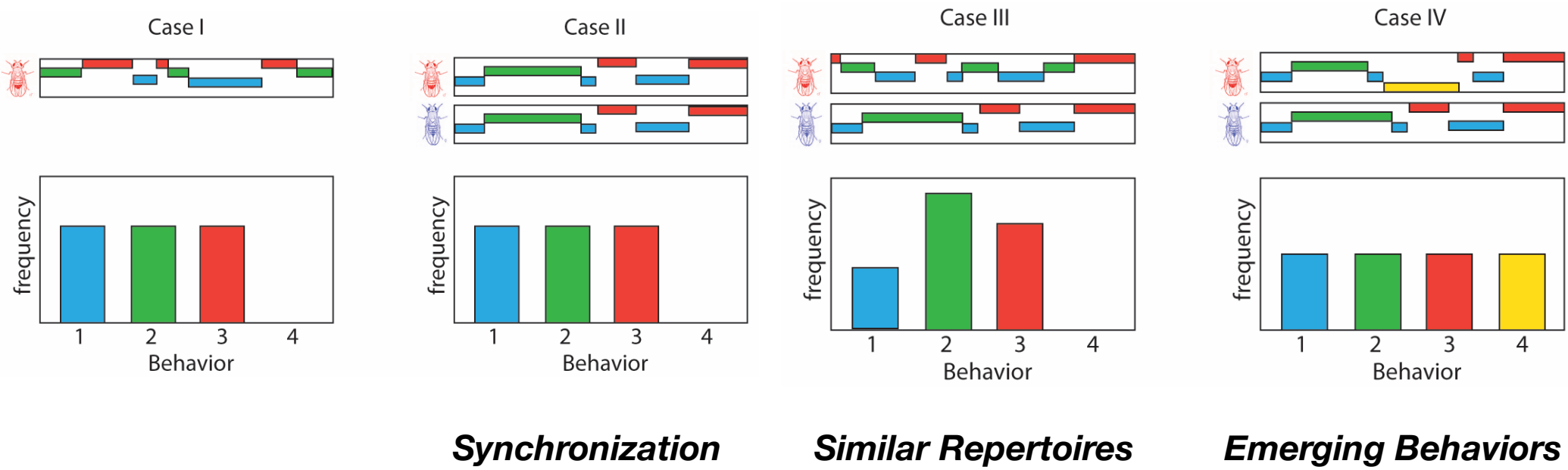


Map of Subject, with Stranger



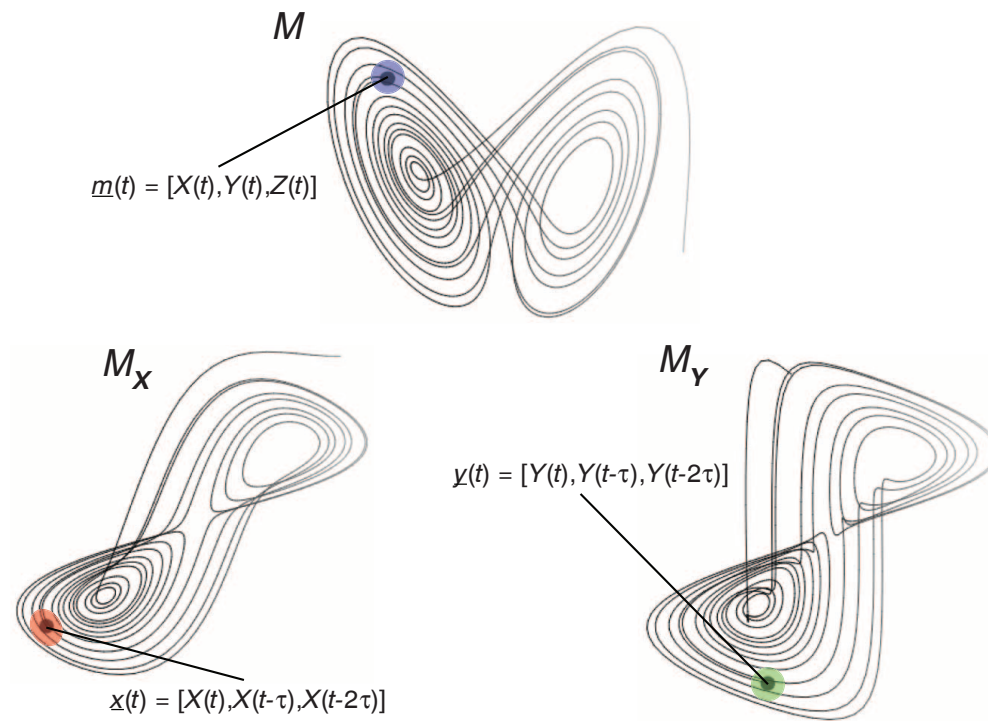
Sena Agezo
Robert Liu

What is an interaction?

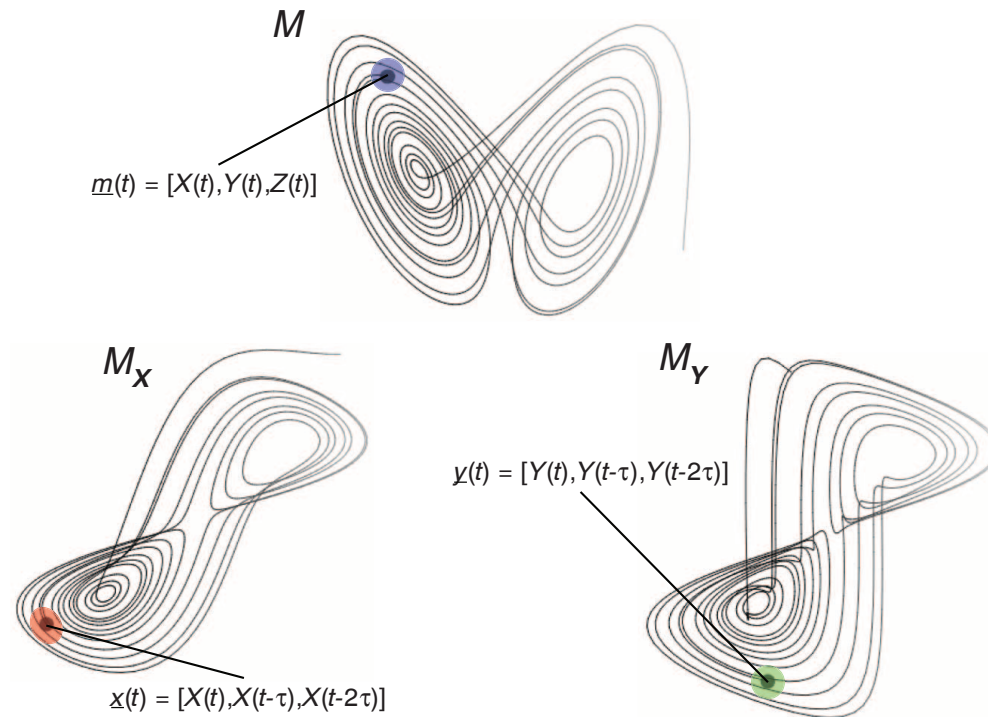
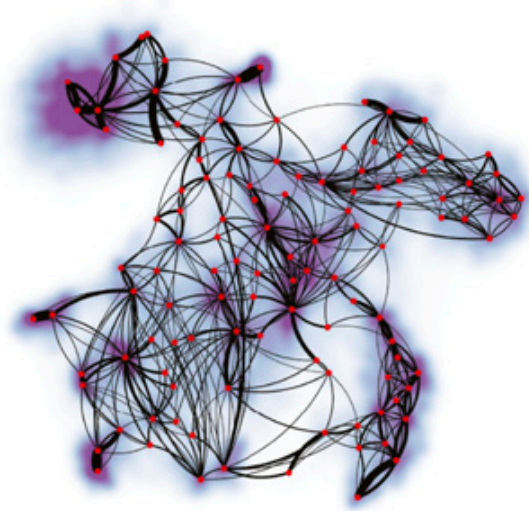


Or Maybe Predictability?

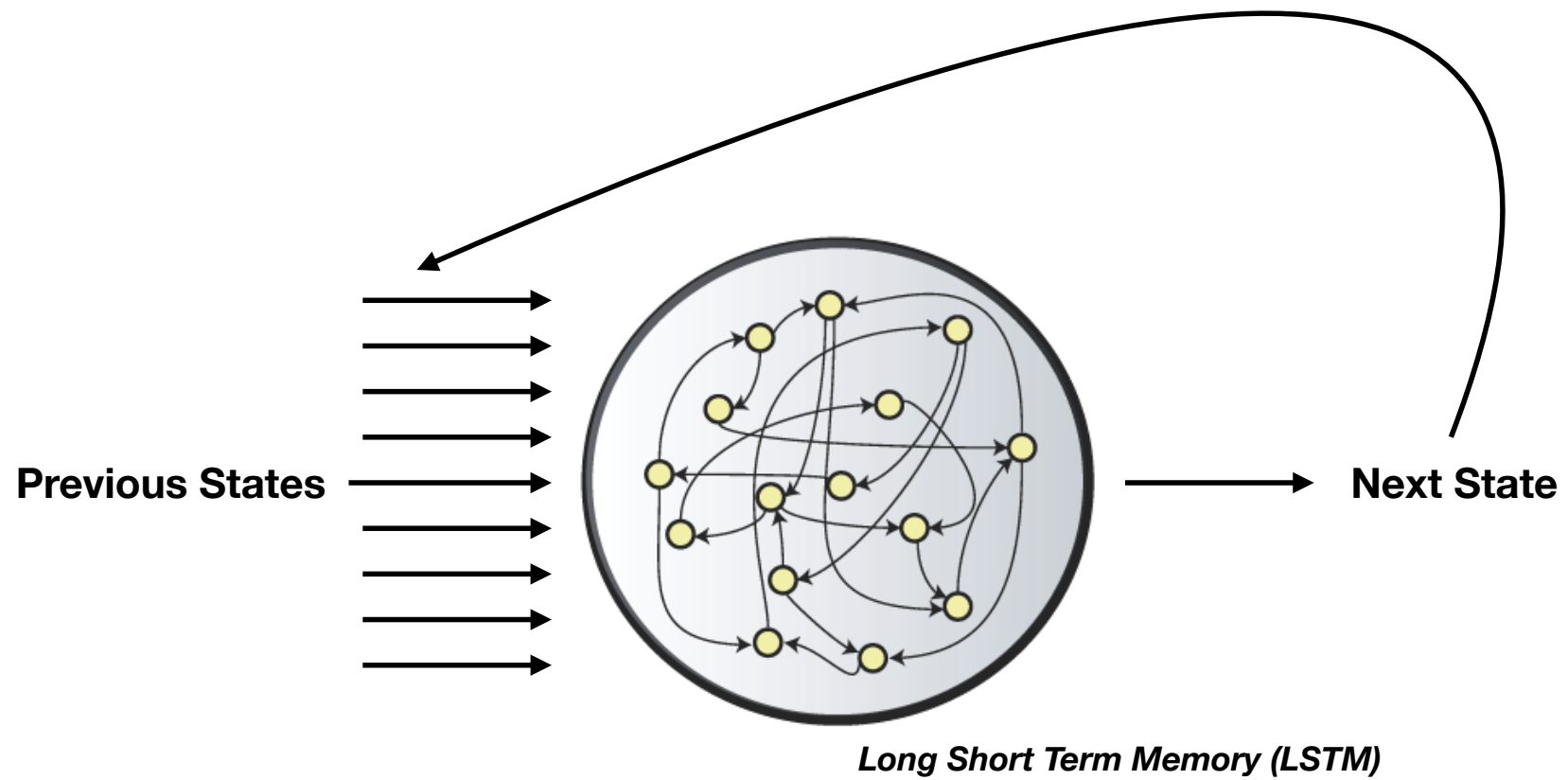
How can we think about predictability as a dynamical property?

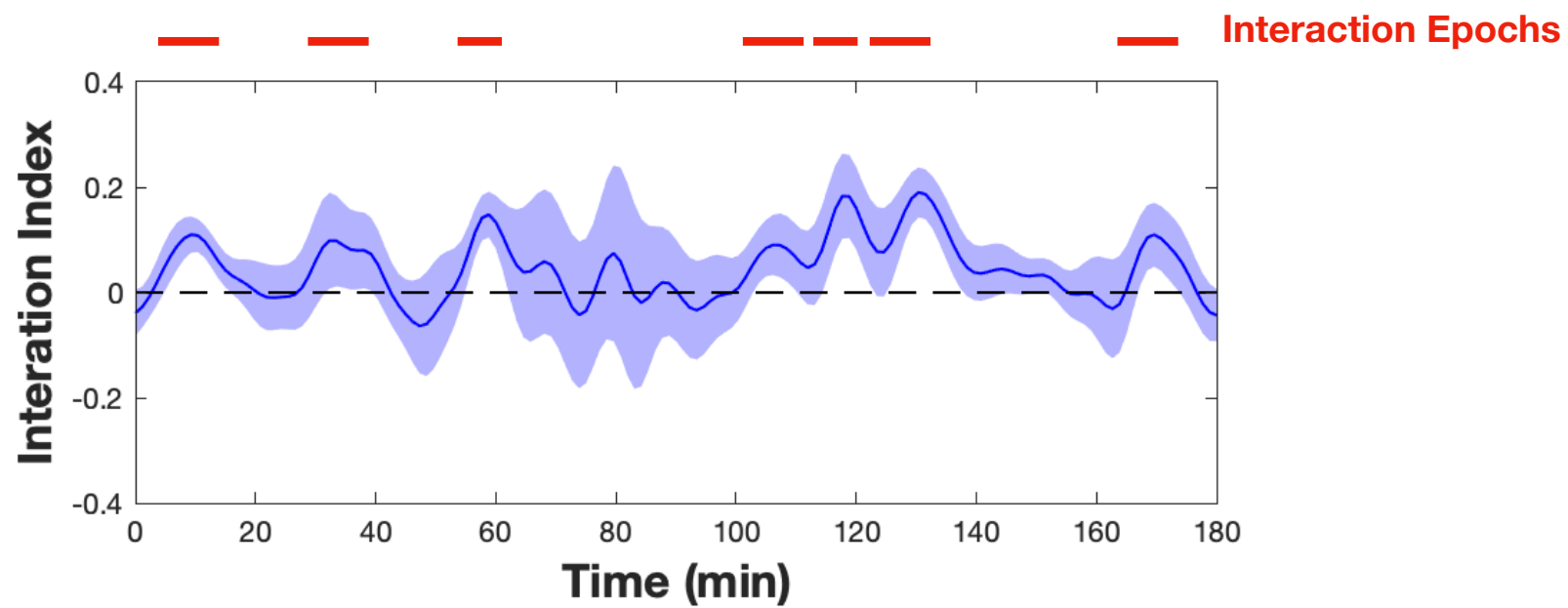


How can we think about predictability as a dynamical property?

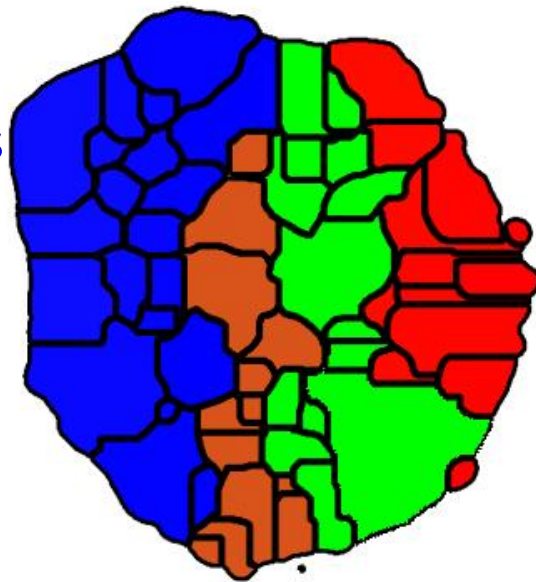


Problem: We don't have a continuous dynamical system...





Head
Movements

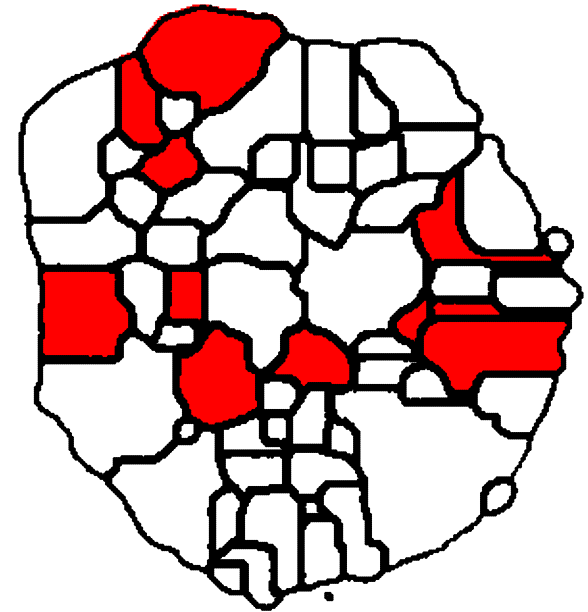


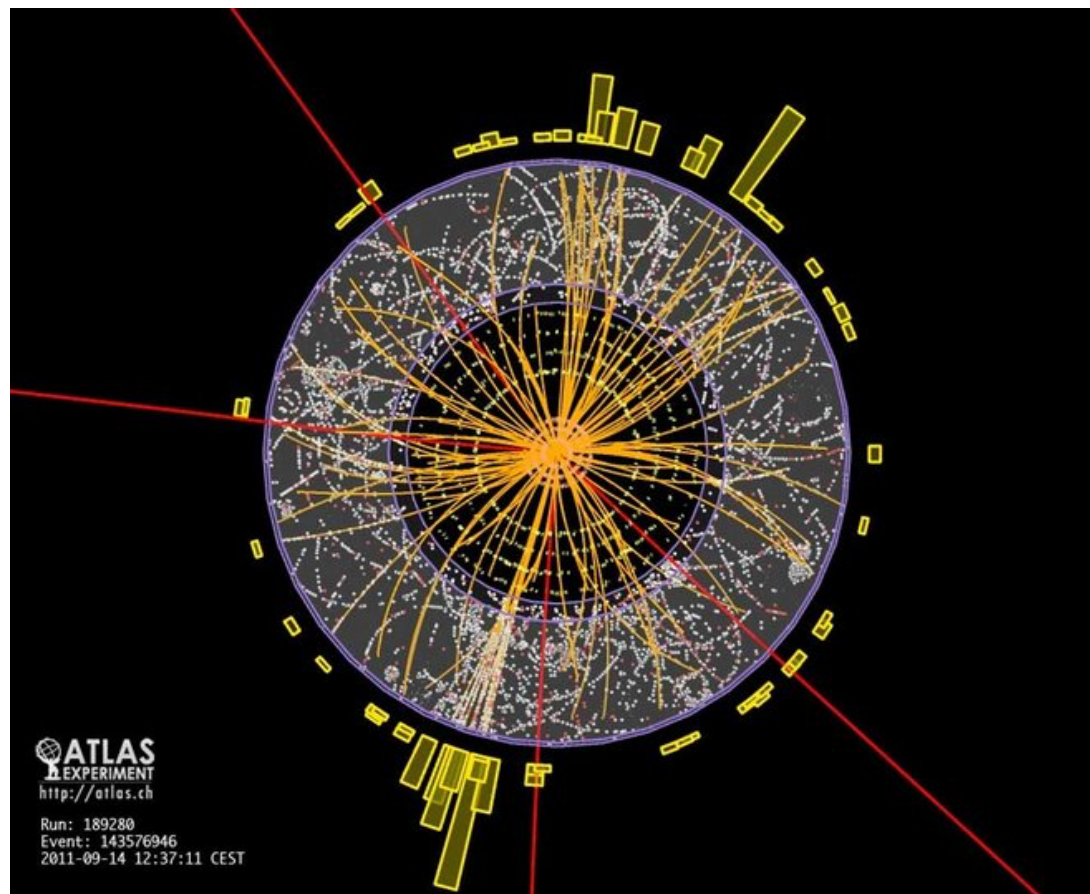
Locomotion

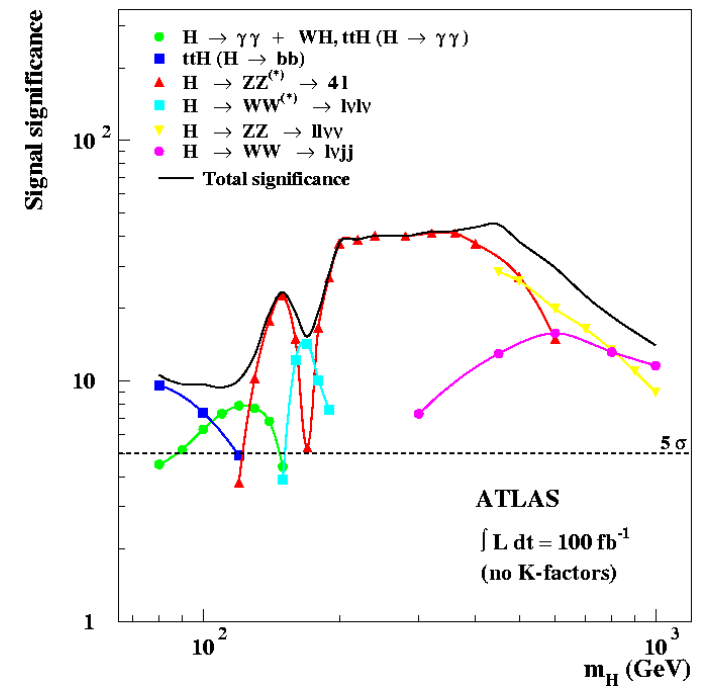
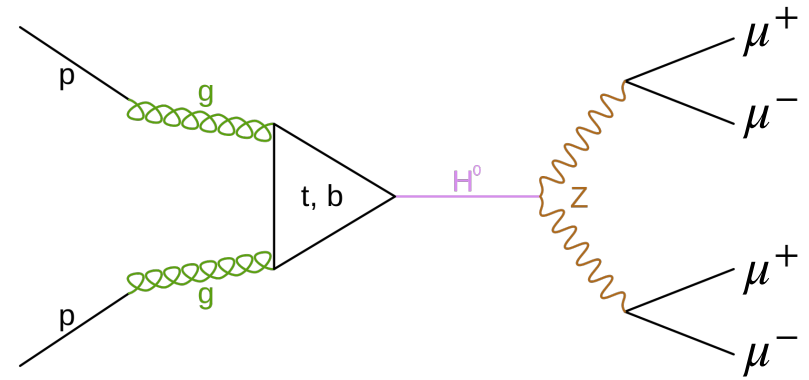
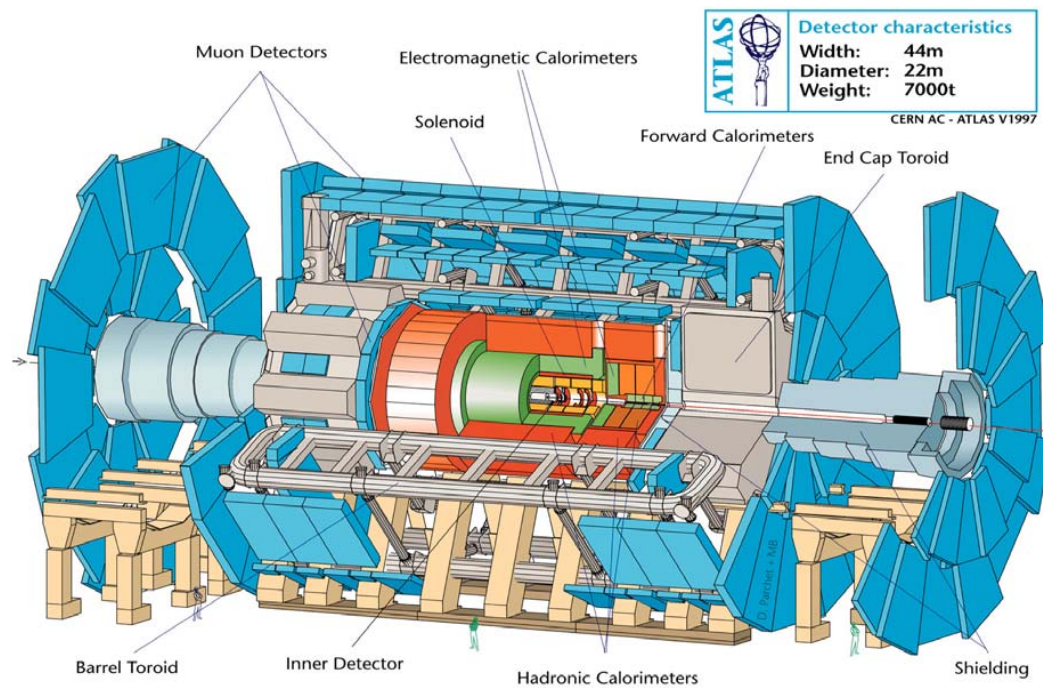
Posterior Body
Movements

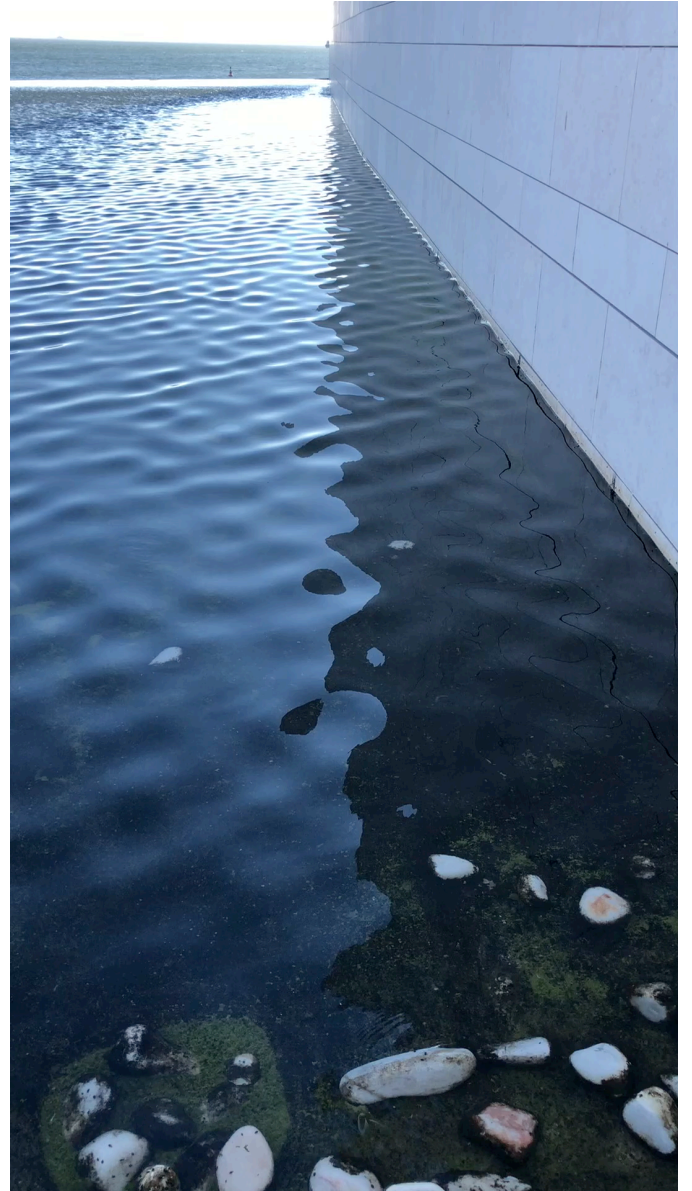
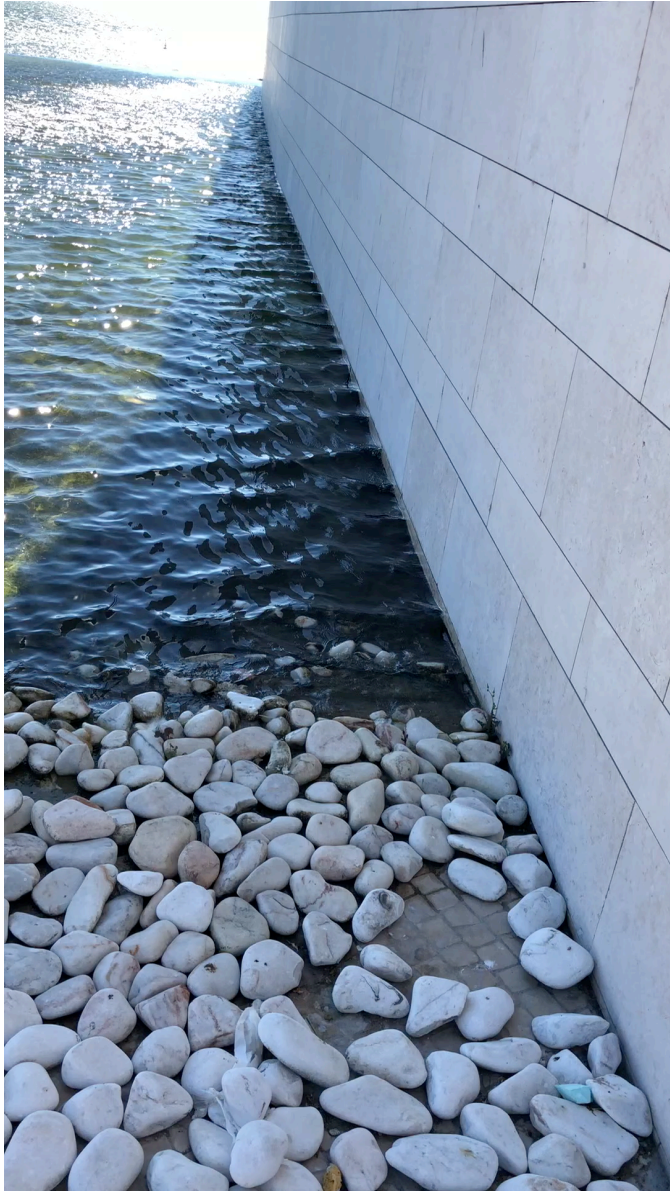
Inactive/ resting-like
Behavior

**Regions with Statistically-Significant
Enrichment in Interacting Epochs**











$h(x, t)$ →



→ Measure $h(x, t)$ and E



Train Model to Accurately
Predict $h(x, t | E)$



Correctly Output
Future Untrained $h(x, t | E)$



Navier-Stokes Equations

(conservation of mass & momentum)

$$\rho \frac{\partial \mathbf{u}}{\partial t} + (\mathbf{u} \cdot \nabla) \mathbf{u} = -\nabla p + \nu \nabla^2 \mathbf{u} + \mathbf{f}$$

$$\nabla^2 p = 0$$



1-D Shallow Water Approximation

$$\frac{\partial h(x, t)}{\partial t} + \frac{\partial [h(x, t)u]}{\partial x} = 0$$



Linearization

$$\lambda = \sqrt{\frac{U^2}{Hg}} \quad A = \frac{U^2 W}{g}$$

$h(x, t)$ →



