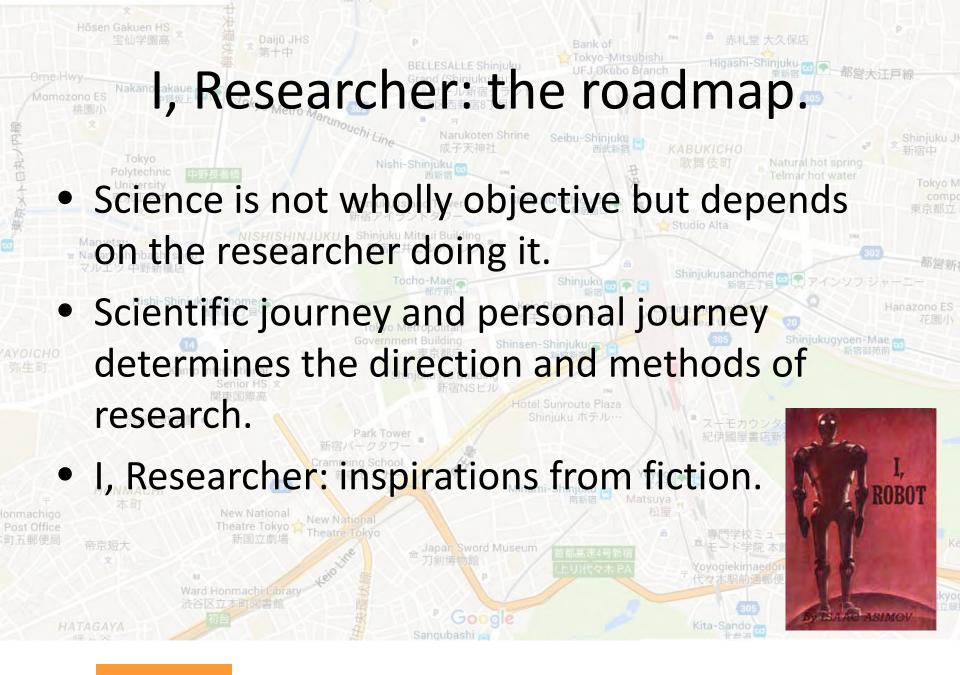
### I, Researcher: Finding one's role in science

#### Ray Luo (LC) RIKEN BSI



ray LC

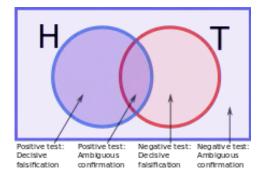
### Science depends on the scientist.

- Trofim Lysenko: exposed seed to humidity low temp (vernalization) to increase yield, passed trait to offspring (reject natural selection for cooperation)
- Questionnaire of farmers confirms agricultural revolution (against theory is against the party)
- Famine, imprison scientists



#### Science depends on the scientist.

- Peter Wason: asked to identify rule applying to three numbers (2-4-6)
- Subjects can ask if any set of 3 nums satisfies rule, most tested seq of even num even though correct rule is increasing nums
- No questions that would falsify rule: confirmation bias, gather positive info





# Cultural personal influences on science.

- Motivation
- Metaphysical
- Practicality
- Culture (science fiction)
- Consistency (avoid cognitive dissonance)
- Controversy (debate)
- Perspective (C. P. Snow, The Two Cultures)

# Case study culture 1: HRL research labs, UC Riverside robotics REU.

8.1. Inheritance Relationships

8.1.1. Application Suite Inheritance Diagram

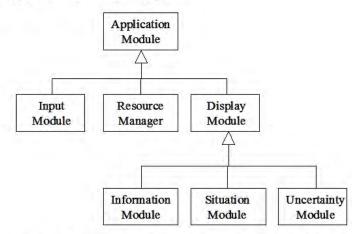
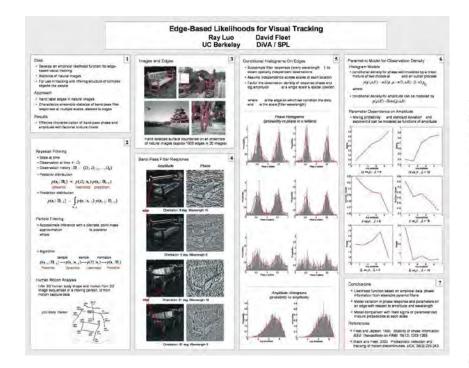


Figure 1. This is an inheritance diagram that represents how the applications will be derived; notice that this is not a class inheritance diagram. The Input Module, Resource Manager, and Display Modules will inherit the sockets implementation and a main control panel from the Application Module. The Information, Situation, and Uncertainty Modules will be inheriting display navigation and display interfaces from the Display Module.



#### Case study culture 2: Cal Berkeley, Palo Alto Research Center.



Every node in the model is continuous, with equations that look like

$$\begin{aligned} H_s(t+1) &= BV_s(t+1) - H_s(t) + W_H(t), \\ V_s(t+1) &= AV_s(t) + W_V(t), \\ H_o(t) &= C_H H_s(t) + U_H(t), \\ V_o(t) &= C_V V_s(t) + U_V(t), \end{aligned}$$

where  $H_s$  is the control module associated with the hand,  $H_o$  is the estimated hand parameters (in particular, hand position),  $V_s$  and  $V_o$  are the estimated and observed target motion characteristics, A, B, and C are corresponding output matrices, and the Ws and Us are noise.  $H_o$  and  $V_o$  are observed. Note that the first equation accounts for sensory correction due to visual feedback.

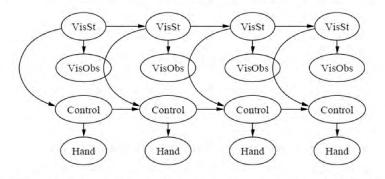
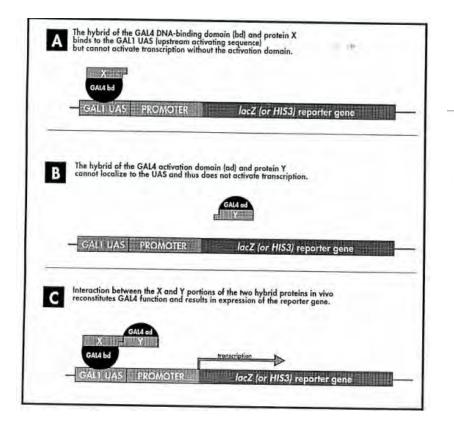
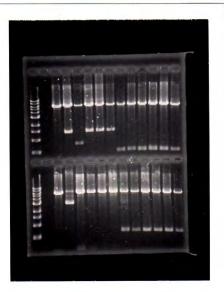


Figure 1: Graphical model of visuomotor tracking. Note that VisSt and Hand nodes are observed in our case.

#### Case study culture 3: UCLA.



### AP{ $2\mu$ , $2\sigma$ , $3\mu$ , $3\sigma$ } ligated to pGBT.

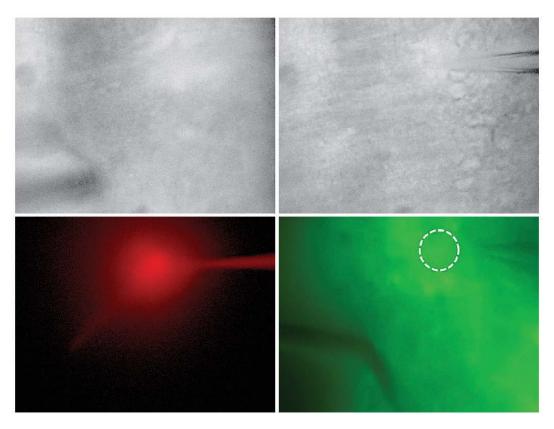




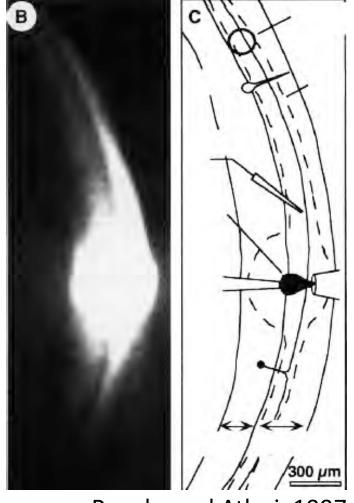
ray LC

#### Case study culture 3: UCLA.

Oregon Green BAPTA-1 AM -> transverse slice

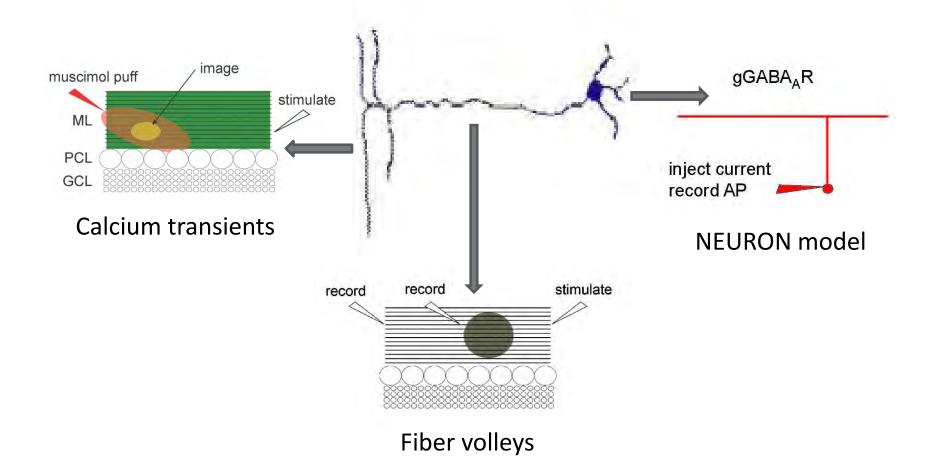


Luo, Dellal, Otis, 2012

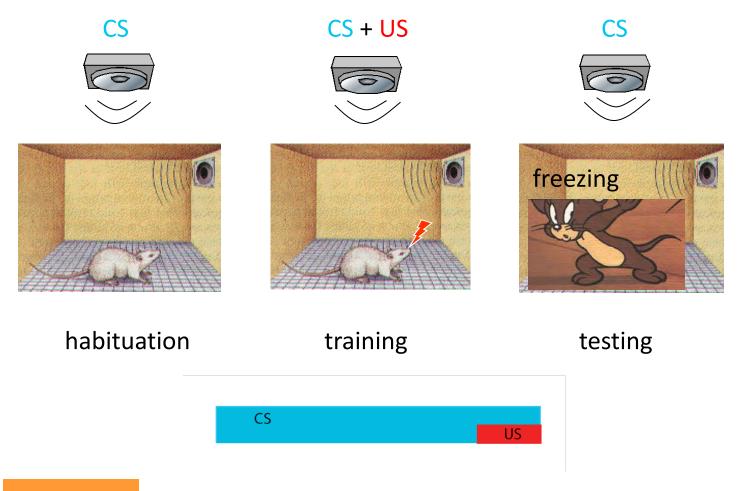


Regehr and Atluri, 1997

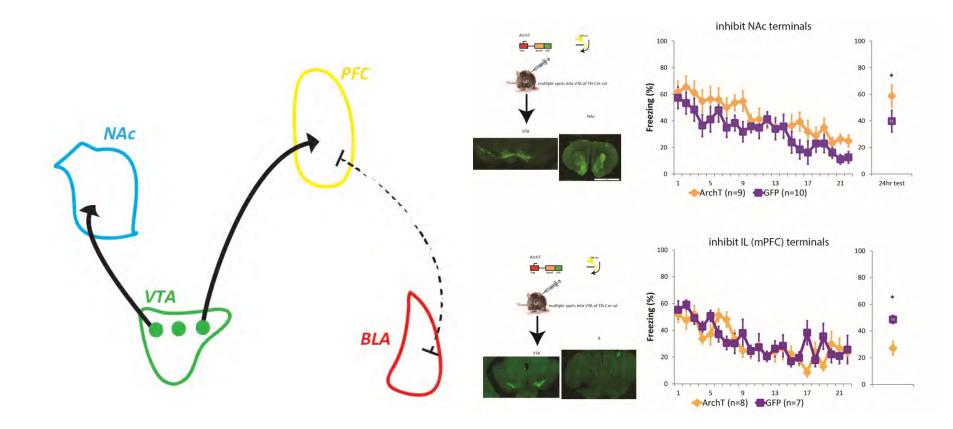
#### Case study culture 3: UCLA.



#### Case study culture 4: RIKEN Brain Science Institue.



### Case study culture 4: RIKEN Brain Science Institue.



#### Lab pictures: a collection.











# How to reconcile doing unbiased science with doing what you want?

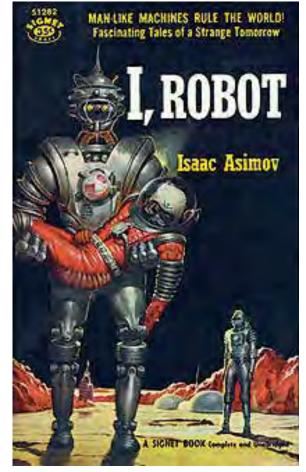
- In social science, interpretation is inevitable.
- Even in science, direction and methods differ.
- In papers we tell "a story".
- In next step we do what is feasible, interesting
- SAT testing has hidden bias (Aguinis et al, 2016).
- Cultural differences: Japan vs. US.
- Like writer making sense of world around her.
- Recognize subjectivity in self, but try to eliminate systematic bias.

### Three Laws of Research

- 1. robot may not injure humans
- 2. obey humans unless conflict 1.
- protect own existence as long as
  and 2.

I, Researcher

- 1. researcher may not bias results
- 2. obey scientific method unless bias
- 3. do what thrills you as curiosity dictates long as 1. and 2.



"Evidence": robot runs for office

#### I, Researcher: the summary.

- Science is not perfectly objective.
- Life goals and interests affect science.
- Recognize one's own limitations.
- Let's discuss!