



Implementation and Evaluation of Audio Based Methods for Robust Inter-Robot Communication

Project Thesis – Introductory Talk

Finn Poppinga

Hamburg University of Technology

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Outline



- Introduction
- Chirp Based Communication
- The NAO Robotic Platform
- Status Quo of Implementation
- Current Problems and Outlook
- References

Introduction



Introduction

Chirp Based CommunicationMotivation and Problems



Motivation

- Aerial acoustic transmission over a large distance (25m)
- Robust transmission in noisy environments

Chirp Based CommunicationMotivation and Problems



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Problem

- Supposedly low achievable bit rate (16bps)
- Designed for single payload transmission with server based backend

Chirp Based Communication Motivation and Problems



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Method introduced by Lee et al. [3]

Chirp Based Communication Working Principle – Symbol Space



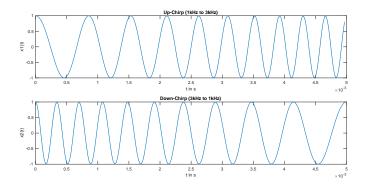


Figure: Time domain plots for up- and down-chirp.

Chirp Based CommunicationWorking Principle – Symbol Correlation



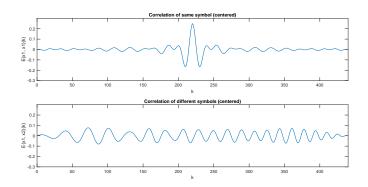


Figure: Correlation of up-chirp with (1) up-chirp and (2) down-chirp

Chirp Based Communication

Working Principle – Symbol Mapping



Definition

For every 0-bit, transmit a down-chirp. For every 1-bit, transmit an up-chirp.

Chirp Based Communication



Working Principle – Receiver Synchronization

Definition

Data is transmitted in packages, each package containing 16bits

Chirp Based Communication





Definition

Data is transmitted in packages, each package containing 16bits

each package is announced by a preamble

Chirp Based CommunicationWorking Principle – Receiver Synchronization



Definition

Data is transmitted in packages, each package containing 16bits

- each package is announced by a preamble
- every two symbols are spaced by a guard interval

Chirp Based CommunicationWorking Principle – Receiver Synchronization



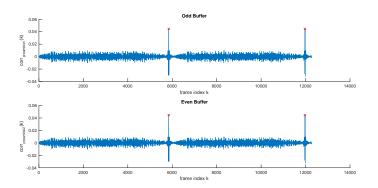


Figure: Correlation with the preamble yields significant peaks at beginning of each package.

Chirp Based Communication Working Principle – Symbol Detection



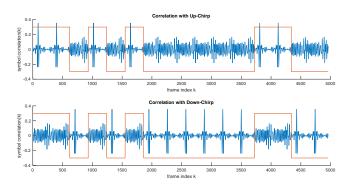


Figure: Matched Filter Symbol Detection. The detected bits are marked orange.

The NAO Robot System





Figure: NAO Robot standing upright.

The NAO Robot System Audio Hardware



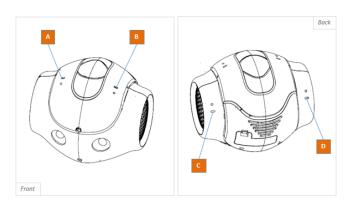


Figure: Positioning of NAO's microphones [4].

The NAO Robot System Audio Hardware



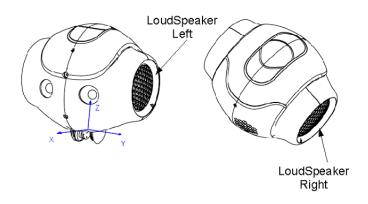


Figure: Positioning of NAO's speakers [4].

Status Quo of Implementation C++ Framework



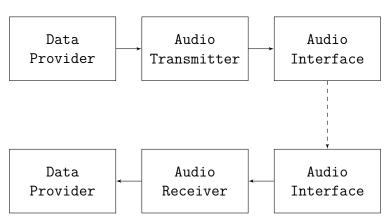


Figure: Data Flow inside the C++ Application

Status Quo of Implementation External Libraries



FFTW

A very fast implementation of the Fast Fourier Transform (FFT), also used by MATLAB [2].

PortAudio

Free, cross-platform, open-source, audio I/O library [1].

Problems and Outlook Pulse Shaping and Band Limiting



 Sharp edges in chirp pulses lead to higher bandwidth than needed.

Problems and Outlook Pulse Shaping and Band Limiting



- Sharp edges in chirp pulses lead to higher bandwidth than needed.
- Solution: Use a pulse shaping filter for each symbol.

Problems and Outlook Envelope Detection for High Frequency Chirps



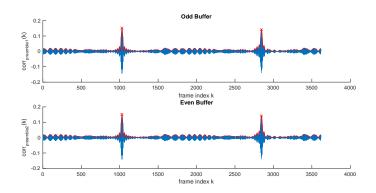


Figure: The Envelope Detection yields more distinctive peaks.

Problems and Outlook

Larger Symbol Space for Higher Data Rate



Idea:

Use multiple Chirps in different frequency areas to utilize more of the available spectrum.

Discussion



Discussion

- Ross Bencina and Phil Burk.
 Portaudio—an open source cross platform audio api.
 In Proc. 2001 Intl. Computer Music Conf. (ICMC-01), 2001.
- Matteo Frigo and Steven G Johnson. Fftw user's manual. Massachusetts Institute of Technology, 1999.
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In Computer Communications (INFOCOM), 2015 IEEE Conference on, pages 2407–2415. IEEE, 2015.

- Aldebaran Robotics.
 - Nao software 2.1.4 documentation. *URL http://www.aldebaran-robotics.com*, 2016.