

# A semblance based TDOA algorithm for sound source localization

*Guilherme Seidyo Imai Aldeia*

Digital Signal Processing Team - UFABC  
Universidade Federal do ABC

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# Quem somos



Guilherme S. I. Aldeia  
Bacharel em Ciéncia da Computação



Kaleb Alves  
Engenharia de Informação



Guilherme Barreto  
Engenharia de Instrumentação,  
Automação e Robótica



Alex E. Crispim  
Bacharelado em Física



Henrique Ferreira  
Bacharelado em Física



Kenji Nose-Filho  
Doutorado em Engenharia Elétrica

# Como surgimos

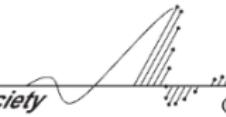
Em janeiro de 2019 nos juntamos para participar de uma competição internacional de processamento de sinais digitais. O resultado disso foi a criação de uma equipe chamada DSPTeam - UFABC.



2019 IEEE Signal Processing Cup:  
*Search and Rescue with Drone-Embedded  
Sound Source Localization*  
- Competition Details -



IEEE  
Signal Processing Society



# Signal Processing Cup 2019

O objetivo era processar sinais de 8 microfones acoplados em um drone para encontrar a localização de uma fonte sonora.

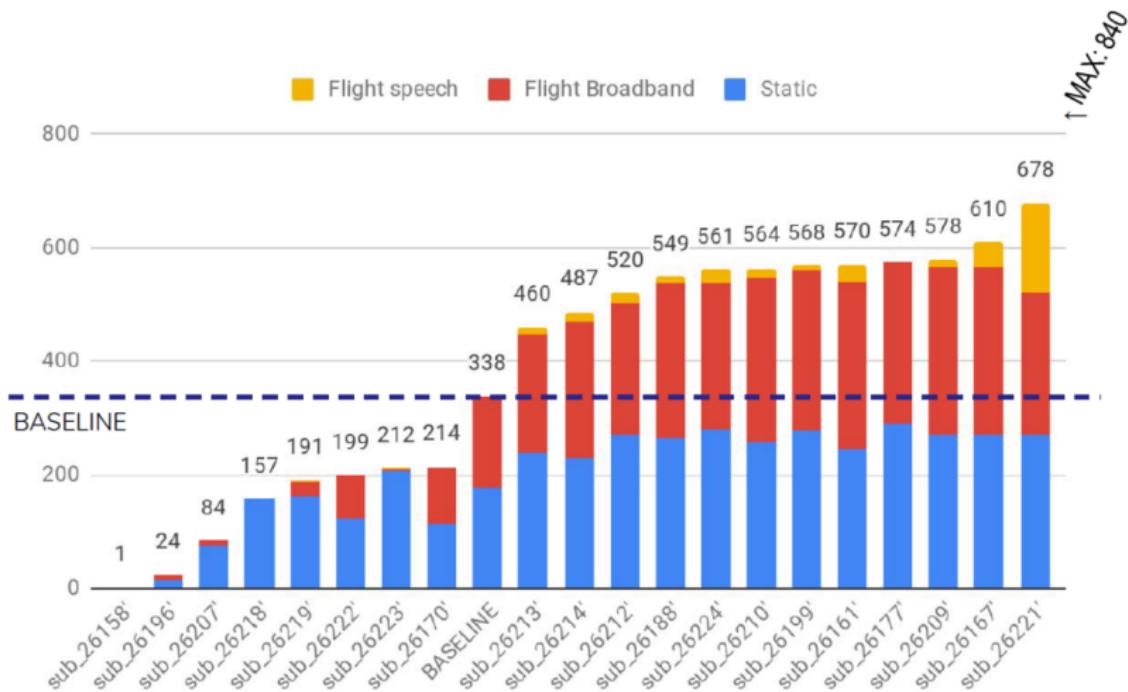


# Motivação da competição

*"Unmanned aerial vehicles (UAV), commonly referred to as drones, have been of increasing influence in recent years. Search and rescue scenario where humans in emergency situations need to be quickly found in areas difficult to access constitute an important field of application for this technology."*



# Nosso desempenho



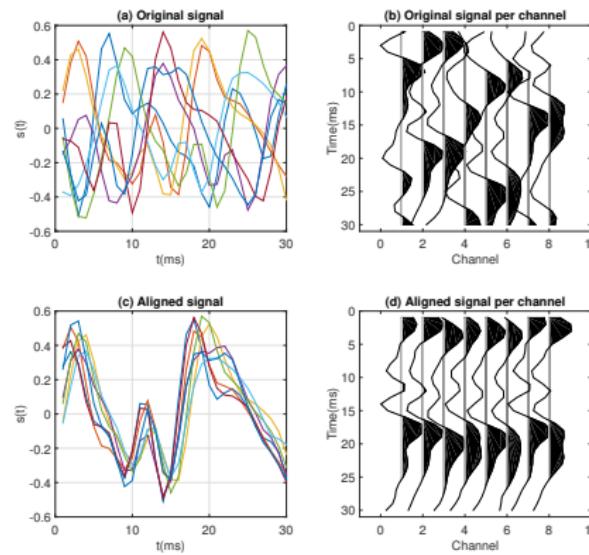
# Nosso desempenho

Nossa classificação foi baixa, e não poderemos mais participar da competição.

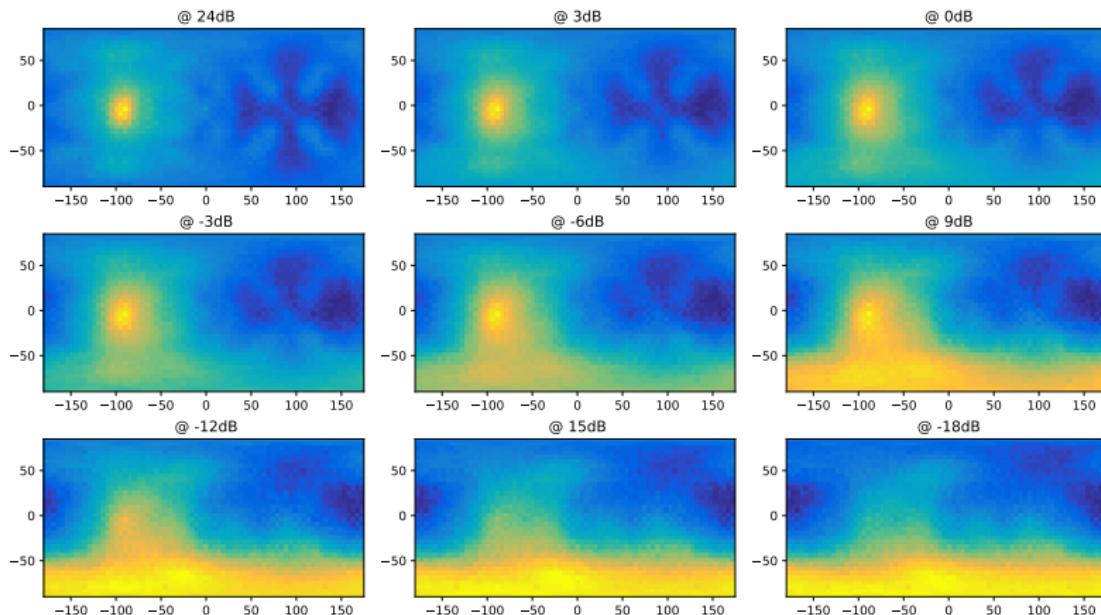
Entretanto, a equipe gostou do método desenvolvido, e desde então vem trabalhando para aperfeiçoá-lo.

# Método baseado no Semblance

Criamos um método inspirado no processamento de sinais sísmicos, que funciona buscando alinhar os sinais de todos os microfones.



# O drone agora pode "enxergar"



# Escrevemos um artigo sobre o método

XXXVII SIMPÓSIO BRASILEIRO DE TELECOMUNICAÇÕES E PROCESSAMENTO DE SINAIS - SBdT2019, 29/09/2019-02/10/2019, PETRÓPOLIS, RJ

## A semblance based TDOA algorithm for sound source localization

Guilherme Seidyo Imai Aldeia, Alex Enrique Crispim, Guilherme Barreto, Kaleb Alves, Henrique Ferreira, Kenji Nose-Filho

**Abstract**— In this paper we propose a new time difference delay of arrival technique based on the semblance multichannel coherency function for the problem of sound source localization. The proposed algorithm was tested on recordings from an Unmanned Aerial Vehicle (UAV) equipped with an array of 8 microphones, for estimating the azimuth and elevation angles of a speech based source. Our results shown that the semblance method has proven to be a robust strategy, obtaining good results regardless of the ego noise even in cases where the signal-to-noise ratio (SNR) was very low.

**Keywords**— time difference of arrival, semblance, sound source localization

### II. A SEMBLANCE BASED TDOA ALGORITHM

In this paper, we want to find the direction of a sound source (azimuth, elevation) using the records from an 8-channel cube-shaped microphone array embedded in a flying UAV [7].

The proposed algorithm is based on correcting the time-delay that the propagating wave arrives in each of the 8-channel microphones. Given a source at direction  $\mathbf{k}_d \in \mathcal{R}^3$ , that point towards a source parametrized by azimuth  $\Theta_d \in [-\pi, \pi]$  and elevation  $\Phi_d \in [-\frac{\pi}{2}, \frac{\pi}{2}]$ . The time delay of a microphone at location  $\mathbf{m}_i$  and a reference point at the origin

# Escrevemos um artigo sobre o método

Semana passada recebemos a notícia de que o artigo foi aprovado!

Conference	Paper title (details)	Status
SBrT 2019	<i>A semblance based TDOA algorithm for sound source localization</i>	Accepted

# SBrT 2019!



SBrT 2019 ▾ Artigos Aceitos Inscrições Programação Técnica ▾ Local do Evento Hospedagem Contato ▾

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## XXXVII Simpósio Brasileiro de Telecomunicações e Processamento de Sinais

Comunicação, Aprendizado e Cooperação entre Máquinas, Objetos e Humanos



# SBrT 2019!

$$\Delta\sigma = \arctan \frac{\sqrt{(\cos \phi_2 \sin(\Delta\theta))^2 + (\cos \phi_1 \sin \phi_2 - \sin \phi_1 \cos \phi_2 \cos(\Delta\theta))^2}}{\sin \phi_1 \sin \phi_2 + \cos \phi_1 \cos \phi_2 \cos(\Delta\theta)}.$$

$$Z_d = \frac{\sum_n |\sum_i s_i(n)|^2}{N_r \sum_n |s_i(n)|^2} \quad 4\pi \sin^2(\theta/2) \approx \pi \theta^2 \approx 0.1 \text{ sr},$$

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**Algorithm 2:** Find semblance local (find\_local)

**input :** frameSize: size of the frames  
 overlap: overlap between frames  
 $\Delta$ : interval between angles to be tested  
 $SoS$ : speed of sound on the medium  
 $Fs$ : sampling rate  
 $x$ : the data of the 8-channel  
 $micPos$ : array with coordinates [x, y, z] of the microphones positions

**output:**  $z$ : matrix mapping correlation with angles  
 $\Theta$ : tested values for elevation  
 $\Phi$ : tested values for azimuth

```

sTotal = length(x);           // total samples
sSize = round(frameSize * Fs); // sample size
sOverlap = round(overlap * sSize); // sample overlap
nFrames =
    ceil((sTotal - sSize)/(sSize - sOverlap)) + 1;
painels = [ ];
for i in range(nFrames) do
    begFrame = i * (sSize - sOverlap);
    endFrame = begFrame + sSize;
    xFrame = x[begFrame : endFrame, :];
    painels[i] = find_global(delta, SoS, Fs, xFrame);
return pooling(painels), Θ, Φ;

```

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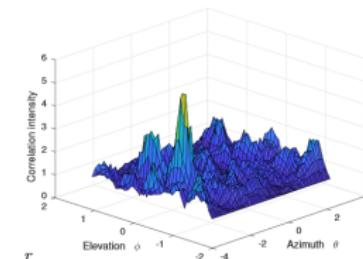
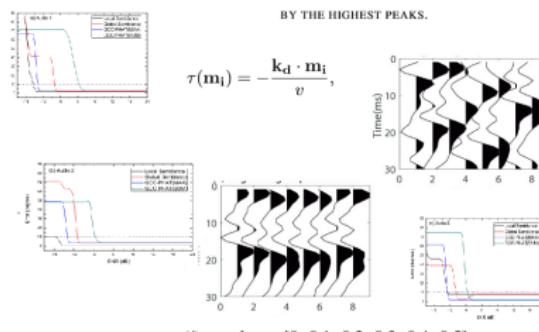


Fig. 1  
 3D SURFACE REPRESENTATION OF THE SEMBLANCE FUNCTION RESULT.  
 THE HIGHER VALUES OF THE SIGNAL CORRELATION ARE REPRESENTED BY THE HIGHEST PEAKS.



$$\tau(m_i) = -\frac{\mathbf{k}_d \cdot \mathbf{m}_i}{v},$$

- (i)  $overlap = [0, 0.1, 0.2, 0.3, 0.4, 0.5]$
- (ii)  $\Delta = [17.5, 15, 12.5, 10, 7.5, 5]$
- (iii)  $frameSize = [0.064, 0.128, 0.256, 0.512, 1.024]$