Voice Control for a Gripper Using Mel-Frequency Cepstral Coefficients and Gaussian Mixture Models

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Abstract

This work presents an implementation of a speaker-dependent speech recognition system used to control a gripper. The application was made using MATLAB and the gripper was assembled using the Lego Mindstorm NXT robotic kit. Four commands are implemented for controlling the gripper: Open, close, rotate left and rotate right. The development was divided into two stages. In training stage, we use Mel Frequency Cepstral Coefficients (MFCCs) and Gaussian Mixture Models (GMMs) to generate a representation of each defined command. Then, in testing stage, those models are used to identify the speakers utterance and send the command to the actuator. Finally, we present test results that show a performance of 95.09% for our system, and then we compare it with similar works.

Methodology

The methodology developed along this work is based on two main features. The first one is that the system is focused on detecting isolated words; this means that the speaker will say words separated by silence spaces. The second feature is that the system detects words only for the speaker for whom the models were computed.

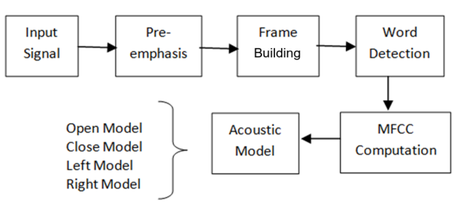

Figure : Training Stage.

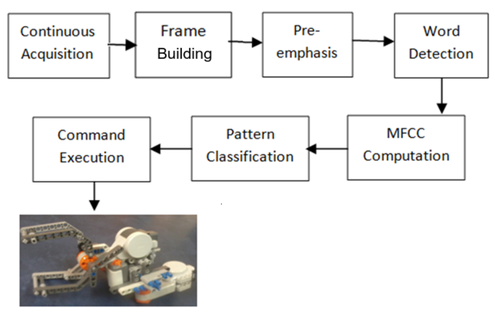

Figure : Testing Stage.

Results

Speaker	GMM Number	No. of words	Command Performance (%)				Global Performance (%)
			Open	Close	Left	Right	
1	5	17	94.11	100	94.11	100	**97.05**
1	8	17	100	88.23	82.35	94.11	**88.23**
1	11	17	94.11	82.35	82.35	94.11	**88.23**
2	5	18	100	94.11	94.11	100	**97.05**
2	8	16	100	100	100	100	**100**
2	11	18	100	100	100	100	**100**

Table : Performance of the Voice Recognition System

Approach	Description	Performance
Tezer [6]	Used LPC and DTW. Implemented in MATLAB.	86%
Beritelli [3]	Used VQ. Proposed to noise-robust application	92%
Bedoya [2]	Used wavelts, HMMs and MFCCs	98%
Phokharatkul [5]	Used filter banks and Mel scale analysis	96.3%
Ali [1]	Used MFCCs and ANN. Isolated or continuous speech mode	96%
Chin [4]	Used MFCCs and ANN	98.9%
Ours	Used MFFCs and GMMs, implemented in MATLAB	95.09%

Table : Comparision of different speech recognition systems

Conclusions

In this paper we presented an speaker-dependent speech recognition system based on Mel Frequency Cepstral Coefficients (MFCCs) for extracting features and Gaussian Mixture Models (GMMs) for creating the model of each command. We test the systems with two different speakers and the worst case was 91.17% (average of global performance for speaker 1) of accuracy for a speaker. For a particular command, the worst case was 82.35% and the average of the global performance of the system was 95.09% (see Results section).
As future work, we propose the evaluation of the system with more than four commands and the creation of models with utterances from different speakers in order to test the capability of the system to be speaker-independent.

References

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