HANDS-FREE HUMAN-MACHINE DIALOGUE CORPORA, TECHNOLOGY AND EVALUATION

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ABSTRACT

In this paper we will review the progress of hands-free, Voice User Interface (VUI) research work at Bell Labs, including: a multichannel data base collection, technology development, and performance evaluation. Thirty-channel, simultaneous recordings have been conducted in a moving car, collecting speech from 57 subjects under various weather, road, and noise conditions. These are being used for both testing and adaptation purposes. Technology issues relevant to hands-free VUI are specifically addressed, including: (1) acoustic echo cancellation (AEC) and near-end (user's) speech detection; (2) background noise estimation and suppression; (3) reliable and timely barge-in; (4) signal pickup improvement using intelligent microphone arrangements; and (5) speaker and environment adaptation. An evaluation of the developed technologies using the car database is presented. An all software, hands-free, full duplex voice user interface demo has been implemented on a LINUX PC. The real-time demo provides services like: voice-dialing (dialing a person by name or a connected digit string), information service (accessing headline news, weather reports, sports and stock quotations), personal message service (retrieving email, voice mail and fax) and voice control of a DVD-player (selecting topics, controlling volume and video playback speeds).

1. Introduction

Currently, automatic speech recognition is being deployed in many application areas such as voice dictation, key-word based automatic telephone operator assistance, automatic voice dialing and call routing, etc. However the applications, despite their popularity, are still rather limited and in many cases head-mounted, close-talking microphones or telephone handsets are required. To free users from these tethering constraints and to facilitate truly hands-free human machine communication, technologies need to be advanced. Ongoing research has been done in various organizations [7][8][11]. In this paper we give a progress report on our infrastructure development, technology advances, and system integration and evaluation at Bell Labs, Lucent Technologies. First, we will give a review of our database collection effort. A series of simultaneous 30-channel recordings from 57 subjects has been conducted in a Ford Explorer SUV under real driving conditions. The database is used for developing and evaluating many of the critical technologies for hands-free VUI applications. We next present our research advancement along various technology frontons and its corresponding results. Finally, we discuss the issues relevant to LINUX PC implementation.

2. A Multi-Channel Car Database

Before we can engage in in-depth research work on hands-free VUI technologies, collecting a speech database which encompasses the rich acoustic varieties in such an environment is a prerequisite. A speech database collected in a car under real driving conditions, with multi-channel microphones, is a good starting point. Useful applications, e.g., hands-free voice control of various devices such as cellular phones, audio/video equipments, windows, wipers, etc., and hands-free access to information such as email, voice-mail and fax messages through wireless links make such a database highly desirable. Many unsolved problems such as robust ASR in the adverse acoustic environment of a moving car and adaptive beam-forming using multichannel input justify the effort to collect such a speech database.

Also, a voice-controlled, human-machine interface is considerably safer for a driver to operate than a keyboard coupled with a visual display. A database has thus been collected for research work in acoustic signal processing operations such as beamforming, noise suppression, and robust front-end feature selection as well as for ASR related tasks such as on-line noise tracking and modeling, and speaker and environment adaptation. Technologies so developed will find immediate relevance to in-vehicle speech applications.

Recording Channel Assignment

Thirty channels have been simultaneously recorded to Hi-8 video tape via a TEAC digital recorder sampling at 24 kHz with 16 bit precision. A list of these channels is given in Table 1. The linear microphone array, consisting of 16 equi-spaced, hyper-cardioid microphone elements and mounted in lieu of the sunvisor on the passenger side. For comparison purposes, an omnidirectional microphone was installed next to the linear array. Four additional microphones (two omni and two hyper-cardioid) were mounted on top of the dashboard. Two close-talking boom microphones were worn by the subject, and those recordings were used as high signal-to-noise ratio (SNR) reference signals. Since all channels were recorded in a time-aligned fashion, the speech endpoints found in the close-talking microphone channels were conveniently used to precisely segment all the other data channels as well. The close-talking signals additionally served as an upper limit baseline measure of ASR performance.

The left and right stereo channels of the car radio were recorded as well, for stereo-echo cancellation study. The velocity and position of the car were recorded, as reported through the ASCII output of a roof mounted GPS receiver. An x-y-z 3-axis accelerometer sensor was cemented to the windshield to record mechanical movements (up to 12 kHz) of the car in order to register any chassis vibration from e.g., uneven road conditions. This information can be used to distinguish acoustic noise from mechanical movement of the microphone's membrane. Finally, a separate channel recorded laptop ASCII data about the road type, weather condition, radio state, etc. as well as the text prompts that were displayed on the laptop screen for the subjects. As can be seen in Figure 1, the SNR's of simultaneous recordings from the close-talking, single array element, and omnidirectional microphones are significantly different. Due to the directivity of the hyper-cardioid microphones, noise from the windshield is significantly reduced and the recorded signal is much quieter than that from the omnidirectional, but still noisier than its close-talking counterpart.
Table 1: Recording Channel assignment

<table>
<thead>
<tr>
<th>Channel no</th>
<th>Device</th>
</tr>
</thead>
<tbody>
<tr>
<td>1 - 16</td>
<td>line array, hyper-cardioid</td>
</tr>
<tr>
<td>17</td>
<td>omni-directional mike</td>
</tr>
<tr>
<td>18 - 20</td>
<td>accelerometers x-y-z axis</td>
</tr>
<tr>
<td>21</td>
<td>boom mike (headset) B&amp;K</td>
</tr>
<tr>
<td>22</td>
<td>boom microphone (headset) Sennheiser</td>
</tr>
<tr>
<td>23 - 24</td>
<td>dashboard cardioid</td>
</tr>
<tr>
<td>25 - 26</td>
<td>dashboard omni</td>
</tr>
<tr>
<td>27 - 28</td>
<td>radio left and right ch's</td>
</tr>
<tr>
<td>31</td>
<td>ASCII from laptop PC</td>
</tr>
<tr>
<td>32</td>
<td>GPS</td>
</tr>
</tbody>
</table>

The block LS (BLS) echo canceler algorithm:
1. Block \( N \) samples of source signal samples, \( x(t) \), and observed microphone input samples, \( z(t) \).
2. Weight \( z(t) \) and \( z(t) \) with an appropriate tapering window.
3. Compute the autocorrelation matrix and cross-correlation vector of the current block.
4. Update \( R_{zz} \) and \( R_{xz} \), with auto and cross-correlation of the current block using a leaky integrator.
5. Find the adaptive echo canceler coefficients by solving the normal equations via efficient Levinson recursion, \( \mathbf{h} = R_{zz}^{-1} R_{xz} \).
6. Compute the estimated echo, \( y(t) \), and subtract it from the microphone input sample, \( z(t) \). Continue at 1 with the next block.

The computational complexities of the BLS AEC is actually less than a corresponding LMS-based algorithm since the autocorrelation, crosscorrelation estimation and Levinson recursion only need to be done once on a per block, rather than per sample basis.

**AEC Experimental Results**
To illustrate the high performance of the new echo canceler and near-end speech detector, both the microphone input and the echo cancelled output around a near-end speech segment are displayed in Figure 2 in both narrowband spectrograms and waveforms. Before BLS cancellation, the far-end echo, due to a long echo response, smears the corresponding spectrogram. When this echo mixes with the near-end speech, near-end speech detection becomes very difficult. After cancellation, while almost all far-end echoes disappear, the near-end speech remains intact and becomes distinctively prominent against the low background noise level. The cancelled output contains almost no audible far-end speech and the near-end phrase “sports results” becomes audibly crisp and clear, including the weak fricatives at both ends.

**4. Intelligent Microphone Arrangement**
As shown in Figure 1, a hyper-cardioid microphone, due to its directivity pattern, can improve the SNR over an omni-microphone. To further improve the directivity pattern, we can use the delay-and-sum beam-forming technique shown in [3] to adaptively adjust the delay between each microphone element in the array.
such that speech signals from all channels are synchronized for in phase superposition, while the noise sources, being located at various directions from the speech source, are out of phase. When all channels are added together, the speech signals are enhanced and the noise signals are suppressed.

In order to adjust the delay to make an in-phase, delay-and-sum beamforming, we choose one element as a reference and estimate the relative delay between the reference channel and all other array elements. Several time delay estimation techniques have been proposed, such as the generalized correlation method, [4] or the eigen analysis based methods [1]. Issues which deserve special attention in estimating the time delays are the sampling rate of each channel and detecting any malfunctioning channel in the array. Since the array elements are spaced closely and fractional sample delay will be quantized to its nearest integer sample, the resolution of the delay-and-sum beamforming is reduced. In order to solve it, we can increase the sampling rate. Any malfunctioning channel needs to be detected, otherwise the time delay estimate is misleading and can deteriorate the beamforming performance.

Using the multi-channel signals sampled at 24 KHz with delay-and-sum beamforming, we managed to improve both SNR and speech recognition performance [5]. A typical example of waveforms and corresponding spectrograms are shown in Figure 3 before and after the delay-and-sum beamforming. Appreciable noise suppression is observed on the beam-formed output both in the time and frequency domains. Three SNR related measures: segmental SNR, peak-to-background SNR and background noise level are used to calibrate the SNR enhancement performance of the delay-and-sum beamformer over the whole database. As shown in Figure 4, the most significant improvement is from single channel to two channel case, the improve-
put as soon as we are confident that a user has made a speech utterance, such buffering gives an unwanted, “sluggish” feel to the system since, no matter how quickly we are able to stop writing prompt audio to the output port, the previously buffered audio must drain from the buffer before the prompt actually stops.

Fortunately, Linux audio I/O using the Open Sound System (OSS) [6] enables a unique solution that allows us to meet the contradictory requirements of being immune to small time-sharing latencies and providing nearly immediate system prompt muting.

OSS allows programs to map the soundcard's audio buffers directly into user memory. In our application, 64KB of audio input and output buffers (2 seconds worth of 8kHz, 16 bit stereo audio) are mapped into the Audio Server program's address space. Once started, audio I/O runs continuously to and from these buffers without further program intervention. The audio transfer pointers are circular, continuing at the beginning of the buffer after hitting the end.

The Audio Server blocks (waits) in a SELECT call until the next fragment (typ. 4KB) of the buffer has been transferred. For output, typically a full 2 seconds of audio is waiting in the buffer to be played. When the select returns (indicating that at least one fragment has been played), we check how much has actually been played (using a GETOPTR IOCTL), top off the buffer and block again. In this way we can tolerate up to 2 seconds of scheduling latency before an underflow condition occurs.

For input, the situation is reversed, and typically the input buffer remains nearly empty. We block waiting for a fragment of input to become available, check to see how much has actually arrived (GETIPTR IOCTL), give it to the echo canceller, and block waiting for more input. In this way we can tolerate up to 2 seconds of service latency before an overlow occurs.

The advantage we get by using memory mapped I/O occurs when the prompt must be muted after barge-in. In this case we ask the system (GETOPTR IOCTL) precisely where the soundcard's output DMA pointer is and then write zeros into the buffer memory following the pointer. This squelches output within a fraction of a second and gives the system a “snappy” barge-in response.

For further refinement, instead of simply zeroing the prompt buffer to mute it, we read the sample values following the output pointer and taper them to zero over a 100ms interval. This gives the pleasing sense that the system is giving up on its utterance by trailing off, much as a human does when interrupted.

A second benefit of the memory mapped, continuously running audio I/O approach occurs when extreme system latencies occasionally do cause buffer over or underruns. In the output buffer underrun case, the circular DMA pointer will play a previous (2 second old) segment of audio. In the input overflow case, new input will overwrite older samples, causing the new audio to appear twice in the input to downstream modules. However despite these discontinuities, the critical relationship between the input and output pointers remains intact. When the Audio Server does catch up and recover, the estimated impulse response has precisely the same flat delay as before. This, combined with the leaky integrator in the Block Least Squares echo canceller, allows echo cancellation performance to remain essentially unaffected even after extreme latencies.

### 6. REFERENCES