

ARTICLE ONE

END POINT ANALYSIS FOR DETECTING PITCH BOUNDARIES OF SPOKEN INDIAN DEVNAGARI LANGUAGE COMMANDS USING AUTOCORRELATION TECHNIQUE FOR CONTROLLING ROBOT ACTIVITIES

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Abstract:

Pitch boundaries detection of the speech is an important task due to the presence of background noise. By detecting pitch for extracting linear predictive codes, allows the generation of high quality speech recognition system. Primarily start and end points of speech is detected and thereafter pitch boundaries are recognized. This paper emphasized on accurate end point analysis for detection of pitch boundaries for spoken Indian Devnagari language commands by autocorrelation technique in the speech recognition system for speaker controlled various activities of Robot.

Keywords: Pitch Boundaries, Autocorrelation, and Robot

I. Introduction:

Generating speech a source that is passed through a filter with the vocal tract response to produce speech [1][2]. The simplest implementation of this is known as the Linear Predictive Coding (LPC) synthesizer. At every frame, the voiced speech is analyzed to compute the pitch value, filter coefficients, the energy of the excitation and a voicing decision. In order to generate high quality speech recognition system with synthesis based on LPC, a method for detecting the pitch boundaries is important, since detecting start and end point is very critical. This paper discusses the correct detection of start and end point of the spoken Indian Devnagari Language Commands in the presence of background noise and thereby detects the accurate pitch boundaries by autocorrelation technique in the speech recognition system for speaker controlled various Robot activities [3][4].

II. Concept:

A Robot response to the spoken commands can make the programming easier. Voice controlled robots are helpful in various applications since nowadays robot becomes more mobile. The efficient working of Robot is highly dependent on the speech commands in the presence of background noise that are properly recognized by it. In order to control the various activities of robot, highly accurate speech recognition system is employed needs the accurate processing of pitch in the speech commands. Fig 1 shows the concept of speech command recognition system for the speaker controlled robot system.

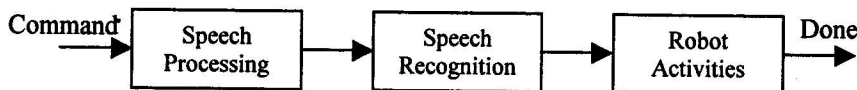


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III. Pitch detection:

The pitch period is estimated by autocorrelation technique by detecting the peak amplitude in the function. The second largest peak relative to the true delay of the correlation is used to determine the pitch period. The peak in the autocorrelation function tends to fall off linearly starting from the first peak [5][6].

The spoken data for Indian Devnagari Language Numericals are recorded at 8KHz sampling frequency with 8 bits representing each sample. Figure 1 shows block-processing model for detecting the pitch boundaries.

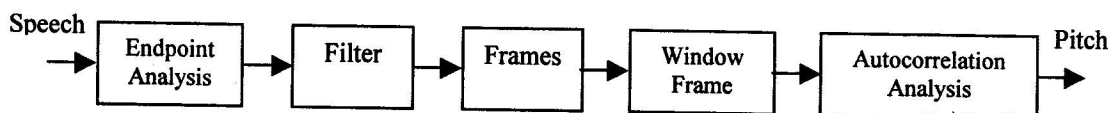


Fig 1. Block Processing Model for Detecting Pitch Boundaries

The data is processed in frame of 200 samples and a vector of pitch is measured. The vector is obtained by pre-emphasizing speech data to flatten it using first order digital filter with transfer function $H(z) = 1 - 0.97z^{-1}$. The signal is processed in the steps of 100 samples to provide smoothing between vectors of pitch. For speech analysis, the hamming window and autocorrelation technique is with different order is used. In the start & End point analysis of speech, each window samples are classified as voiced speech, unvoiced speech or silence, based entirely on measurements made on the signal during the prescribed interval [7]-[11].

IV. Result:

The following results are obtained with the samples of spoken Indian Devnagari Language Command "ek". The autocorrelation system order selected is equal to 10, 11 for analyzing the better performance. Fig 2, 3 shows pitch boundaries detected using the start & end point analysis and autocorrelation technique for the spoken Indian Devnagari Language Command "ek". Table 1 shows the start and end frames of spoken command "ek".

Spoken Command = ek	Starting Frame	Ending Frame
Order=10	42	80
Order=11	38	78

Table 1. Showing the Start & End frames of spoken word "ek"

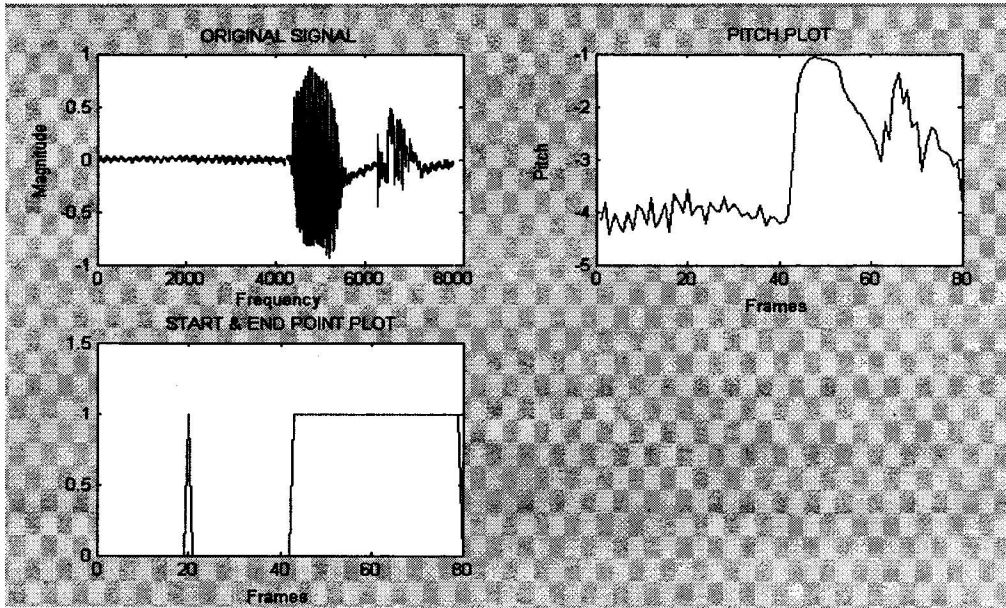


Fig 2. Pitch boundaries for the spoken Indian Devnagari Language Command "ek" with system order 10.

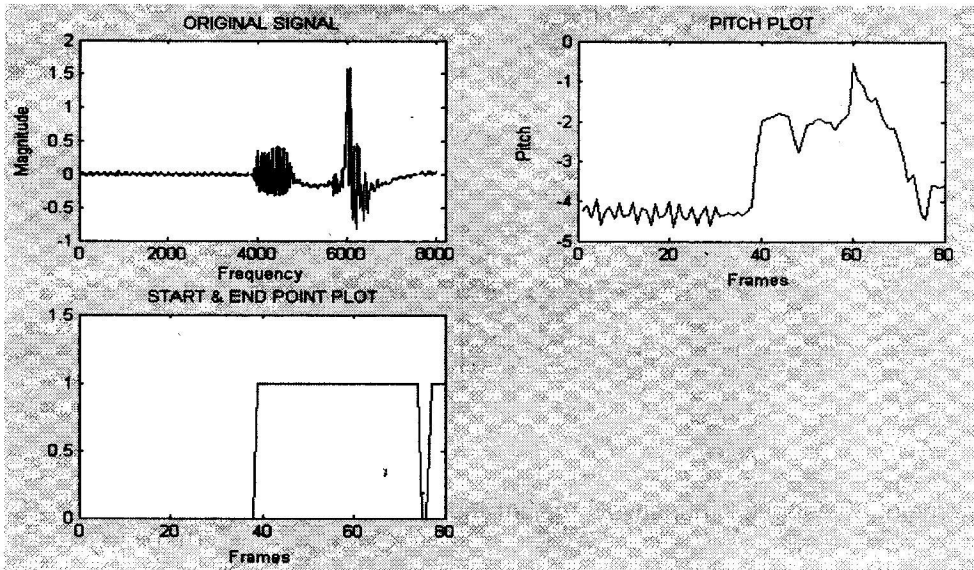


Fig 3. Pitch boundaries for the spoken Indian Devnagari Language Command "ek" with system order 11.

V. Conclusions:

Autocorrelation method with start and end point analysis has an advantage of less computation since only a window length is used as signal component. Even though the speech waveform is not always periodic, the pitch boundaries are detected correctly to build an efficient speech recognition system so that the commands to the robot are properly executed for carrying various activities.

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