Acoustic Equalization for Headphones Using a Fixed Feed-Forward Filter

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Introduction

Novel application: Active acoustic equalization (AAE) for headphones

- Equalization of ambient sound with fixed but arbitrary target transfer function H(s) for, e.g., reconfigurable hearing protection
- Evaluated using a parametric equalizer as an example
- Utilize principles of active noise cancellation

Goal: Design fixed feed-forward FIR filter $\hat{W}(z)$ based on minimum mean square error (MMSE) criterion to approximate H(s) with overall discretetime transfer function $\hat{H}(z) = P(z) - \hat{W}(z)S(z)$



The discrete-time transfer functions P(z) and S(z) comprise the acoustic transfer functions $P_{\mathrm{a}}(s)$ and $S_{\mathrm{a}}(s)$, the ADCs and DAC, as well as the microphones and the loudspeaker

Robust Approach with Respect to Variations in Acoustic Paths

- Variations of P(z) and S(z) due to
- Physiology of ear
- Direction of arrival of ambient sound
- Headphone fitting
- Filter-design based on J previous measurements of P(z) and S(z)

$$\hat{\boldsymbol{h}}_j = \boldsymbol{p}_j - \boldsymbol{S}_j \hat{\boldsymbol{w}} \stackrel{!}{=} \boldsymbol{h}, \quad j = 0, 1, \dots, J$$

• Averaged cost function $\mathcal{C}_{\mathrm{avg}}$ and causal Wiener solution

$$\begin{split} \min_{\boldsymbol{\hat{w}}} \mathcal{C}_{\text{avg}} &= \sum_{j=0}^{J-1} \left\| \hat{\boldsymbol{X}} \left(\hat{\boldsymbol{h}}_{j} - \boldsymbol{h} \right) \right\|^{2} \\ \hat{\boldsymbol{w}}_{\text{avg}} &= \left(\sum_{j=0}^{J-1} \boldsymbol{S}_{j}^{\text{T}} \boldsymbol{\Psi}_{\hat{x}\hat{x}} \boldsymbol{S}_{j} \right)^{-1} \sum_{j=0}^{J-1} \boldsymbol{S}_{j}^{\text{T}} \boldsymbol{\Psi}_{\hat{x}\hat{x}} \left(\boldsymbol{p}_{j} - \boldsymbol{h} \right) \end{split}$$

- Measured transfer functions for J = 12 subjects in studio box using Bose QC20 acoustic front-end and dSPACE real-time system
- Performance shown for different knowledge of actual acoustic paths
- Individualization of P(z) and S(z) can further improve accuracy

System Overview

• Time-domain formulation

$$\hat{m{h}} = m{p} - m{S}\hat{m{w}} \stackrel{!}{=} m{h}$$

with convolution matrix





• Cost function C_{wb} and causal Wiener solution [1,2]

$$\min_{\hat{\boldsymbol{w}}} C_{\text{wb}} = \left\| \hat{\boldsymbol{h}} - \boldsymbol{h} \right\|^2 \qquad \qquad \boldsymbol{h} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{S}^{\text{T}} \boldsymbol{S})^{-1} \boldsymbol{S}^{\text{T}} (\boldsymbol{n} - \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{S}^{\text{T}} \boldsymbol{S})^{-1} \boldsymbol{S}^{\text{T}} (\boldsymbol{n} - \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{S}^{\text{T}} \boldsymbol{S})^{-1} \boldsymbol{S}^{\text{T}} (\boldsymbol{n} - \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{S}^{\text{T}} \boldsymbol{S})^{-1} \boldsymbol{S}^{\text{T}} (\boldsymbol{n} - \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{S}^{\text{T}} \boldsymbol{S})^{-1} \boldsymbol{S}^{\text{T}} (\boldsymbol{n} - \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{S}^{\text{T}} \boldsymbol{S})^{-1} \boldsymbol{S}^{\text{T}} (\boldsymbol{n} - \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{S}^{\text{T}} \boldsymbol{S})^{-1} \boldsymbol{S}^{\text{T}} (\boldsymbol{n} - \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{S}^{\text{T}} \boldsymbol{S})^{-1} \boldsymbol{S}^{\text{T}} (\boldsymbol{n} - \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{S}^{\text{T}} \boldsymbol{S})^{-1} \boldsymbol{S}^{\text{T}} (\boldsymbol{n} - \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{S}^{\text{T}} \boldsymbol{S})^{-1} \boldsymbol{S}^{\text{T}} (\boldsymbol{n} - \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{w} = \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{w} = \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{w} = \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{w} = \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{w} = \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{w} = \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{w} = \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = (\boldsymbol{w} = \boldsymbol{h}) \qquad \qquad \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = \hat{\boldsymbol{w}} = \hat{\boldsymbol{w}} = \\ \hat{\boldsymbol{w}} = \hat{$$

$$\hat{\boldsymbol{w}}_{ ext{wb}} = \left(\boldsymbol{S}^{ ext{T}} \boldsymbol{S}
ight)^{-1} \boldsymbol{S}^{ ext{T}} \left(\boldsymbol{p} - \boldsymbol{h}
ight)$$
 $\boldsymbol{w} = \left(\boldsymbol{S}^{ ext{T}} \boldsymbol{S}
ight)^{-1} \boldsymbol{S}^{ ext{T}} \left(\boldsymbol{p} - \boldsymbol{h}
ight)$
 $\boldsymbol{s} \in \boldsymbol{S}$

• Optional Bluetooth (BT) module to configure $\hat{W}(z)$ or calibrate S(z)



Institute of

- $[p_0, p_1, \dots, p_{L-1}, 0, \dots, 0]^{\mathrm{T}} \in \mathbb{R}^{2L-1}$
- $[h_0, h_1, \dots, h_{L-1}, 0, \dots, 0]^{\mathrm{T}} \in \mathbb{R}^{2L-1}$
- $[\hat{w}_0, \hat{w}_1, \dots, \hat{w}_{L-1}]^{\mathrm{T}} \in \mathbb{R}^L$
- $\mathbb{R}^{2L-1\times L}$

Generalized Solution

 $(g \ll 1)$ as

 $\hat{\boldsymbol{h}} = \left[\boldsymbol{I} - \boldsymbol{S} \left(\boldsymbol{S}^{\mathrm{T}} \boldsymbol{S}\right)^{-1} \boldsymbol{S}^{\mathrm{T}}\right] \boldsymbol{p} + g \boldsymbol{S} \left(\boldsymbol{S}^{\mathrm{T}} \boldsymbol{S}\right)^{-1} \boldsymbol{S}^{\mathrm{T}} \tilde{\boldsymbol{h}}$

• Regain control by extending cost function $\mathcal{C}_{
m wb}$ to

$$\mathcal{C}_{ ext{gen}} = \left\| \hat{oldsymbol{X}} \left(\hat{oldsymbol{h}} - oldsymbol{h}
ight)
ight\|^2$$

with convolution matrix \hat{X} based on signal [3]

$$\hat{\boldsymbol{x}} = \mathcal{Z}^{-1} \left\{ \frac{1}{|H(z)|} \right\}$$

• Causal Wiener solution for cost function $\mathcal{C}_{ ext{gen}}$ yields

 $\hat{\boldsymbol{w}}_{ ext{gen}} = \left(\boldsymbol{S}^{ ext{T}} \boldsymbol{\Psi}_{\hat{x}\hat{x}} \boldsymbol{S}
ight)^{-1} \boldsymbol{S}^{ ext{T}} \boldsymbol{\Psi}_{\hat{x}\hat{x}} \left(\boldsymbol{p} - \boldsymbol{h}
ight)$

with auto-correlation matrix $\mathbf{\Psi}_{\hat{x}\hat{x}}$

Conclusions

- ► Novel active acoustic equalization (AAE) system 2
- high target attenuation 3
- Considering variability of acoustic paths 4 has huge impact on performance
- results

References

- DSP Implementations, Wiley, Hoboken, 1996.
- Control of Noise and Vibration, CRC Press, Boca Raton, 2012.
- Audio Eng. Soc., vol. 49, no. 6, pp. 443–471, 2001.

• For target function $h = g\tilde{h}$ we lose influence of \tilde{h} for high attenuation



Generalized MMSE based solution allows frequency shaping even for



[1] Sen M. Kuo and Dennis R. Morgan, Active Noise Control Systems: Algorithms and

[2] Colin Hansen, Scott Snyder, Xiaojun Qiu, Laura Brooks, and Danielle Moreau, Active

[3] Swen Müller and Paulo Massarani, "Transfer-function measurement with sweeps," J.