

横浜市立大学大学院
ナノシステム科学専攻
物理博士 ミケレット・ルジェロ

知覚情報科学

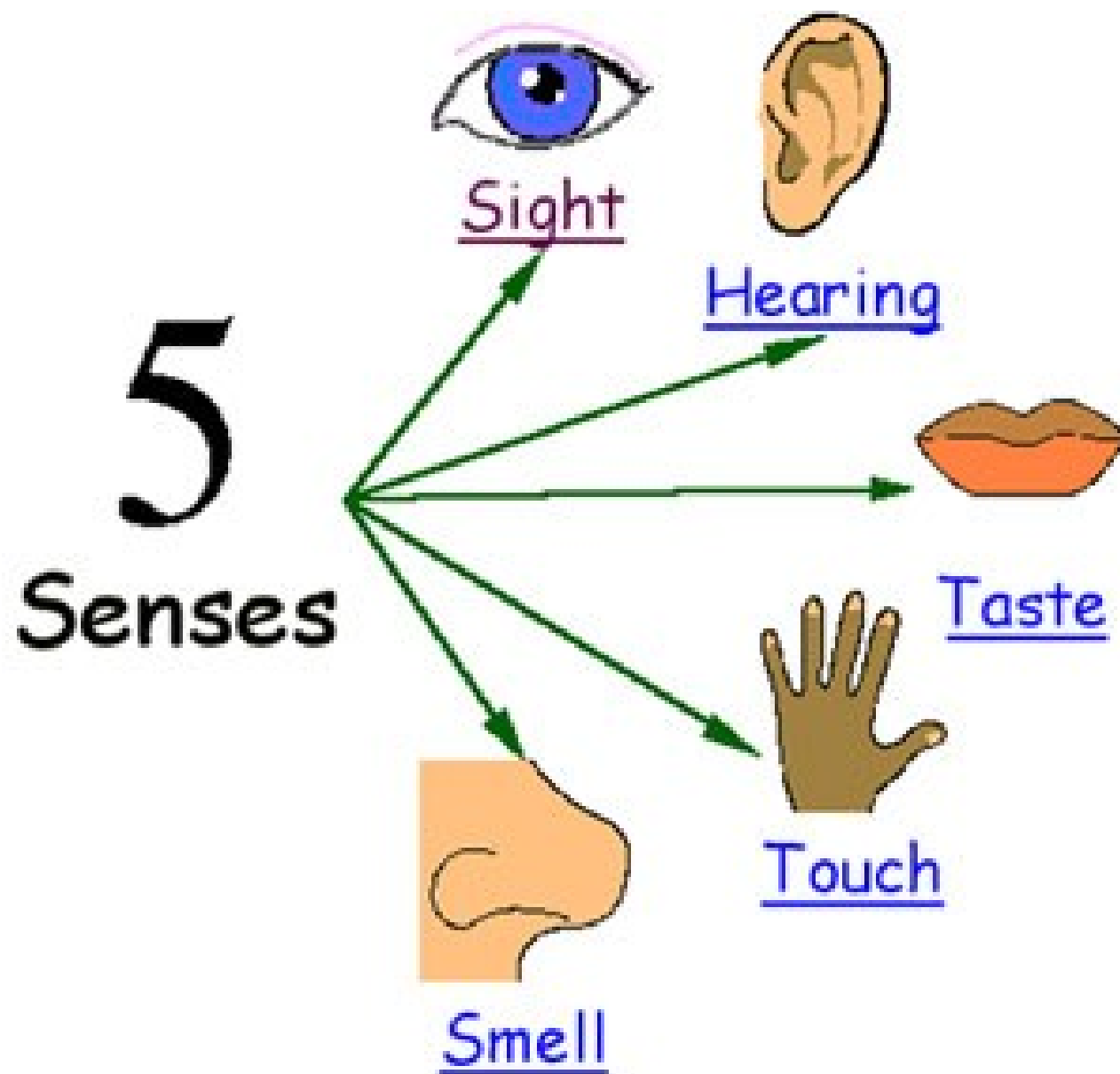
e-mail:ruggero@yokohama-cu.ac.jp

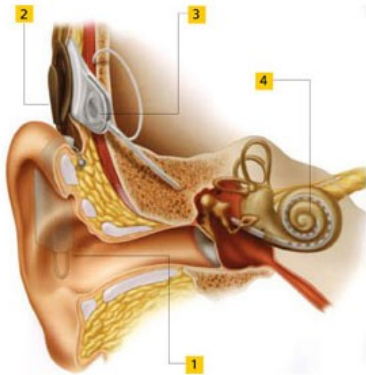
(4)

後期2010年

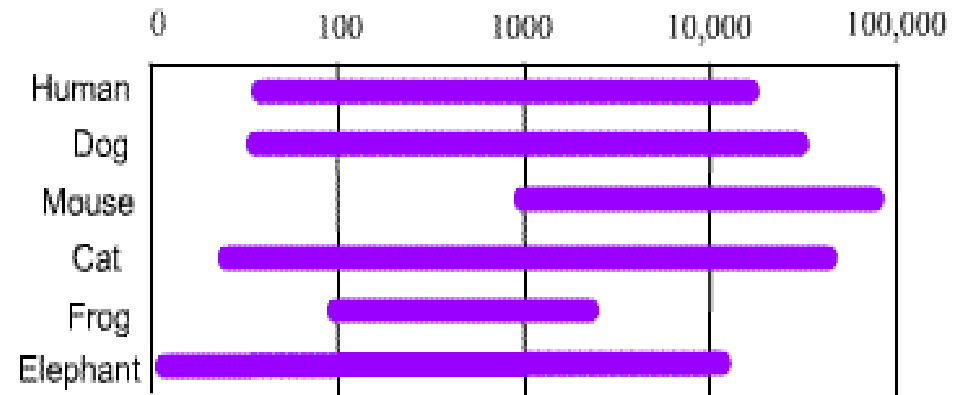
THE EAR: the HEARING sense (聴覚、ちょうかく)







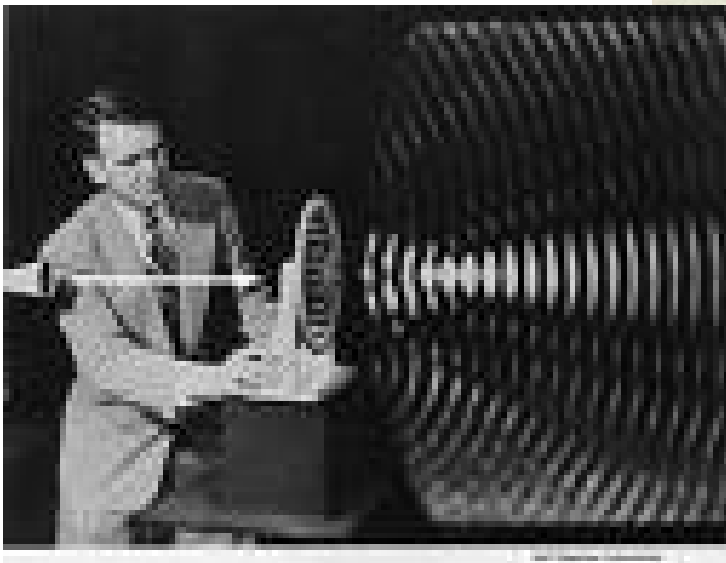
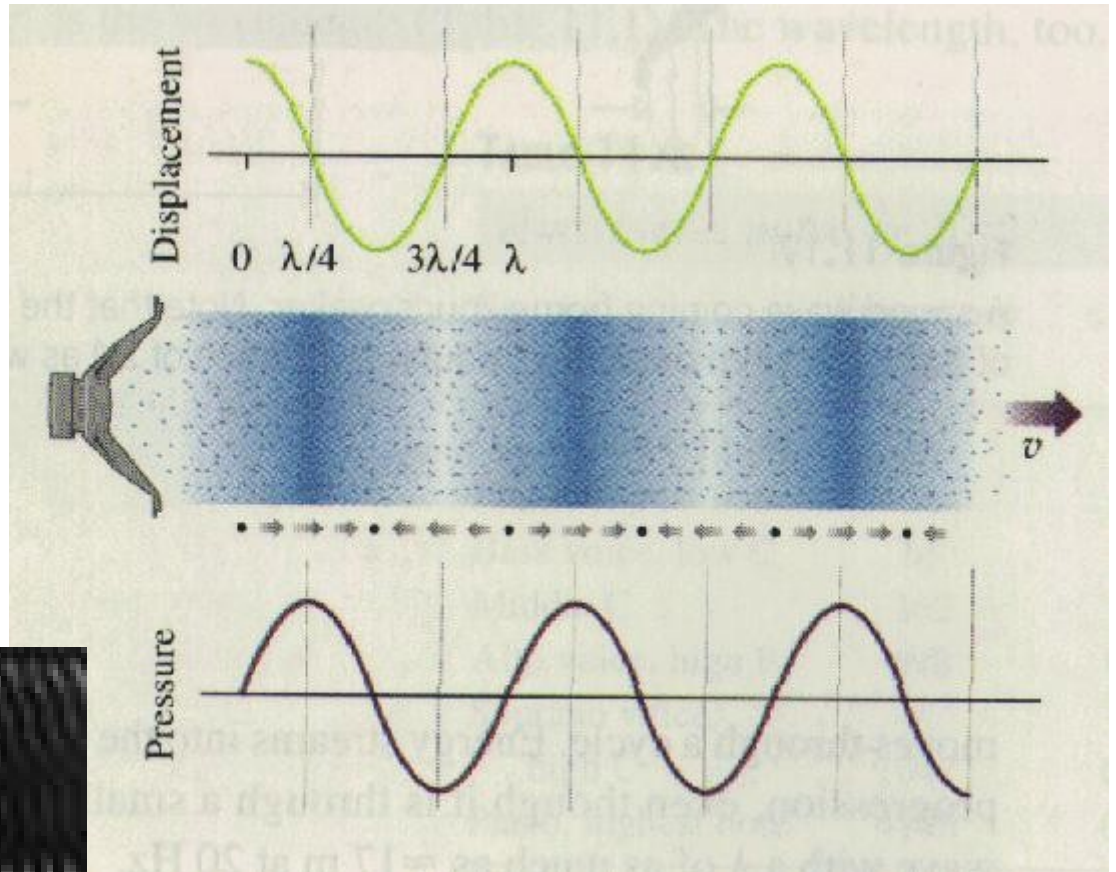
Frequency

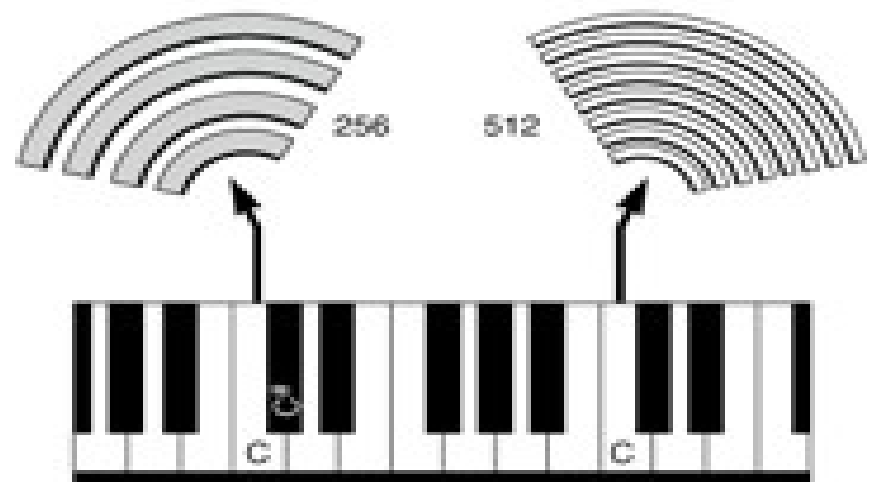
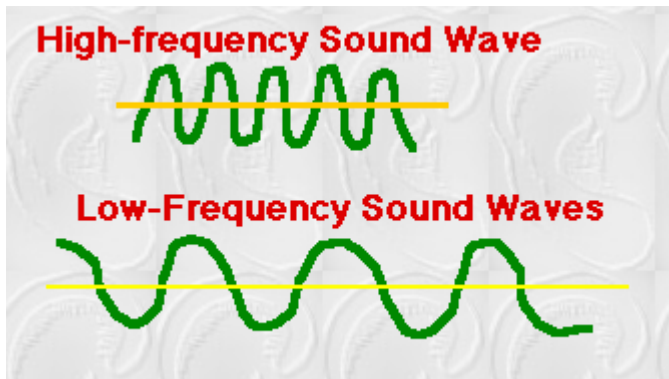
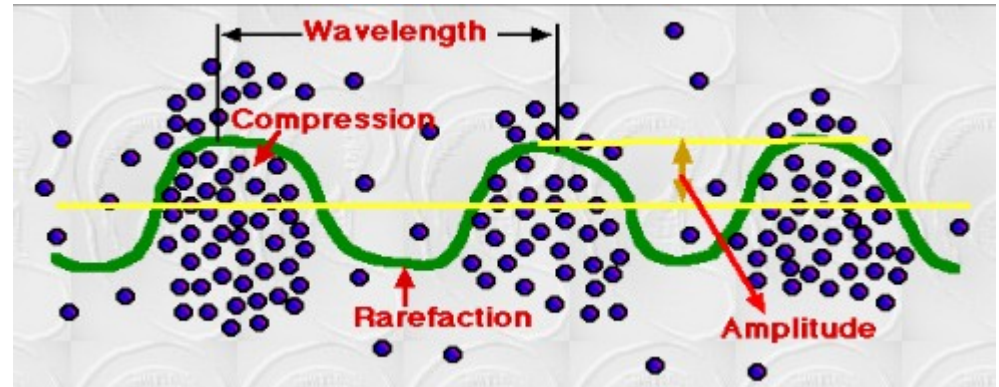
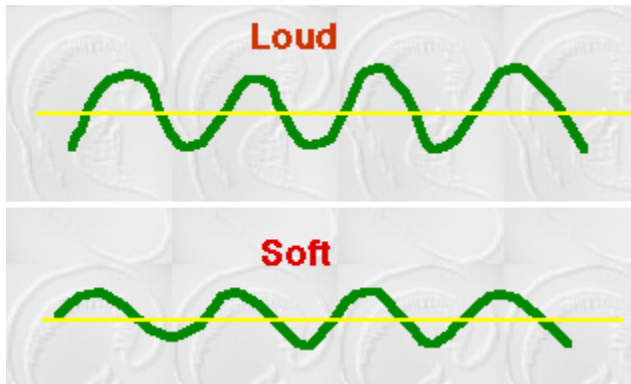


Noise	Decibels
Whisper	20
Normal Talking	50-60
Car Traffic	70
Alarm Clock	80
Lawn Mower	95
Rock Concert	100
Jackhammer	115
Jet Engine	130
Gun Shot	140

Amplitude

The sound it is a PRESSURE WAVE





The sound it is a PRESSURE WAVE

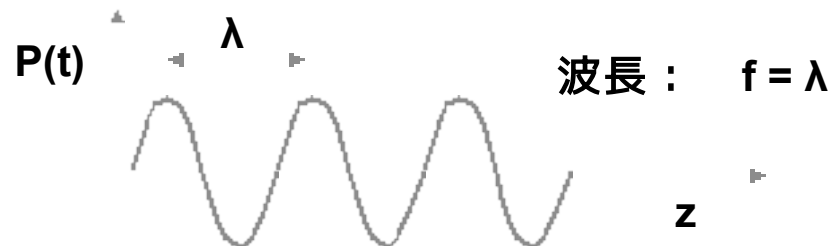
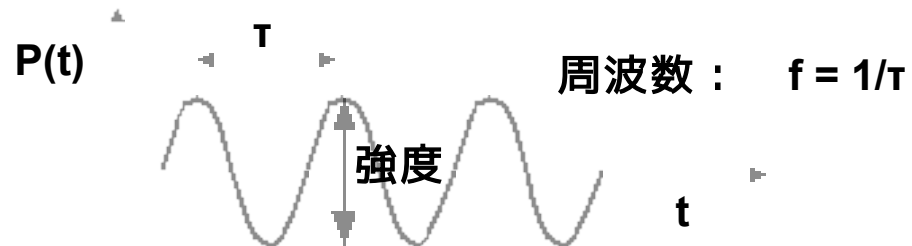
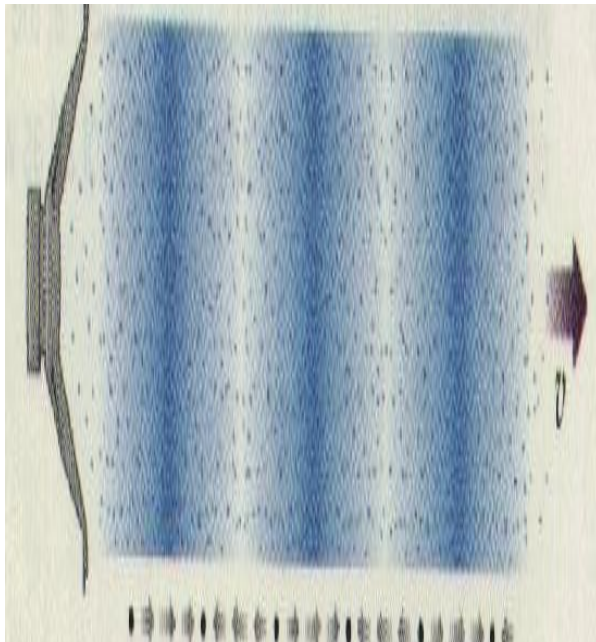
空気の圧力

f=Frequency
 λ =Wavelength

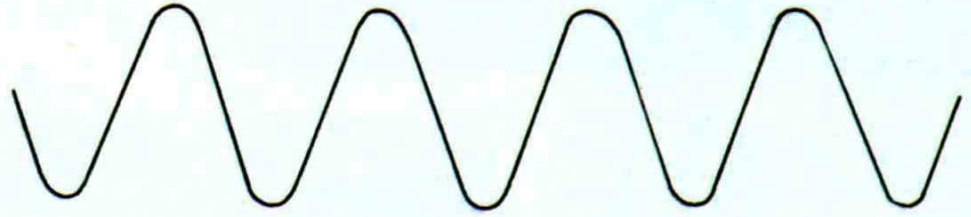
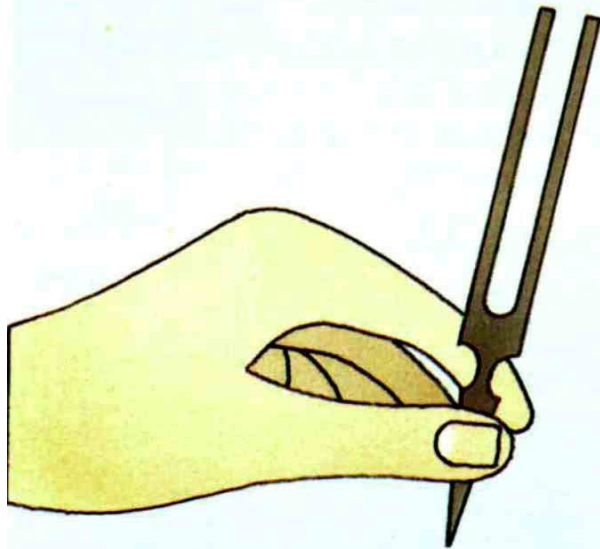
$$P(t) = P_o \sin(\omega t + kx)$$

$$\omega = 2\pi/\tau = 2\pi f$$

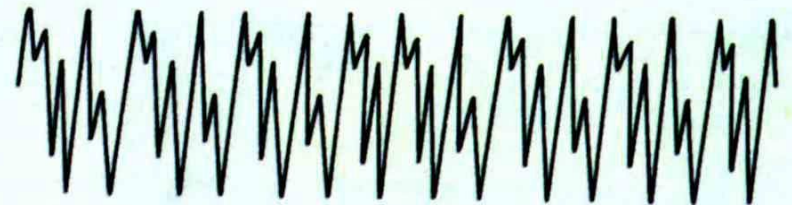
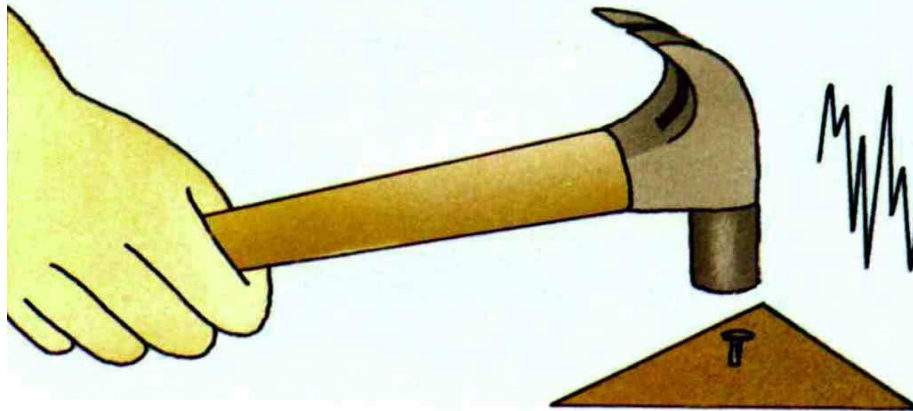
$$k = 2\pi/\lambda$$



PURE SOUND:

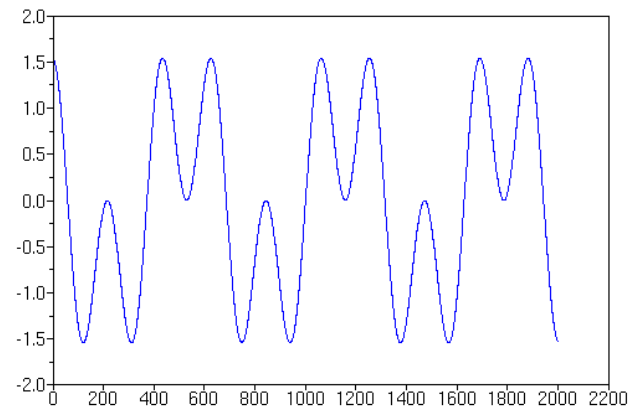
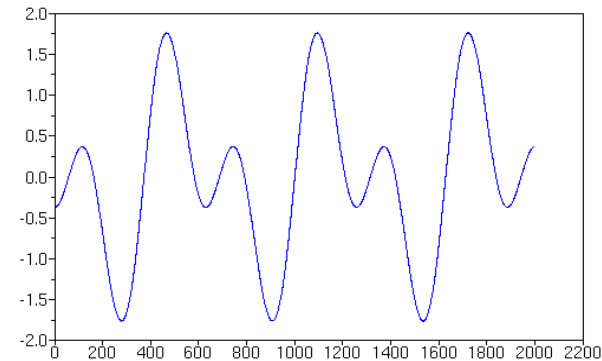
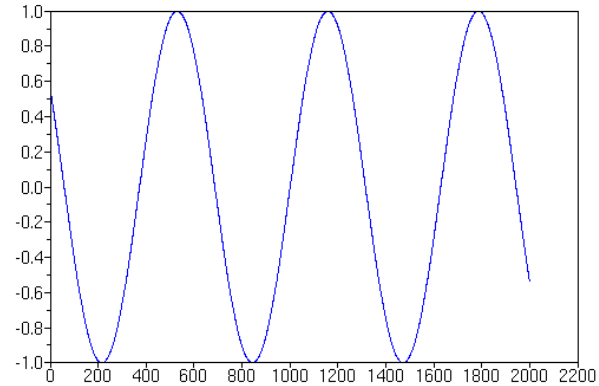


NOISE:

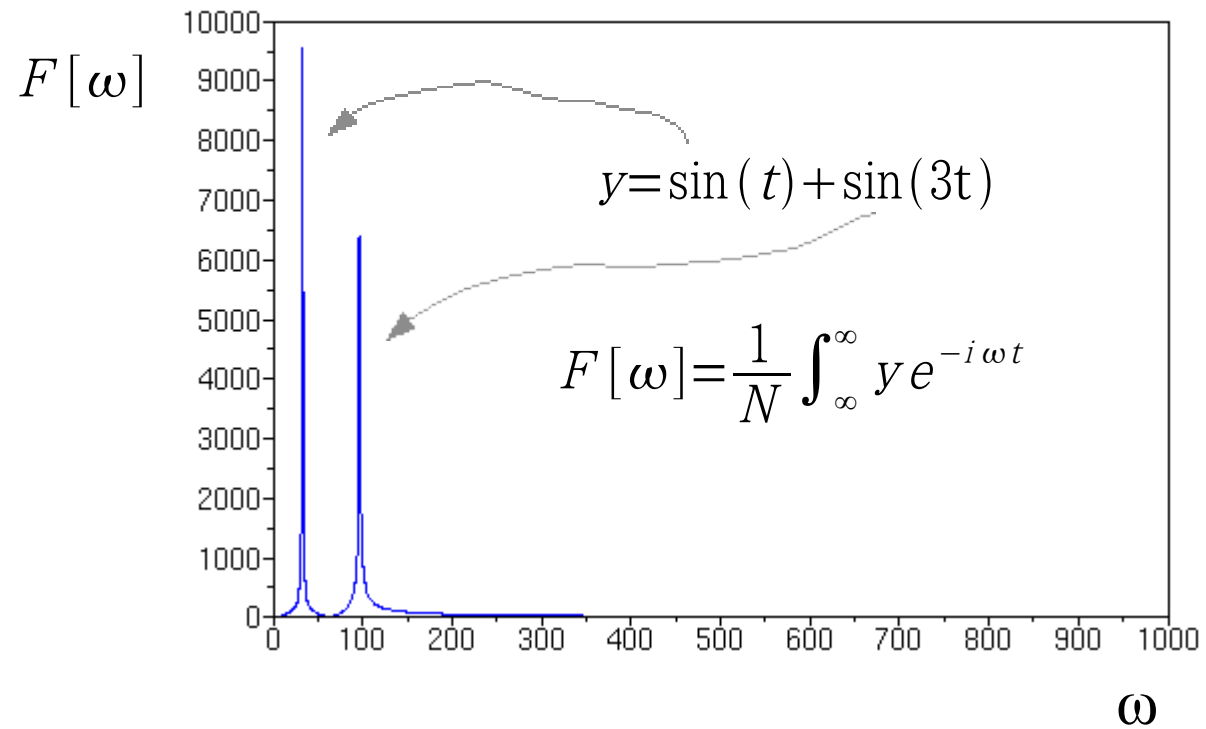


The sound SPECTRUM

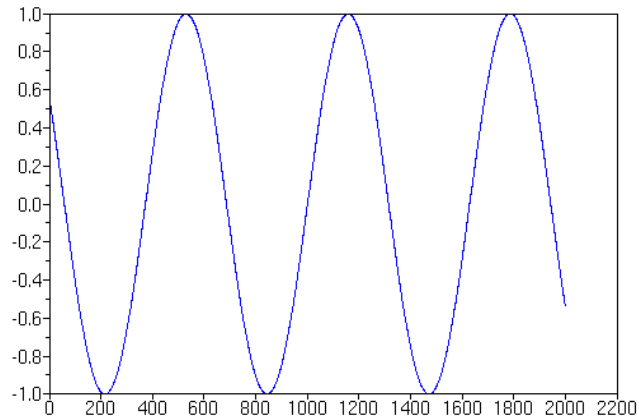
$$y = \sin(t)$$
$$y = \sin(t) + \sin(2t)$$
$$y = \sin(t) + \sin(3t)$$



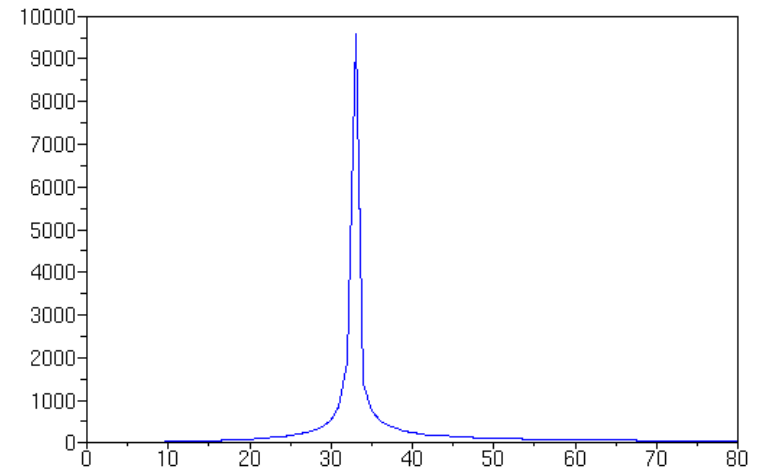
The FOURIER transformation



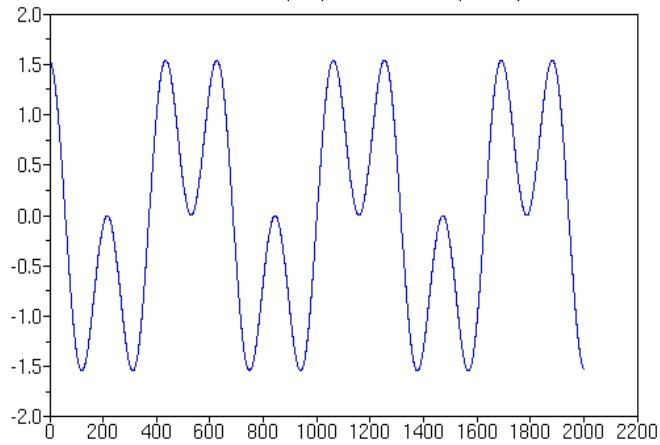
$$y = \sin(t)$$



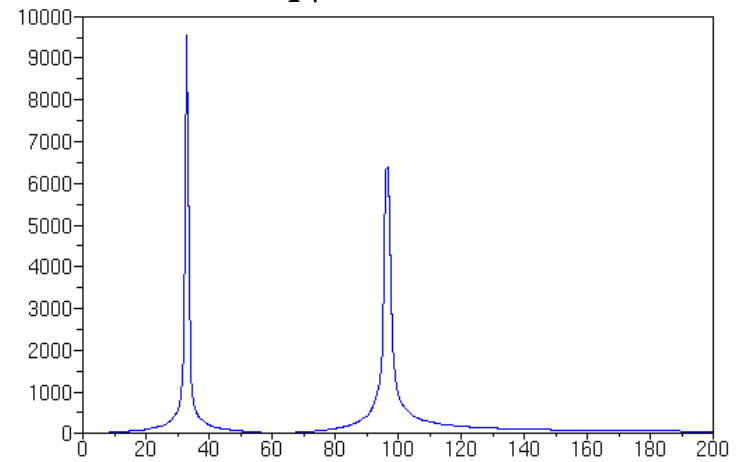
$$F[\omega] = \frac{1}{N} \int_{-\infty}^{\infty} y e^{-i\omega t} dt$$



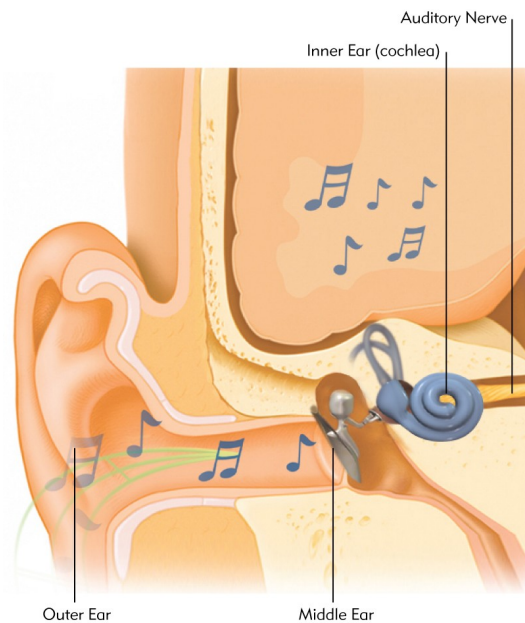
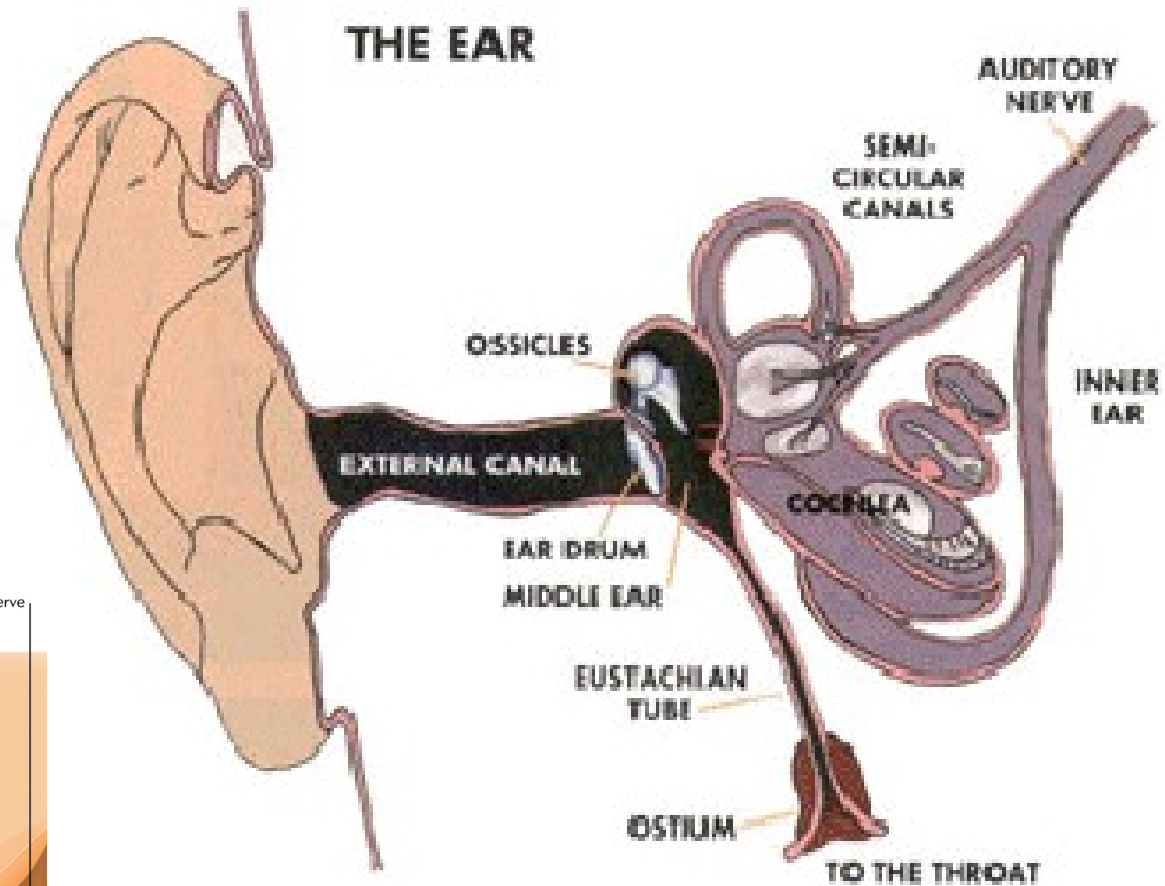
$$y = \sin(t) + \sin(3t)$$



$$F[\omega] = \frac{1}{N} \int_{-\infty}^{\infty} y e^{-i\omega t} dt$$



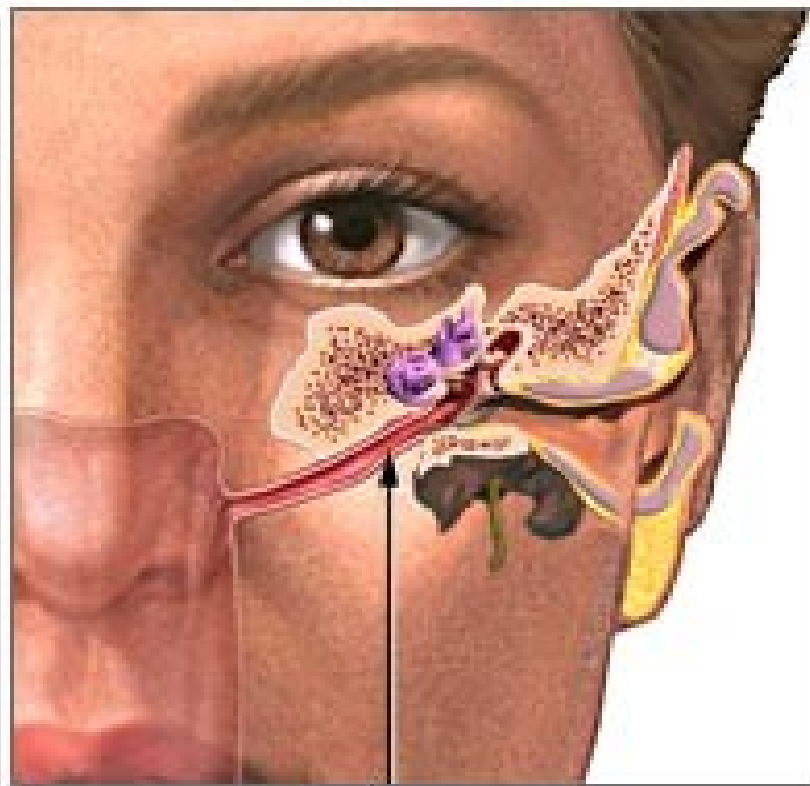
Inner Ear
Middle Ear
Outer Ear



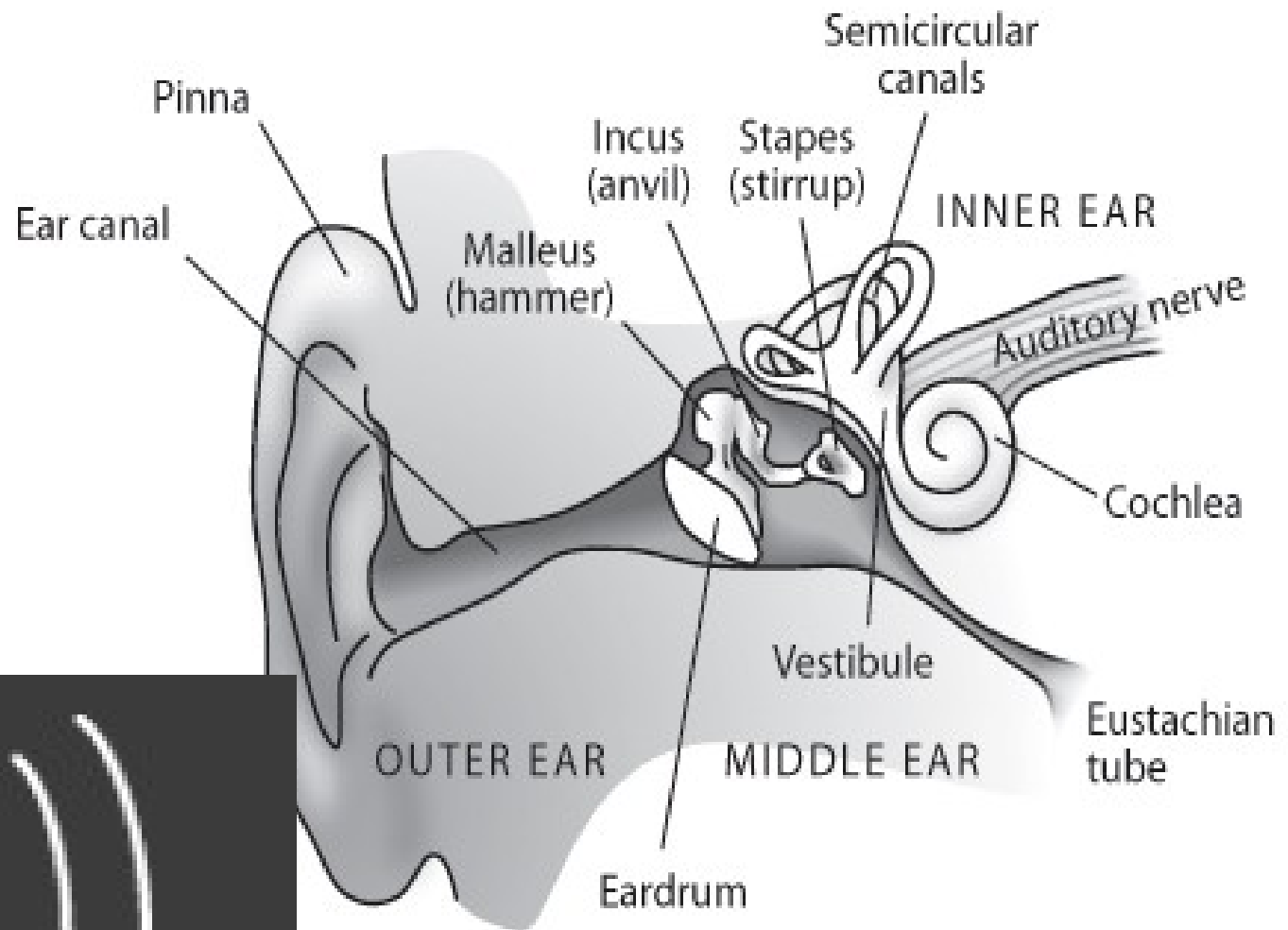
Infant



Adult



Eustachian tube

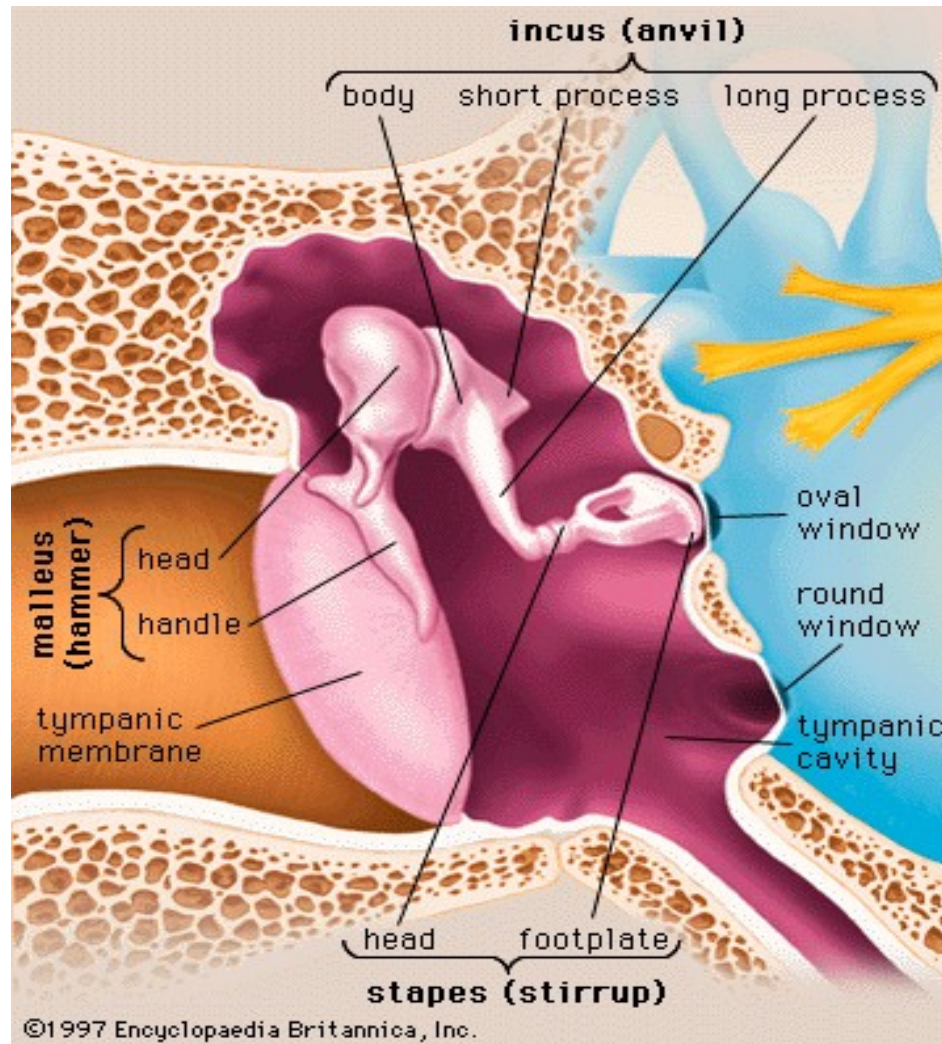


Outer Ear

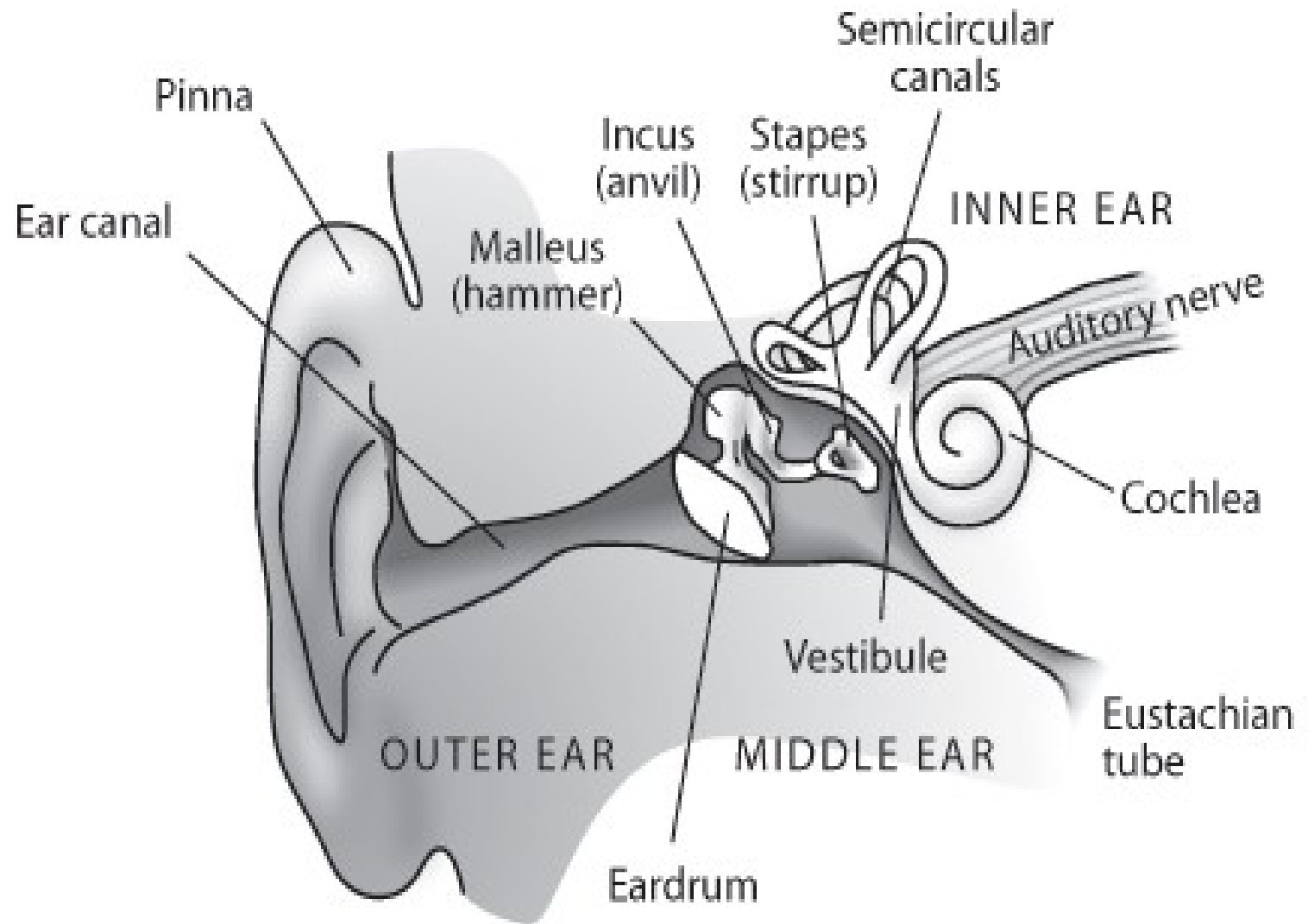
- the “Pinna” is not frequency flat.
Different frequencies are detected at different intensities.

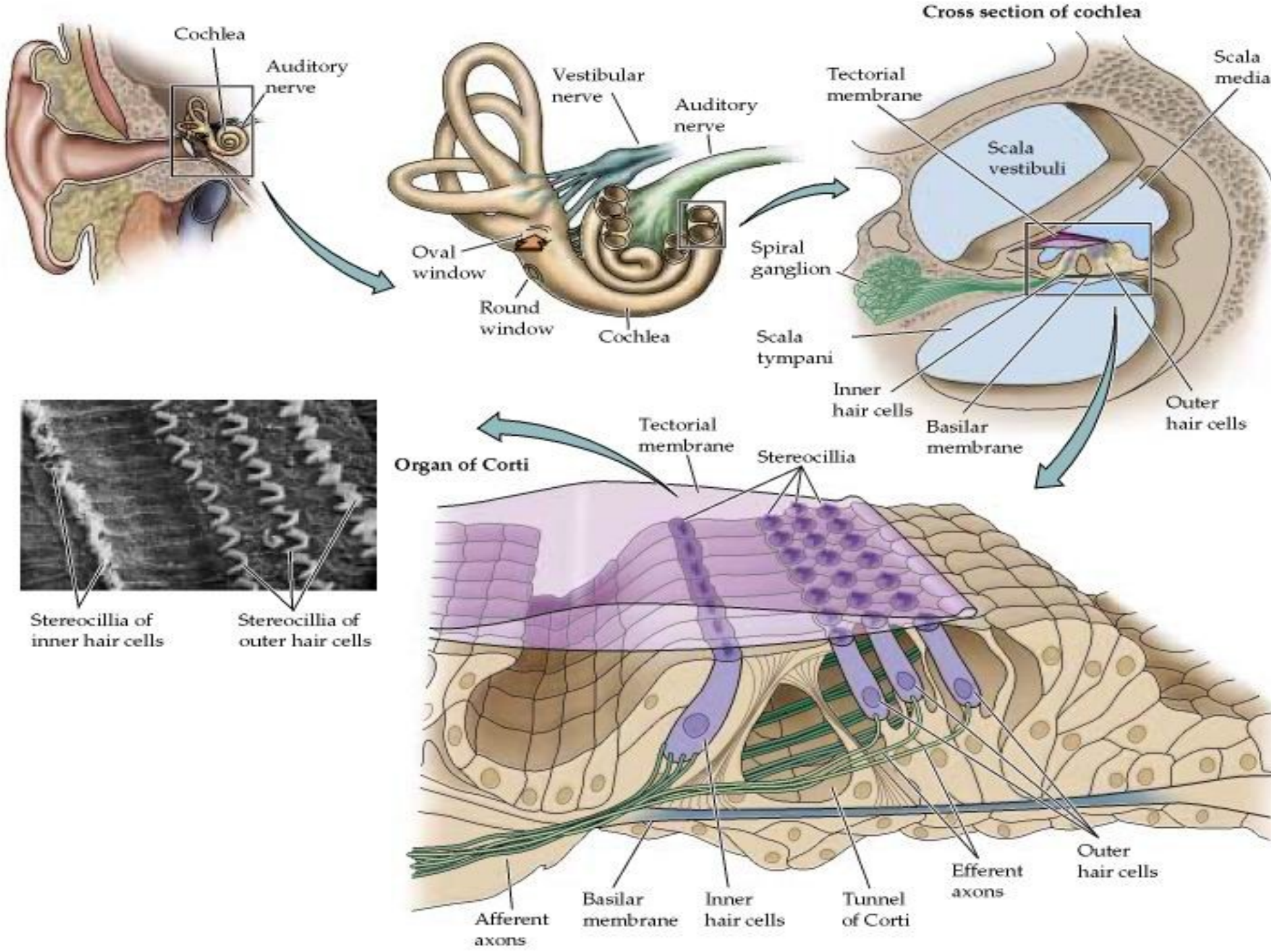


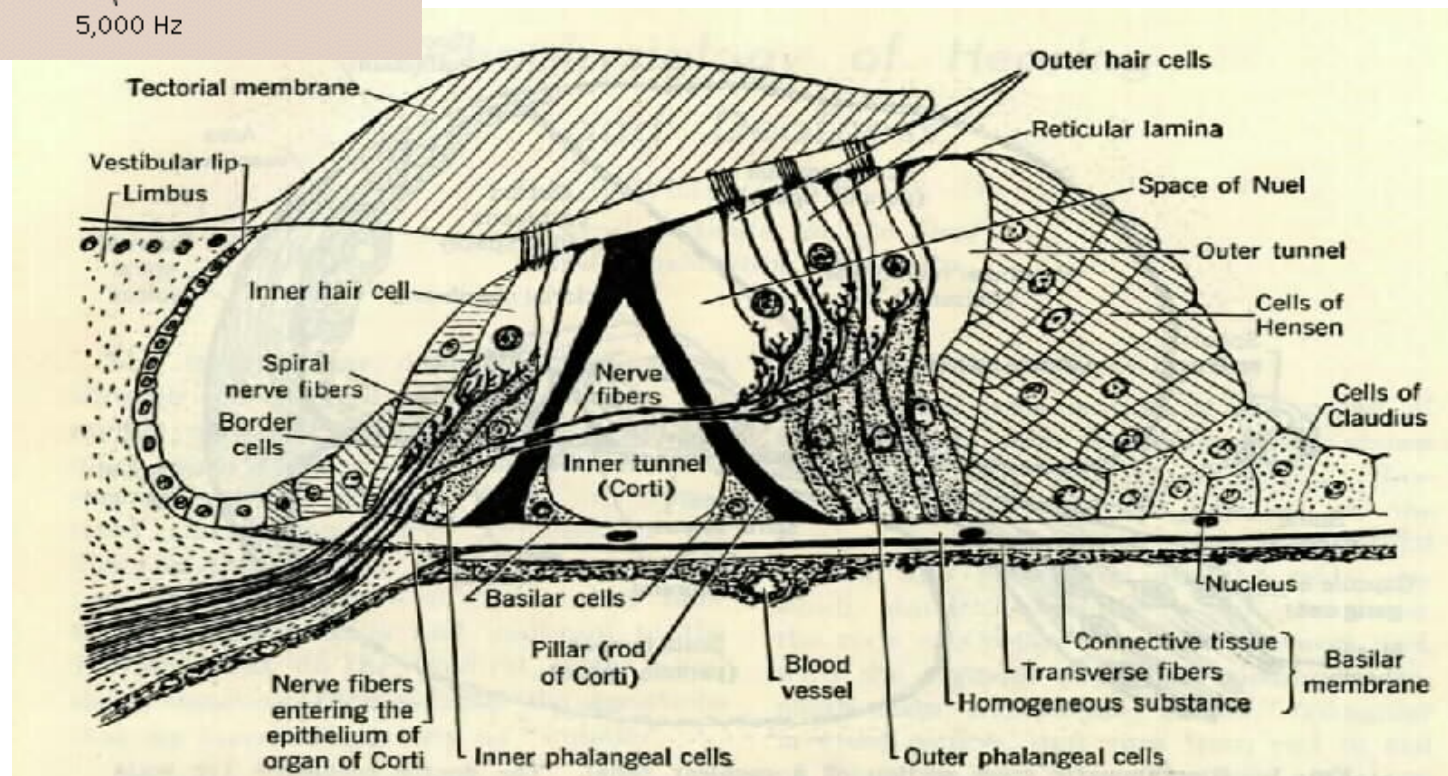
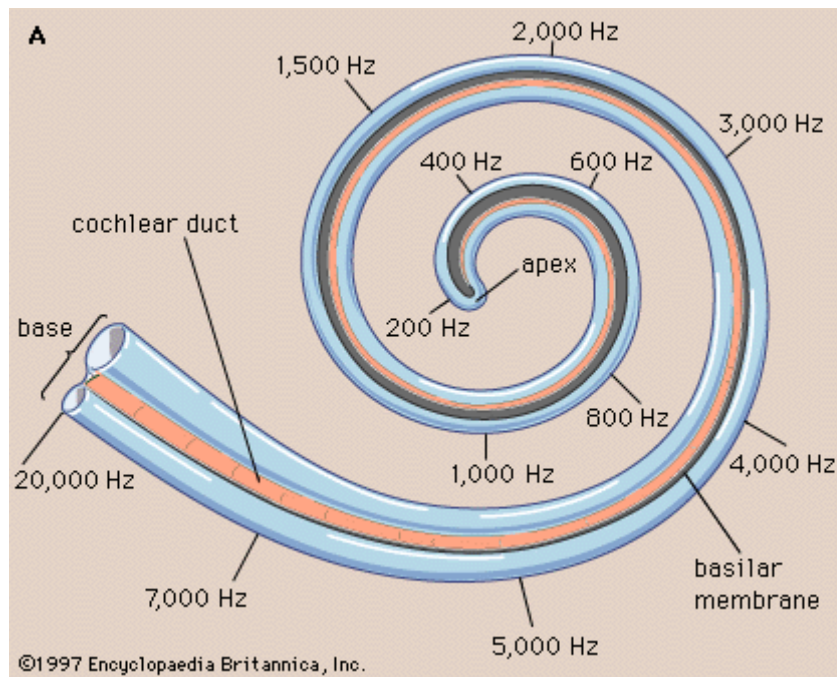
Middle Ear



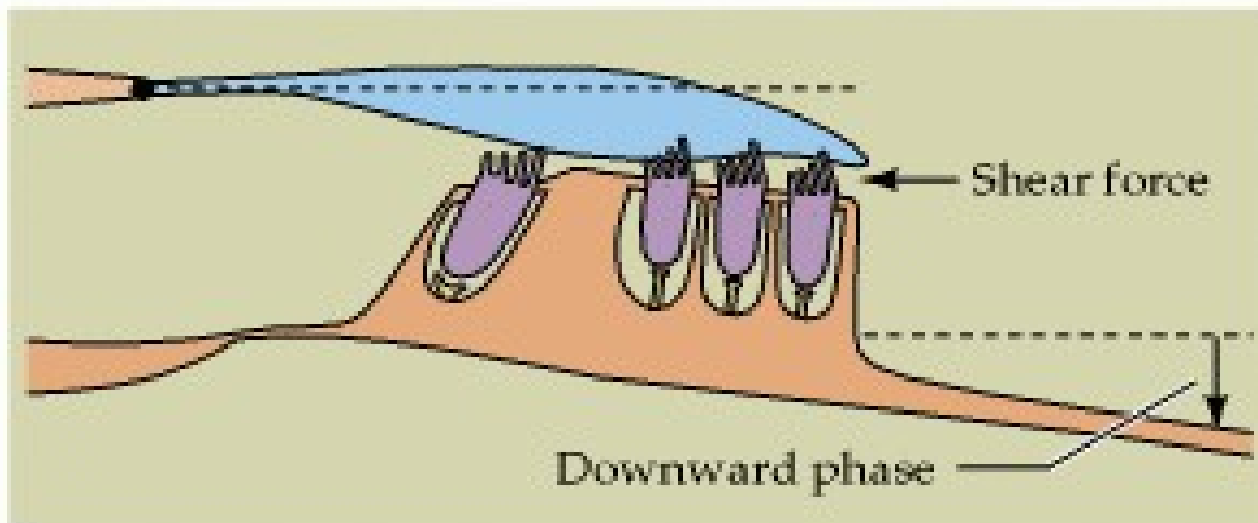
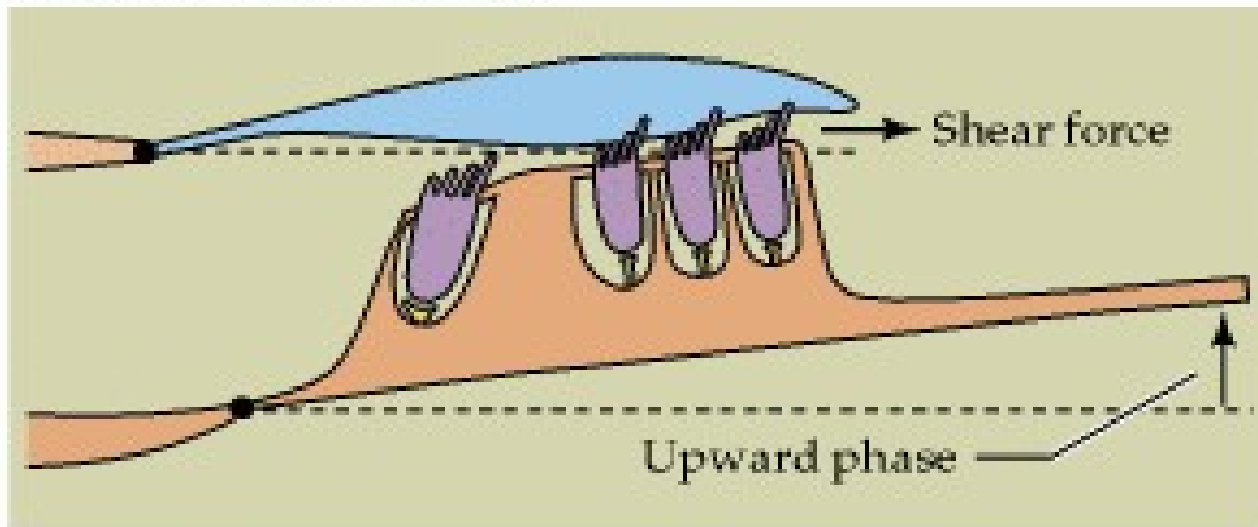
Inner Ear

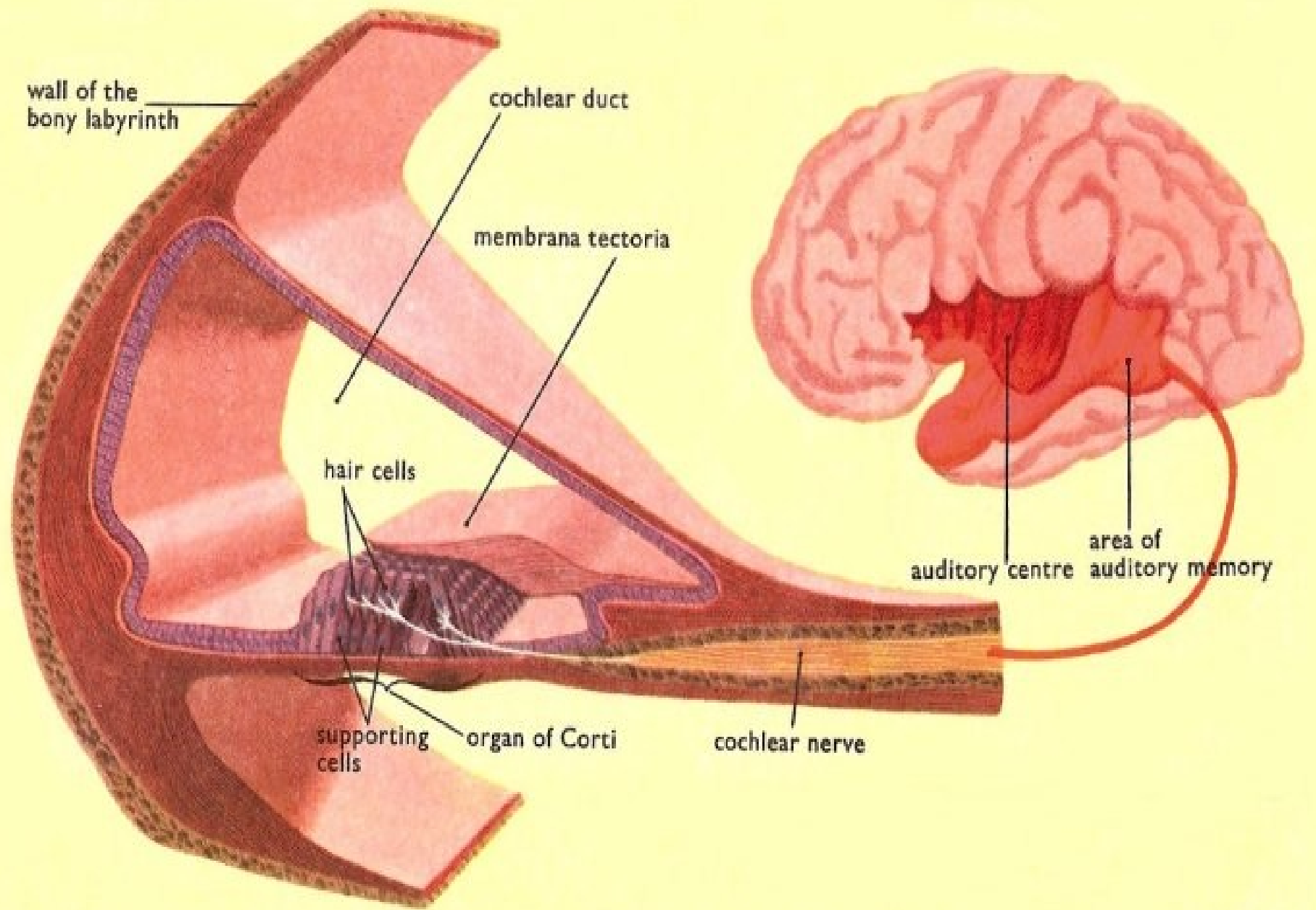


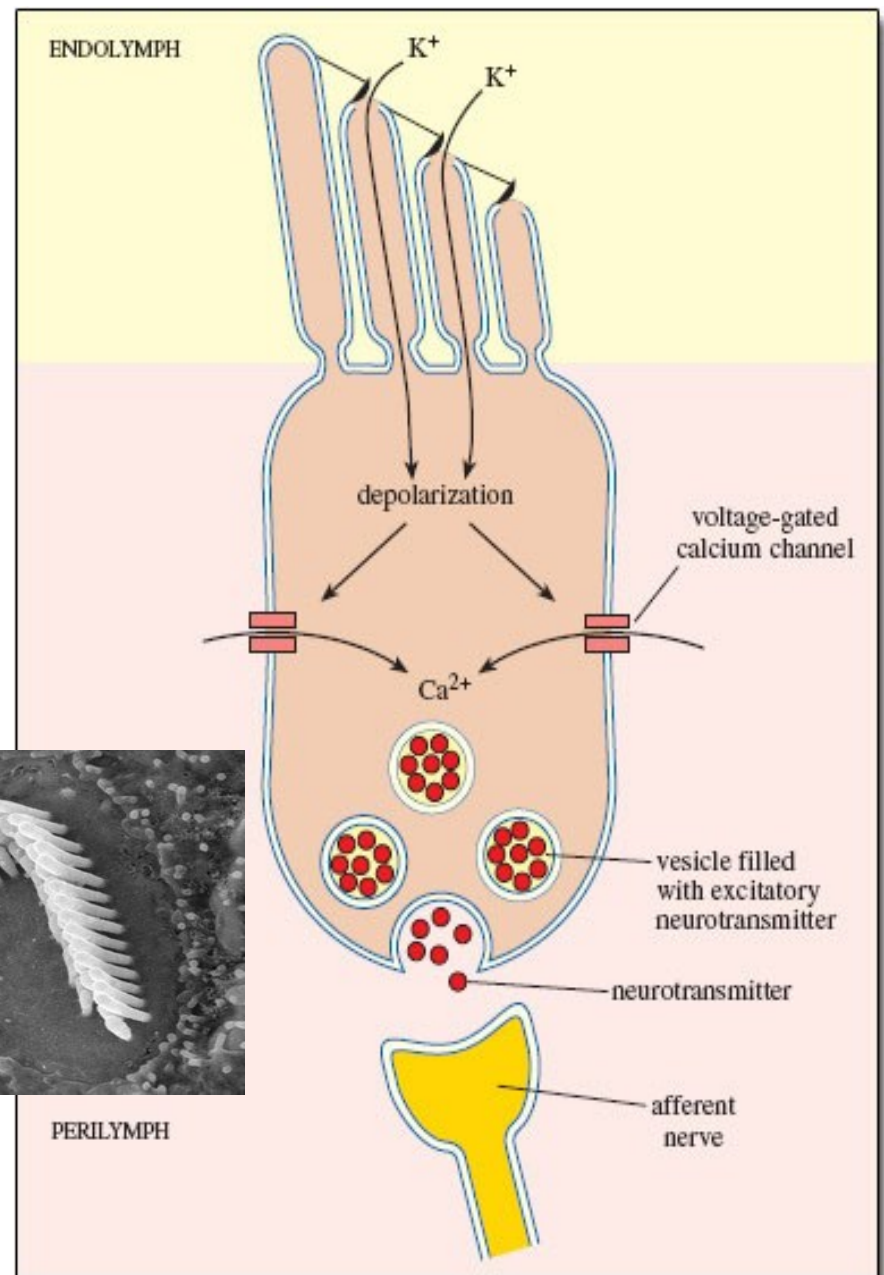
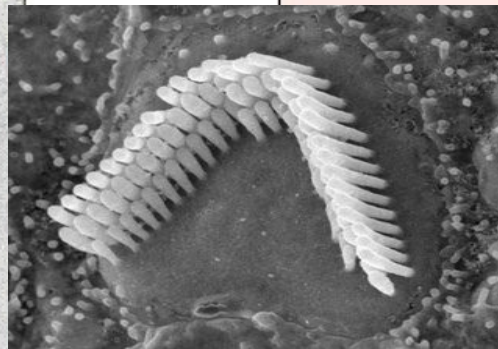
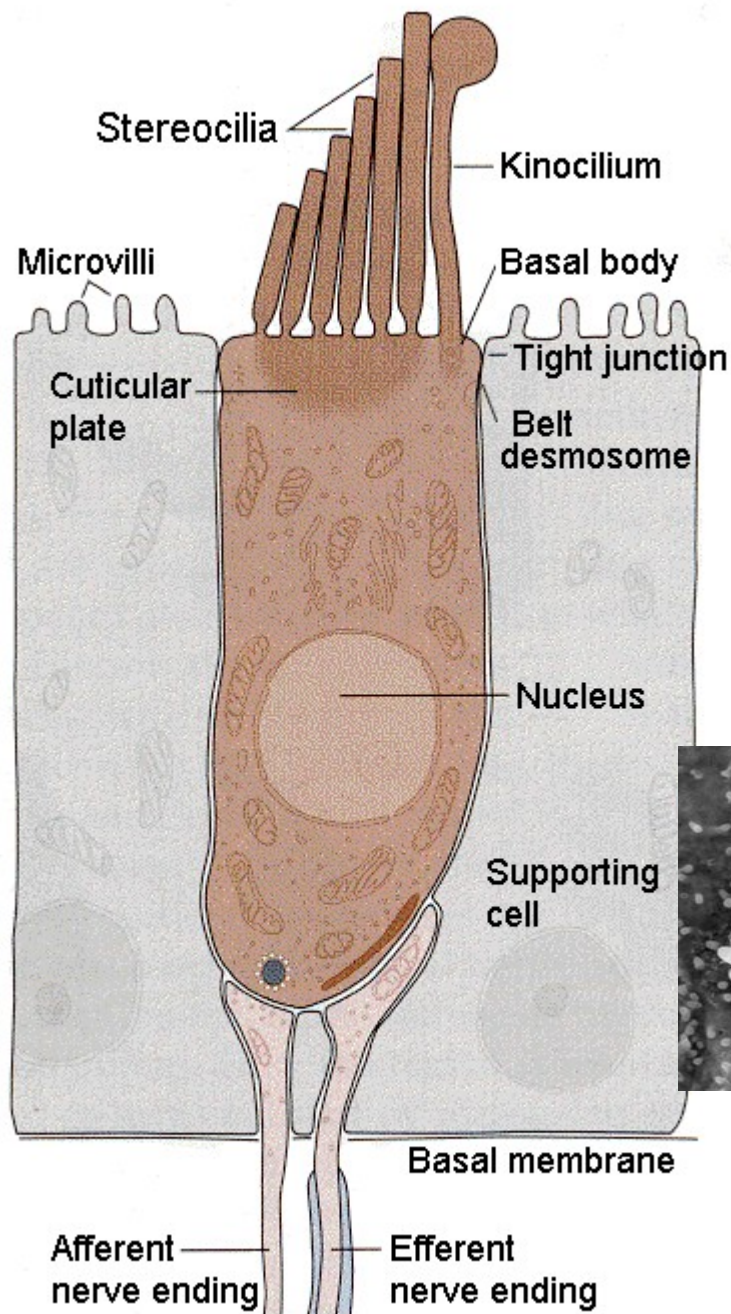


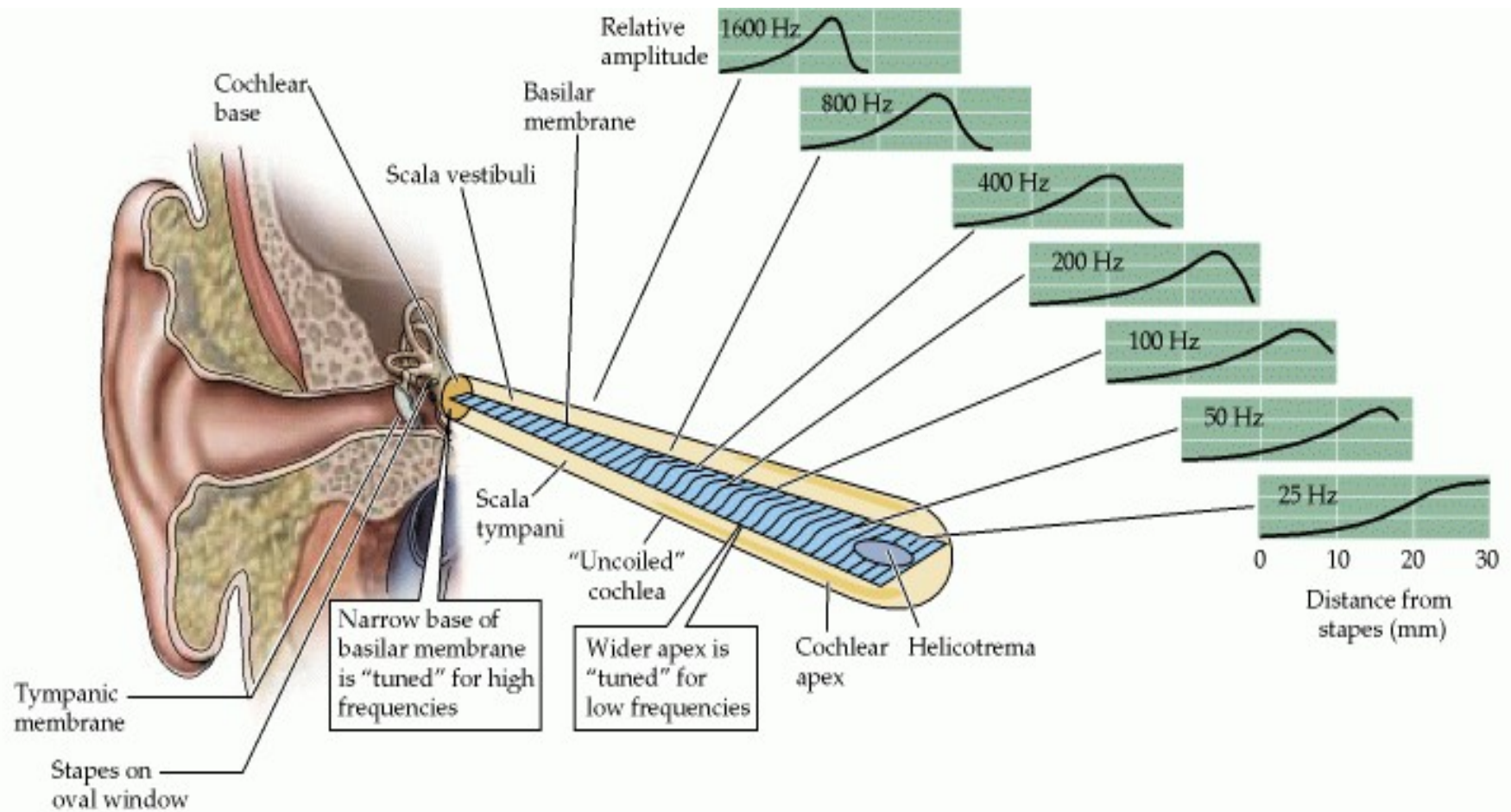


Sound-induced vibration

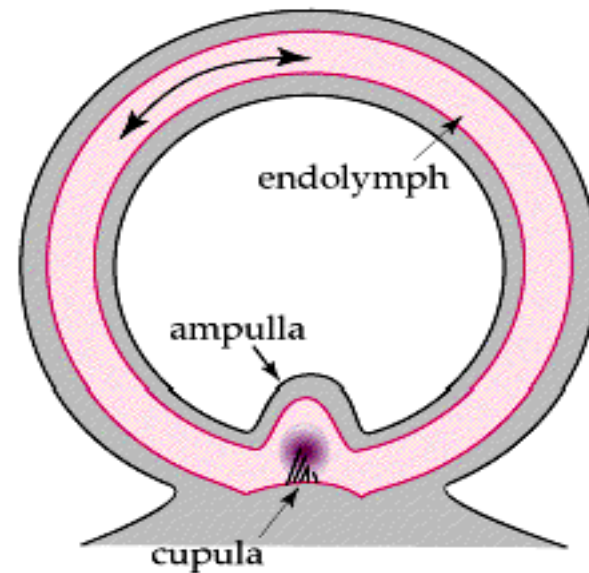
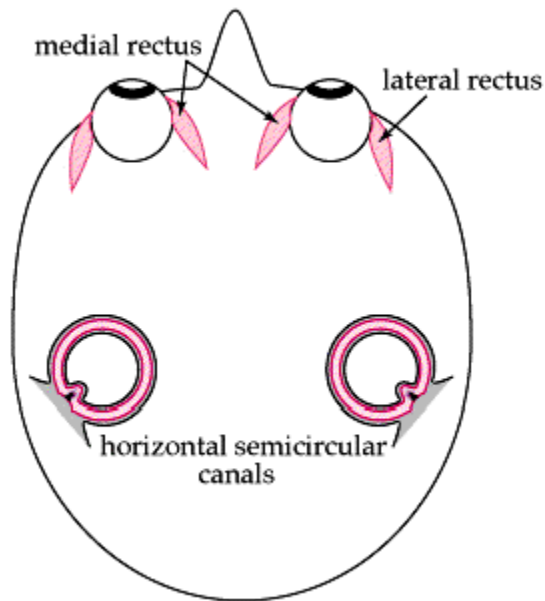








The **semicircular canals** detect angular **acceleration**. There are 3 canals, corresponding to the three dimensions in which you move, so that each canal detects motion in a single plane. Each canal is set up as shown below, as a continuous endolymph-filled hoop. The actual hair cells sit in a small swelling at the base called the ampulla.

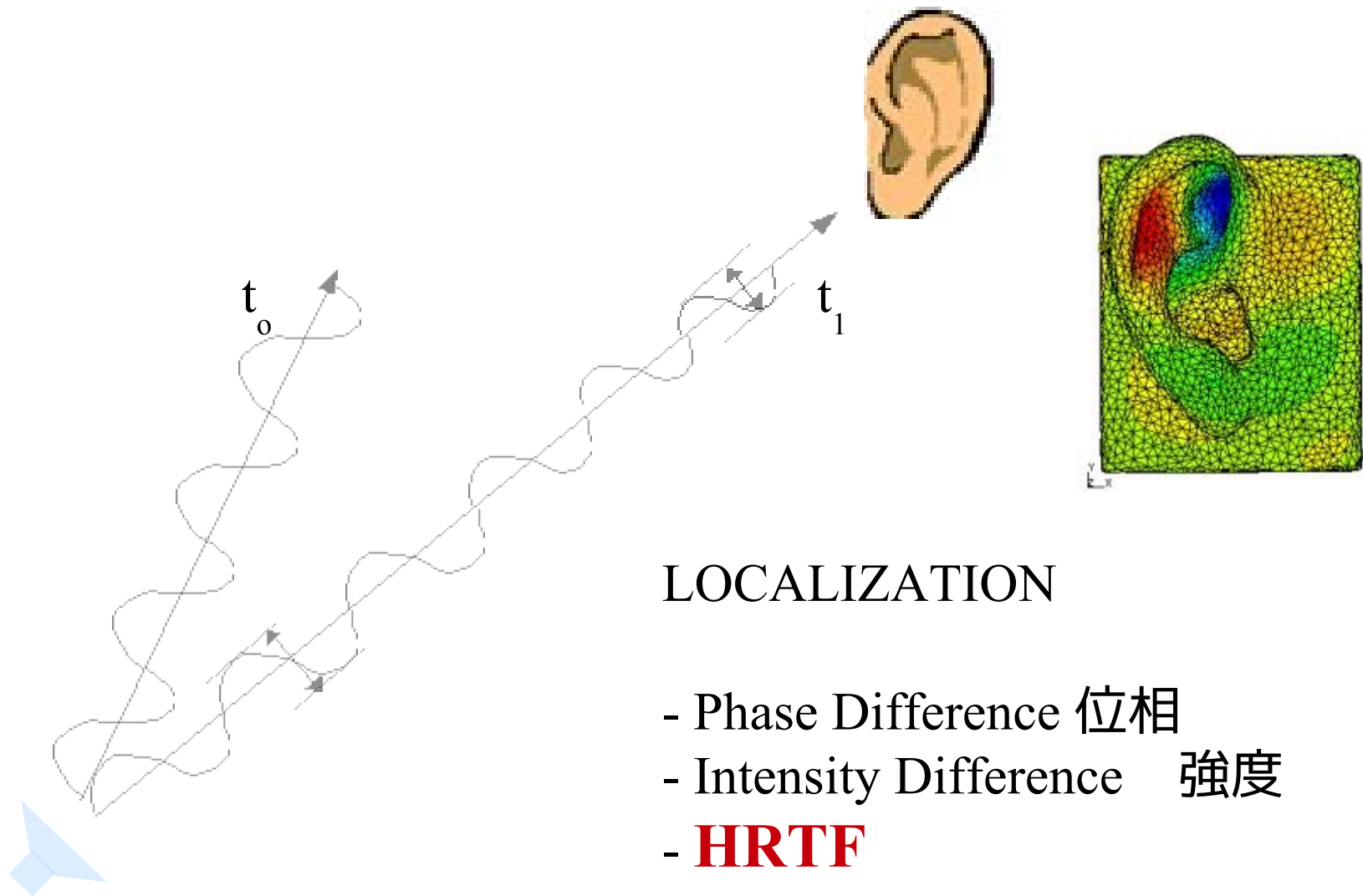


Localization of sound

The ability to estimate just where a sound is coming from, sound localization, is dependent on hearing ability of each of the two ears, and the exact quality of the sound. Since each ear lies on an opposite side of the head, a sound will reach the **closest ear first**, and its amplitude will be larger in that ear.

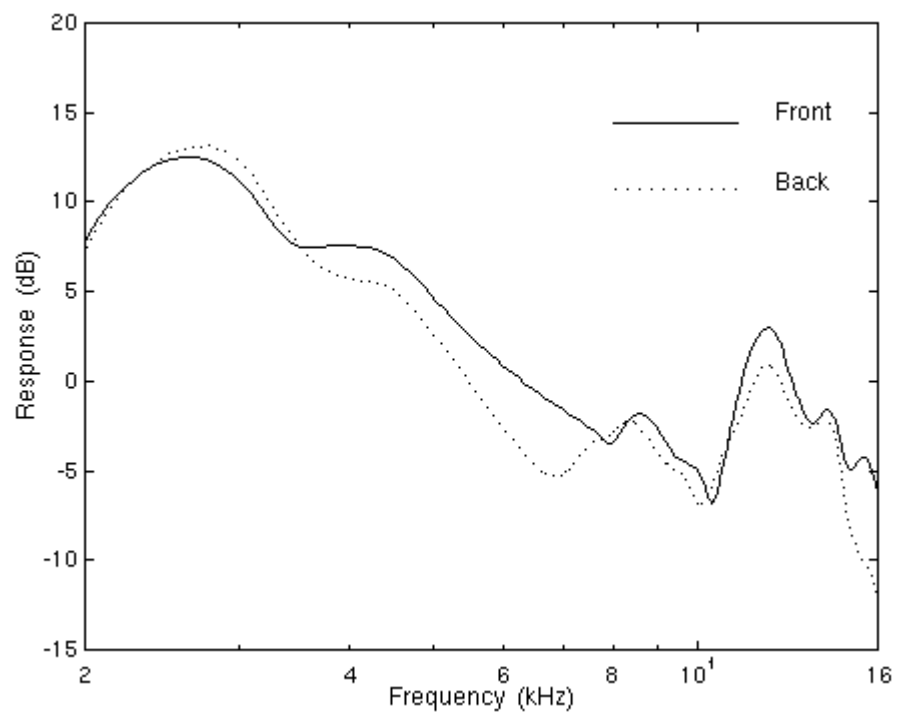
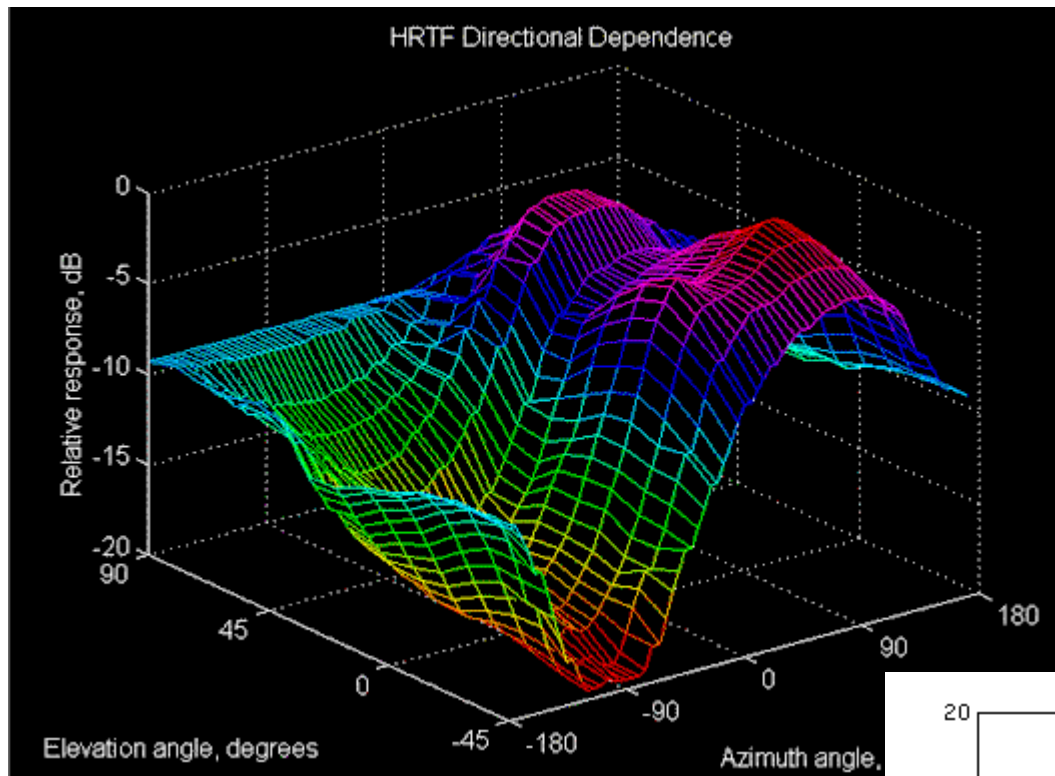
The shape of the **pinna** (outer ear) and of the head itself result in frequency-dependent variation in the amount of attenuation that a sound receives as it travels from the sound source to the ear. Furthermore, this variation depends not only on the **azimuthal angle** of the source, but also on its **elevation**. This variation is described as the head-related transfer function, or HRTF. As a result, humans can locate sound both in azimuth and altitude. Most of the brain's ability to localize sound depends on interaural (between ears) **intensity** differences and interaural **temporal**, or phase, differences. In addition, humans can also estimate the distance that a sound comes from, based primarily on how **reflections** in the environment modify the sound, for example, as in room reverberation.

Human echolocation is a technique used by some blind humans to navigate within their environment by listening for echoes of clicking or tapping sounds that they emit.



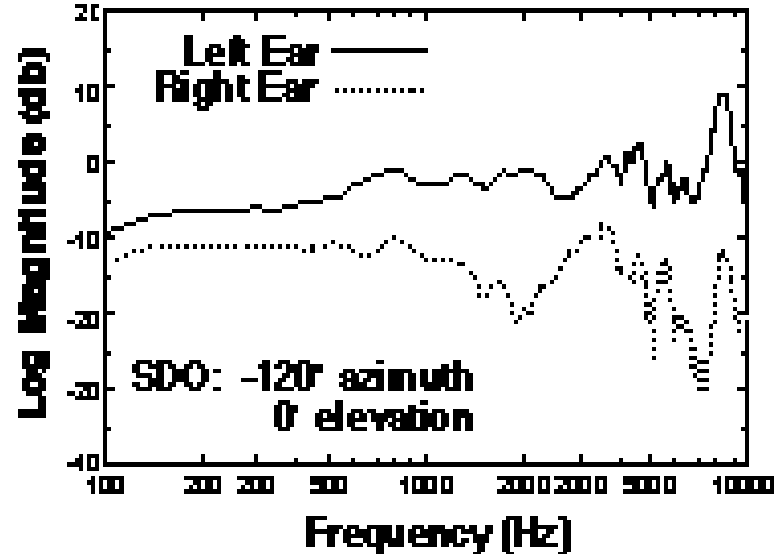
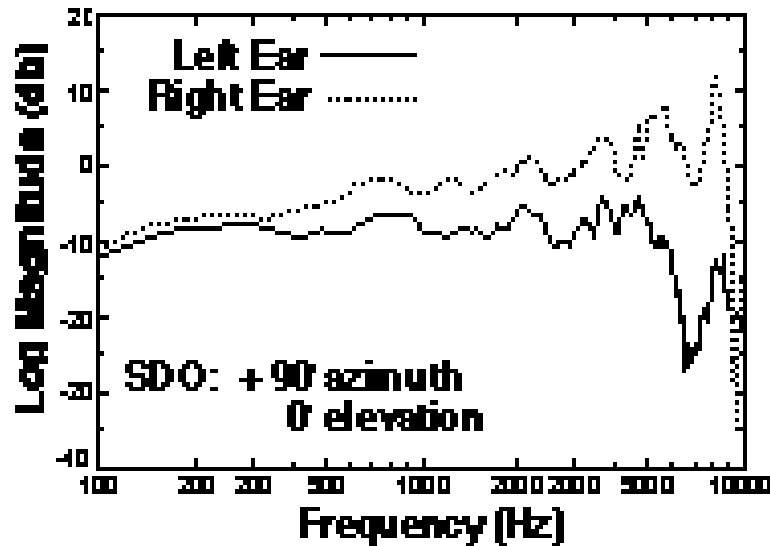
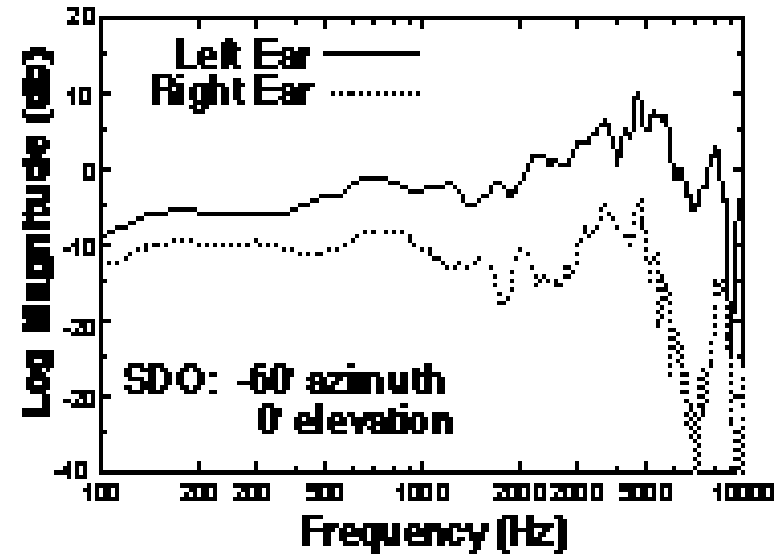
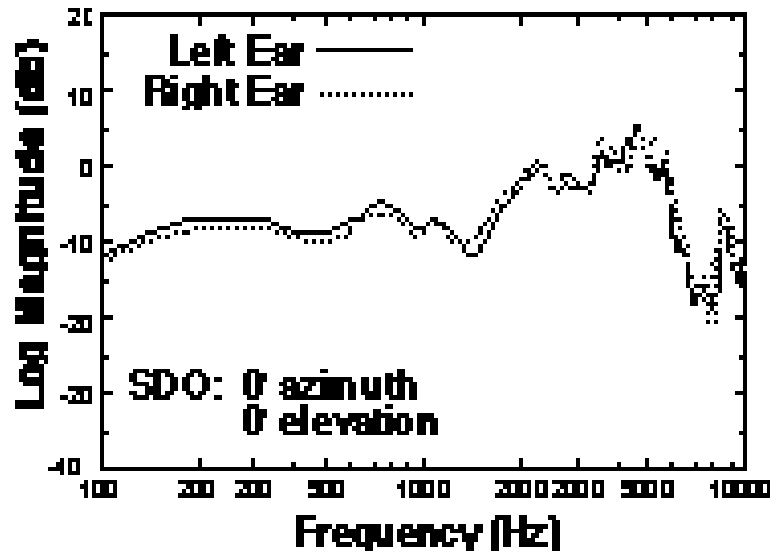
LOCALIZATION

- Phase Difference 位相
- Intensity Difference 強度
- **HRTF**

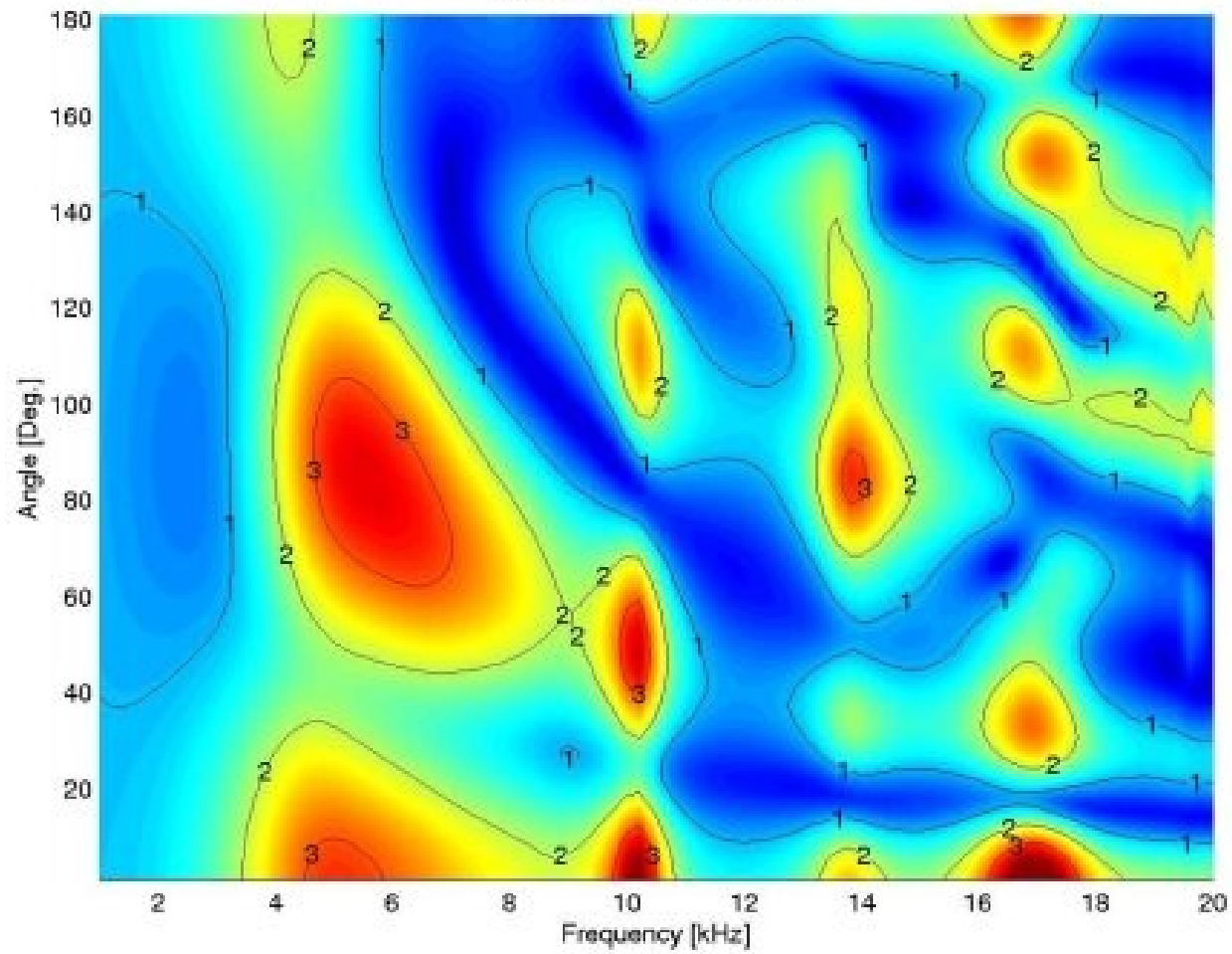


Head-Related Transfer Functions (HRTFs)

Frequency Domain: Magnitude Spectra



DB60 - baffle - simulation

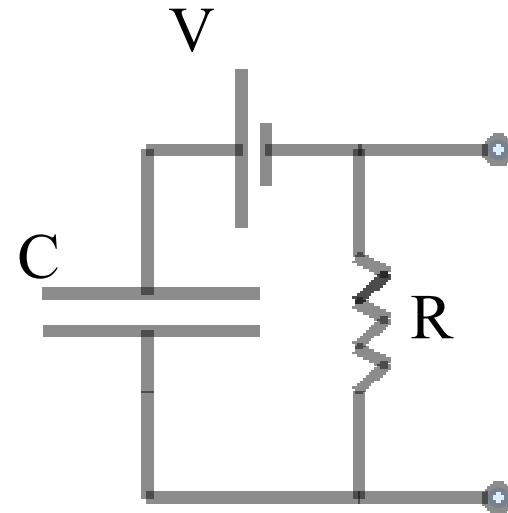
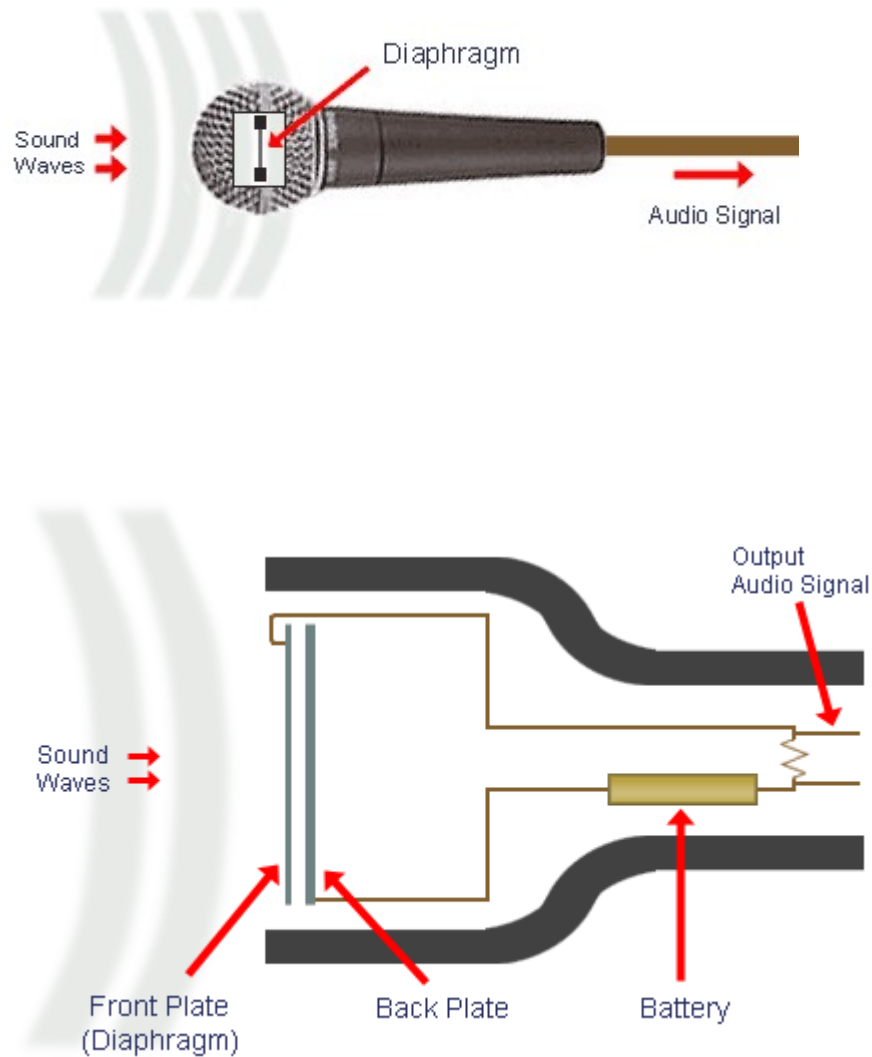


THE ARTIFICIAL EARS: (マイクロホン)



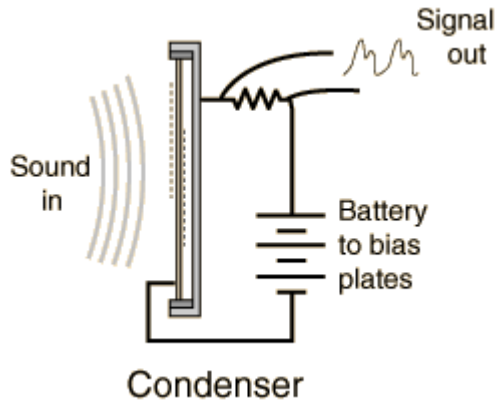
Frequency response
Dynamic Response

Condenser microphones



$$C = \epsilon \frac{S}{d}$$
$$V_c = \frac{Q}{C}$$

Condenser microphones have a flatter frequency response than dynamics



$$Q = CV = \frac{\alpha(\text{Area of plate})(\text{voltage})}{(\text{plate spacing})}$$



Advantages:

Best overall frequency response makes this the microphone of choice for many recording applications.

Disadvantages:

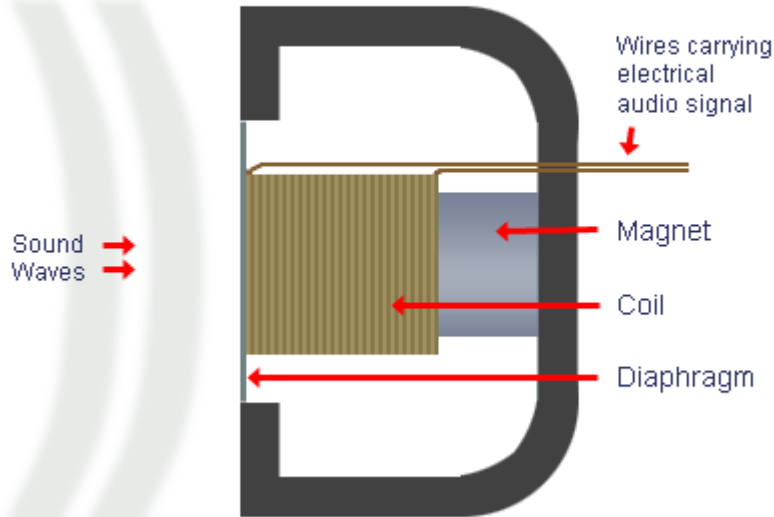
Expensive

May pop and crack when close miked

Requires a battery or external power supply to bias the plates.

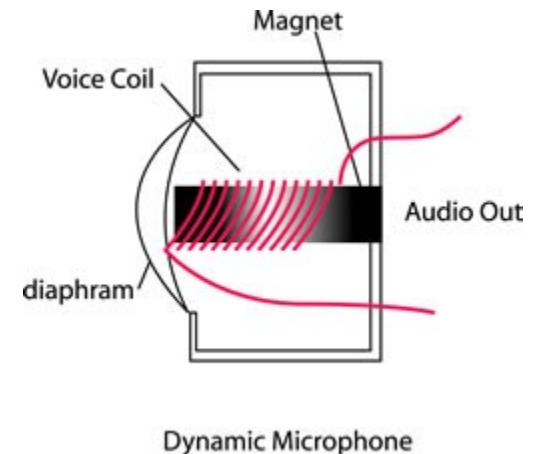
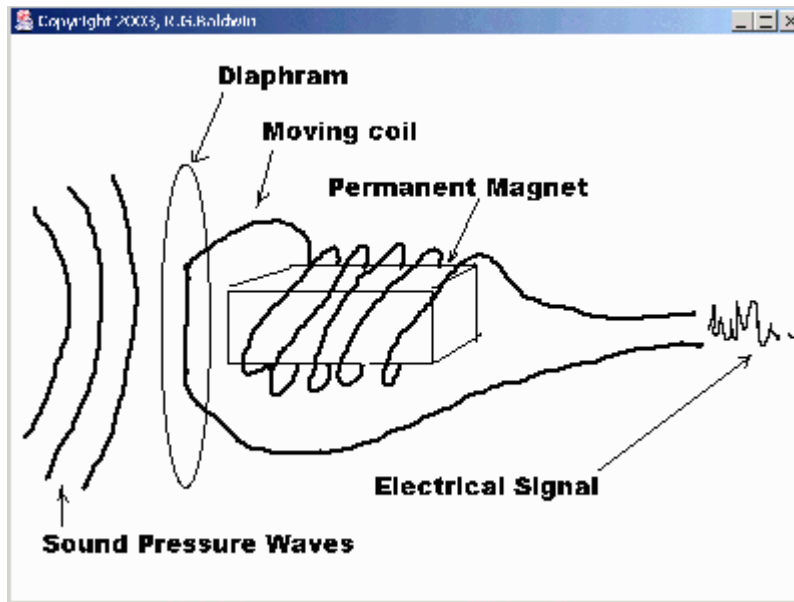
Dynamic microphones (Electromagnetic Microphones)

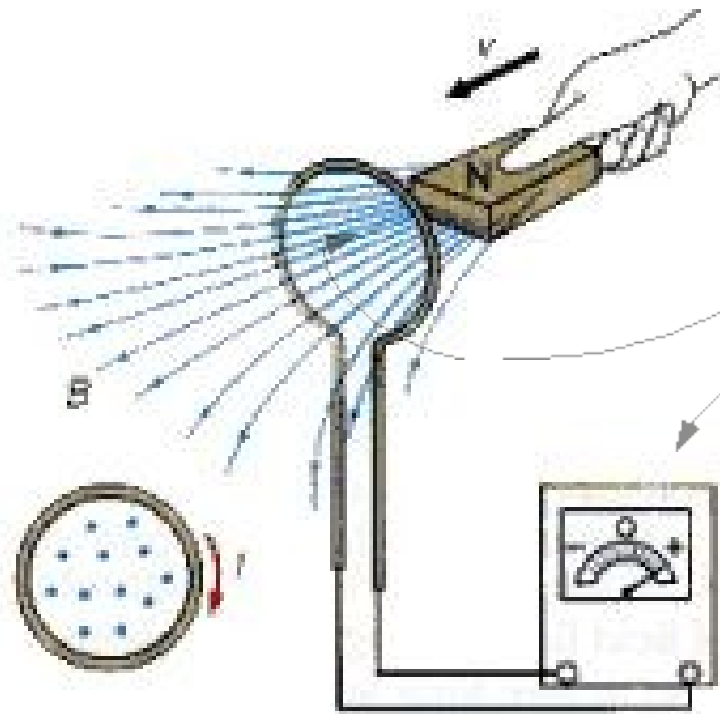
Cross-Section of Dynamic Microphone



Dynamics do not usually have the same flat frequency response as condensers. Instead they tend to have tailored frequency responses for particular applications.

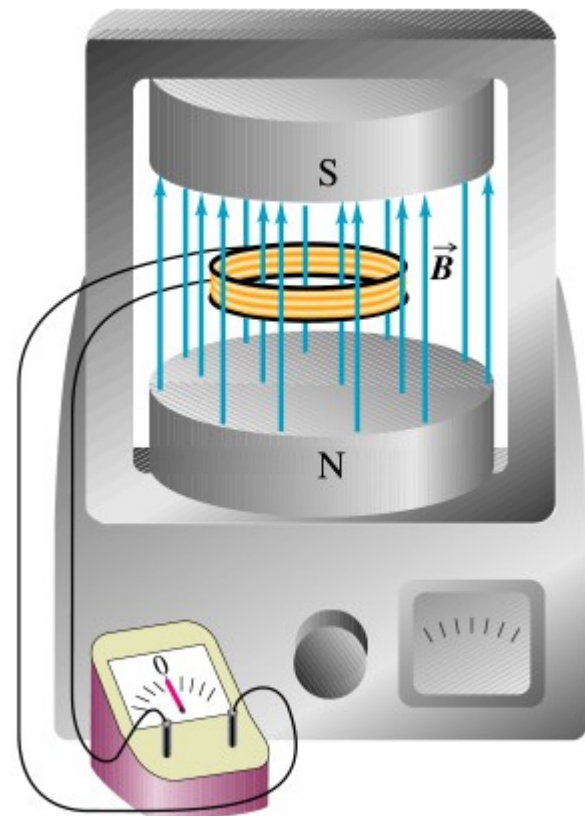
However they have a good Dynamic response.



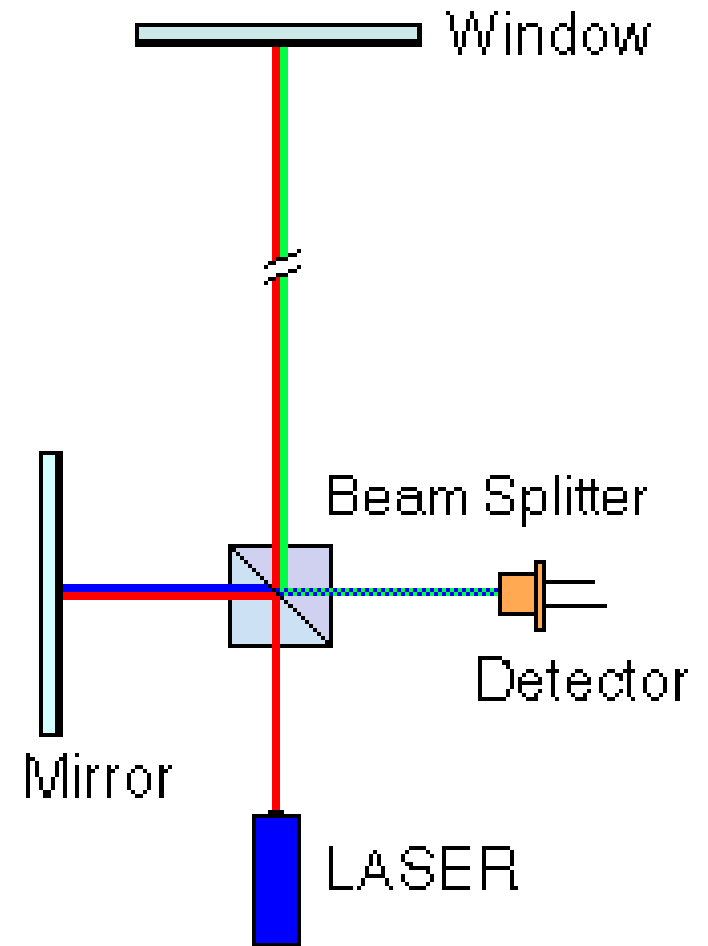
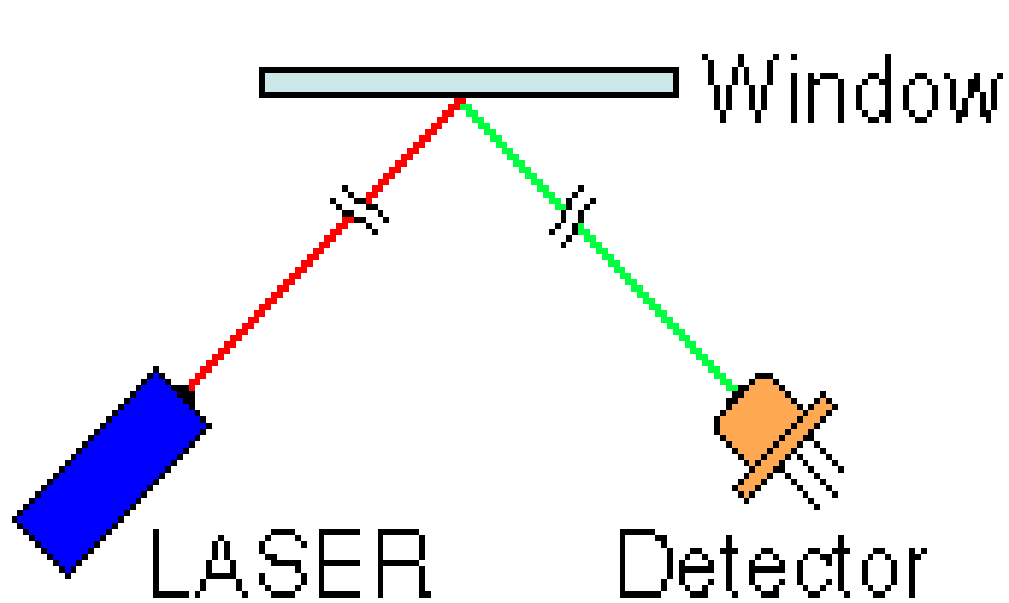


$$\phi = \oint \vec{B} \cdot d\vec{A}$$

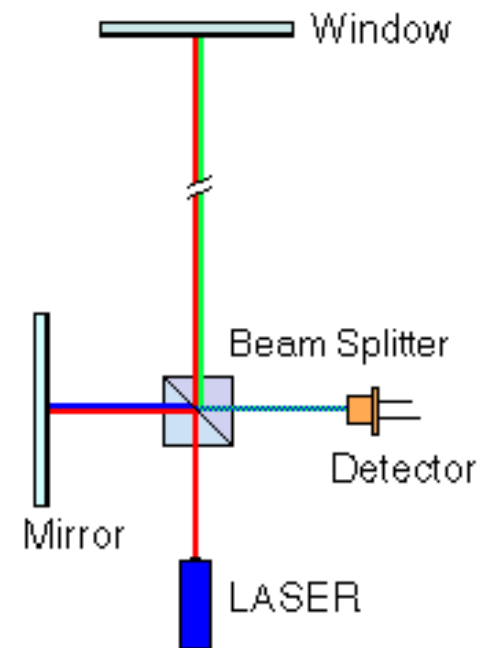
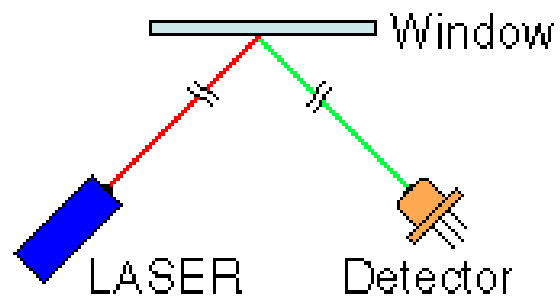
$$\mathcal{E} = -\frac{d\phi}{dt}$$

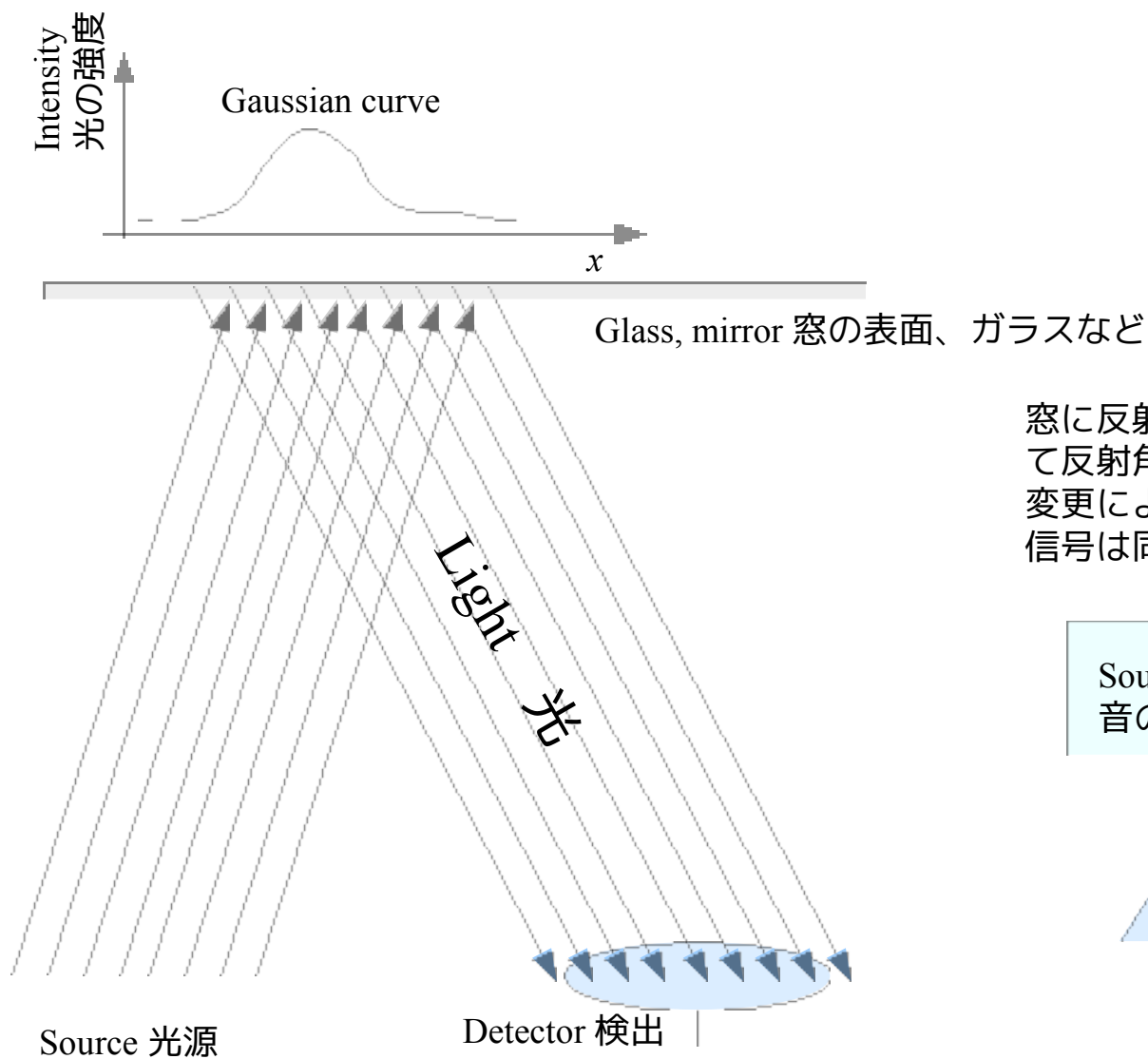


LASER microphone (Spy Microphone)

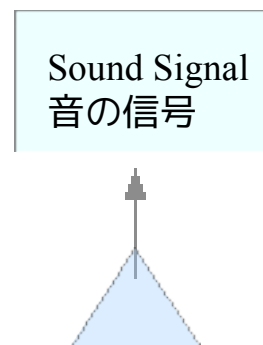


LASER microphone (Spy Microphone)





窓に反射するとき音の強度によって反射角度は少し変更します。角度変更によって、検出に得られた光の信号は同じように変更します。



The sound system, a summary: documentary

