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**EECS 225D**

**Audio Signal Processing in Humans and Machines**

**Lecture 15 – Pitch**

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**2012-3-12**

**Professor Nelson Morgan**  
today's lecture by **John Lazzaro**

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**[www.icsi.berkeley.edu/eecs225d/](http://www.icsi.berkeley.edu/eecs225d/)**

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# Today's lecture: Pitch

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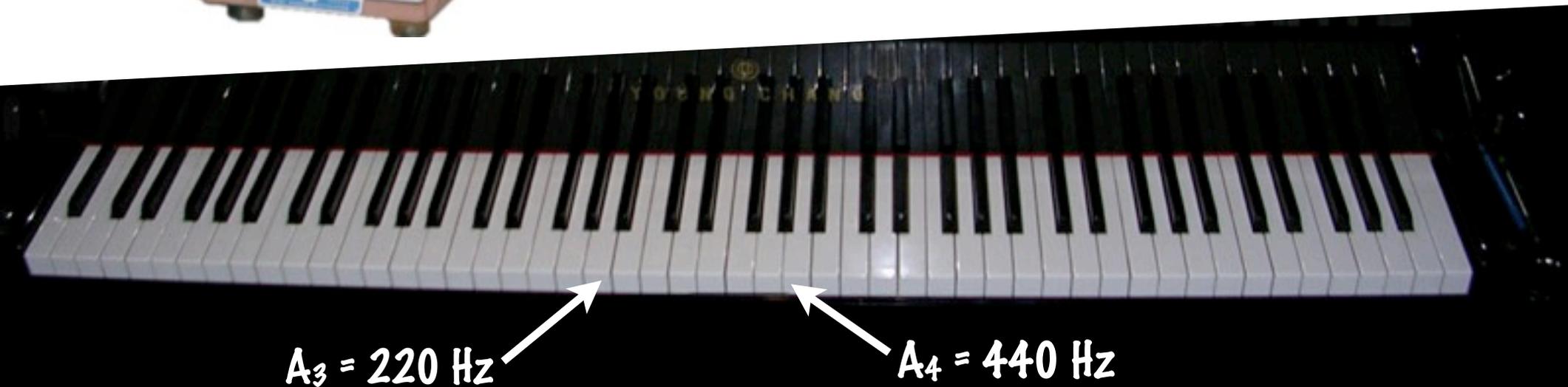
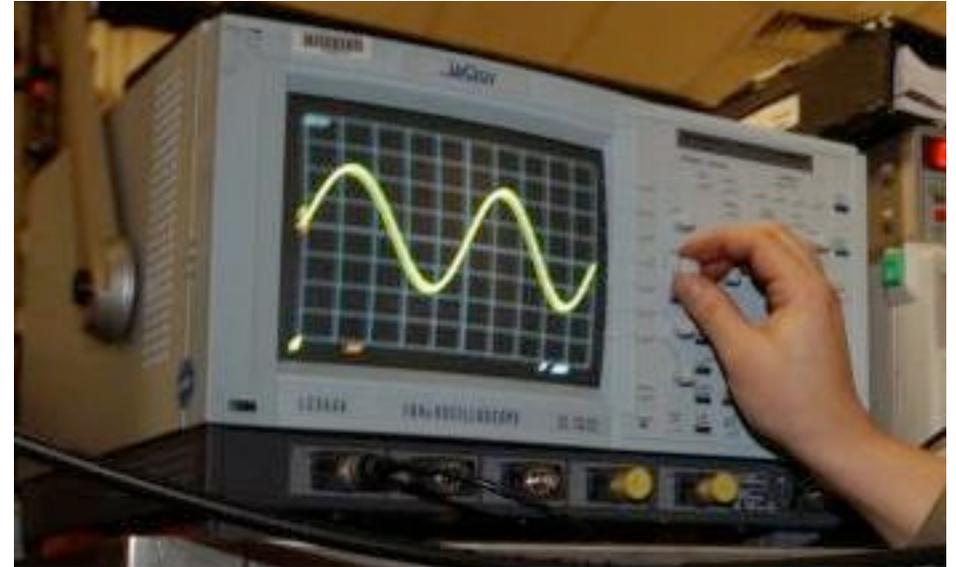
✳ **Basic concepts in pitch detection**

✳ Practical issues in pitch tracking

✳ The quiz ...

# Musical pitch: an experimental definition

**Pitch (unit: Hz).** The frequency of a sine wave whose pitch is heard to be the same as a played note.



# Timbre and Pitch

Why are the timbres different?

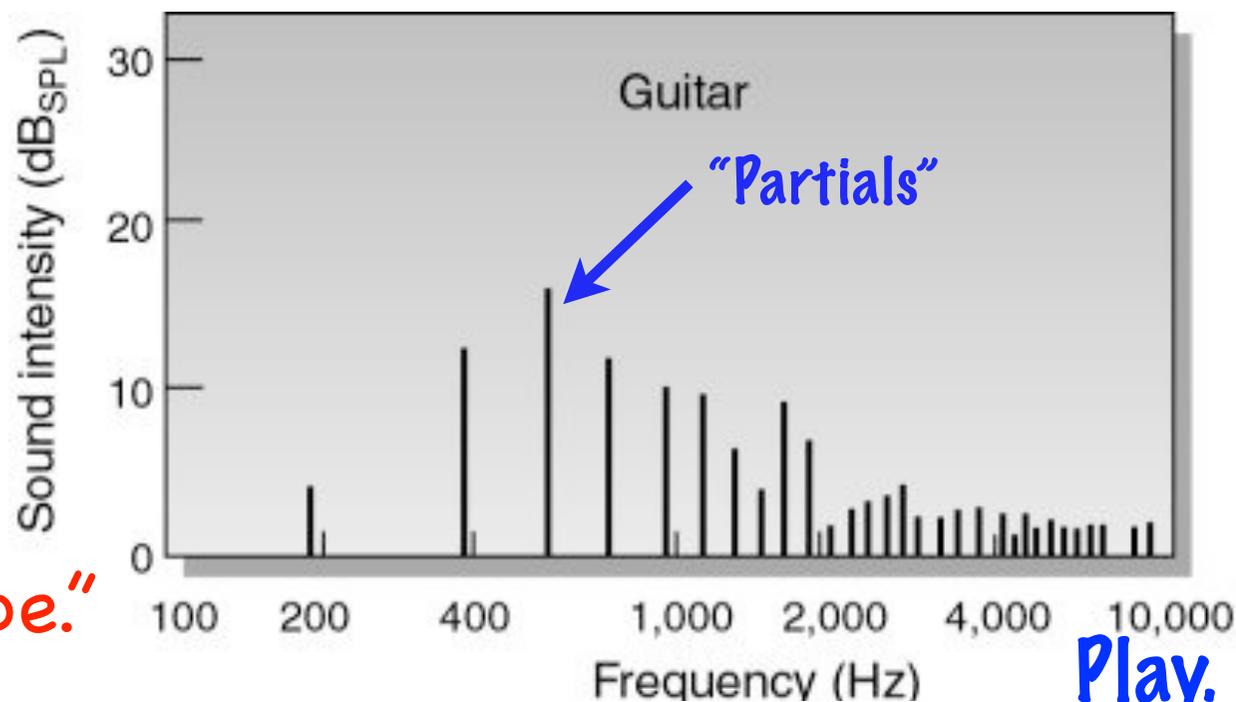
Contributing factor: Partial heights differ, and evolve differently over time. "Spectral Shape."

Why are both sounds pitched?

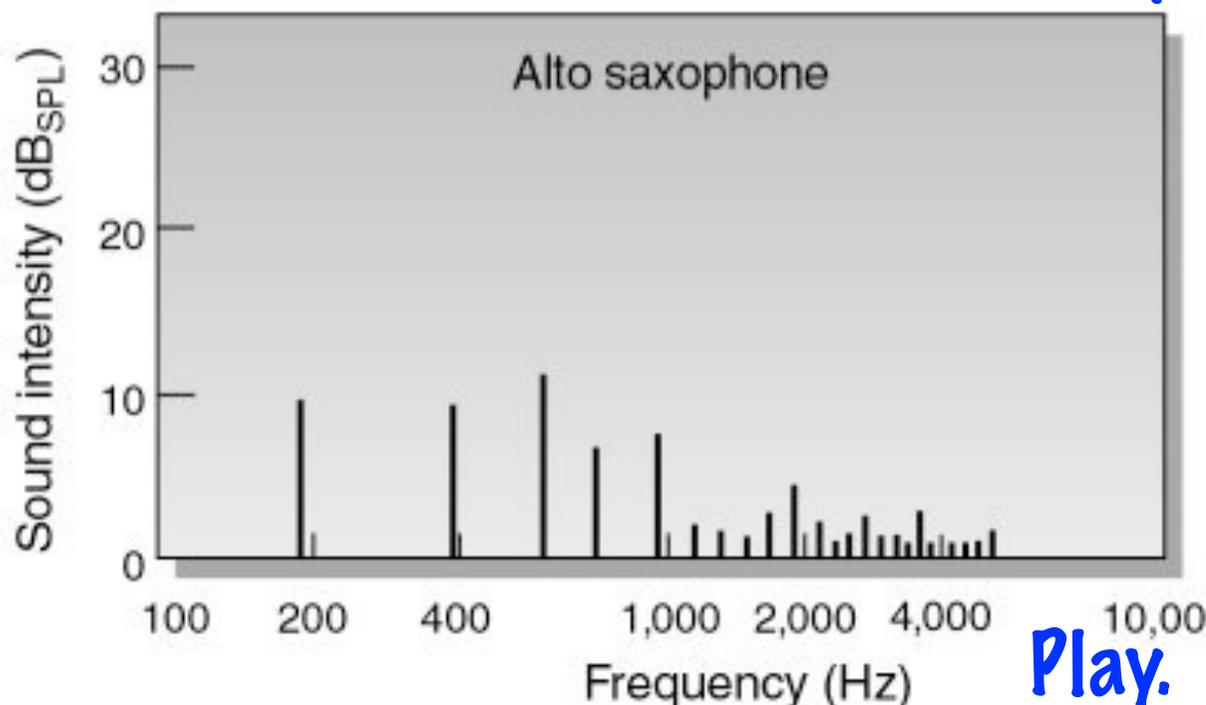
Why is the pitch the same?

Frequency placement of partials share a common structure.

## Same pitch, different timbre

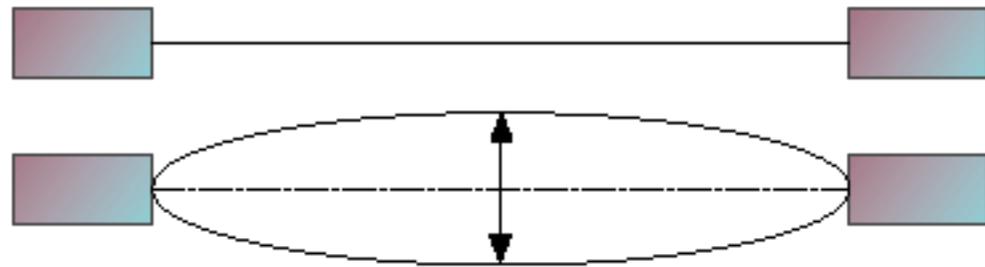
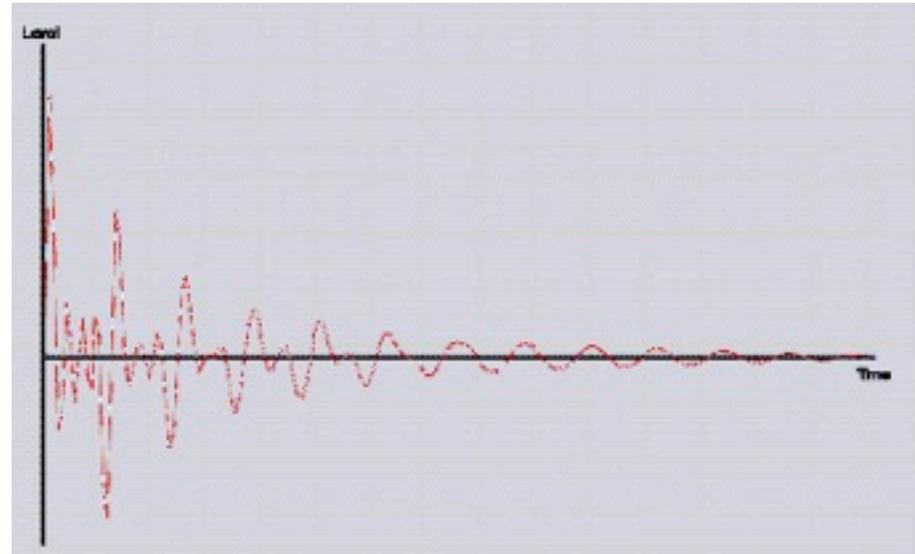


Play.

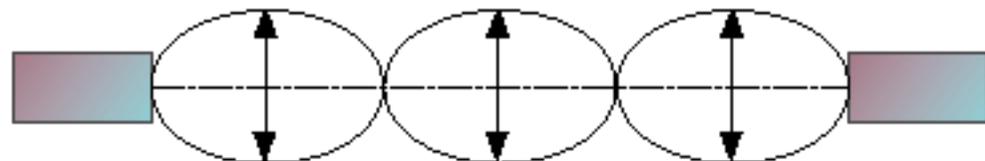
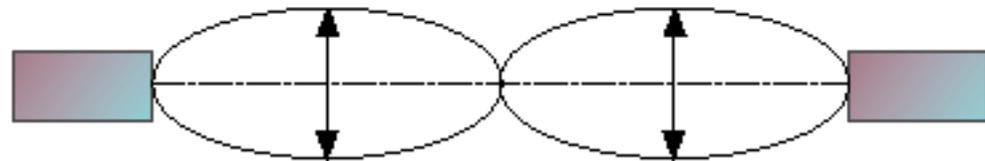
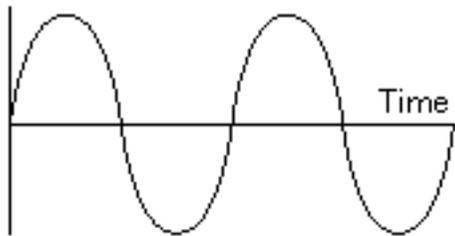


Play.

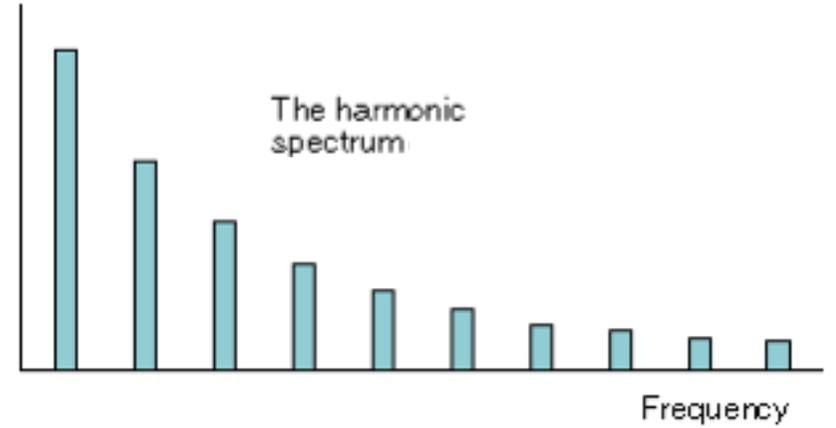
EXAMPLE BY KENNETH STEELE, APPALACHIAN STATE .

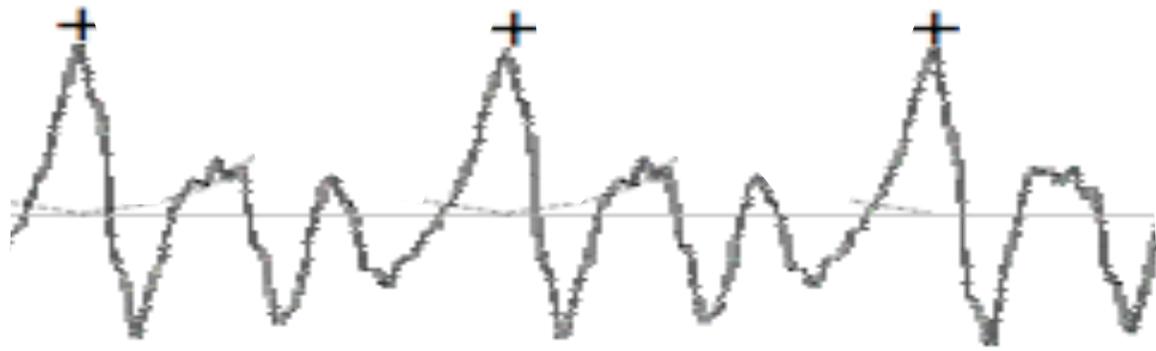


Displacement

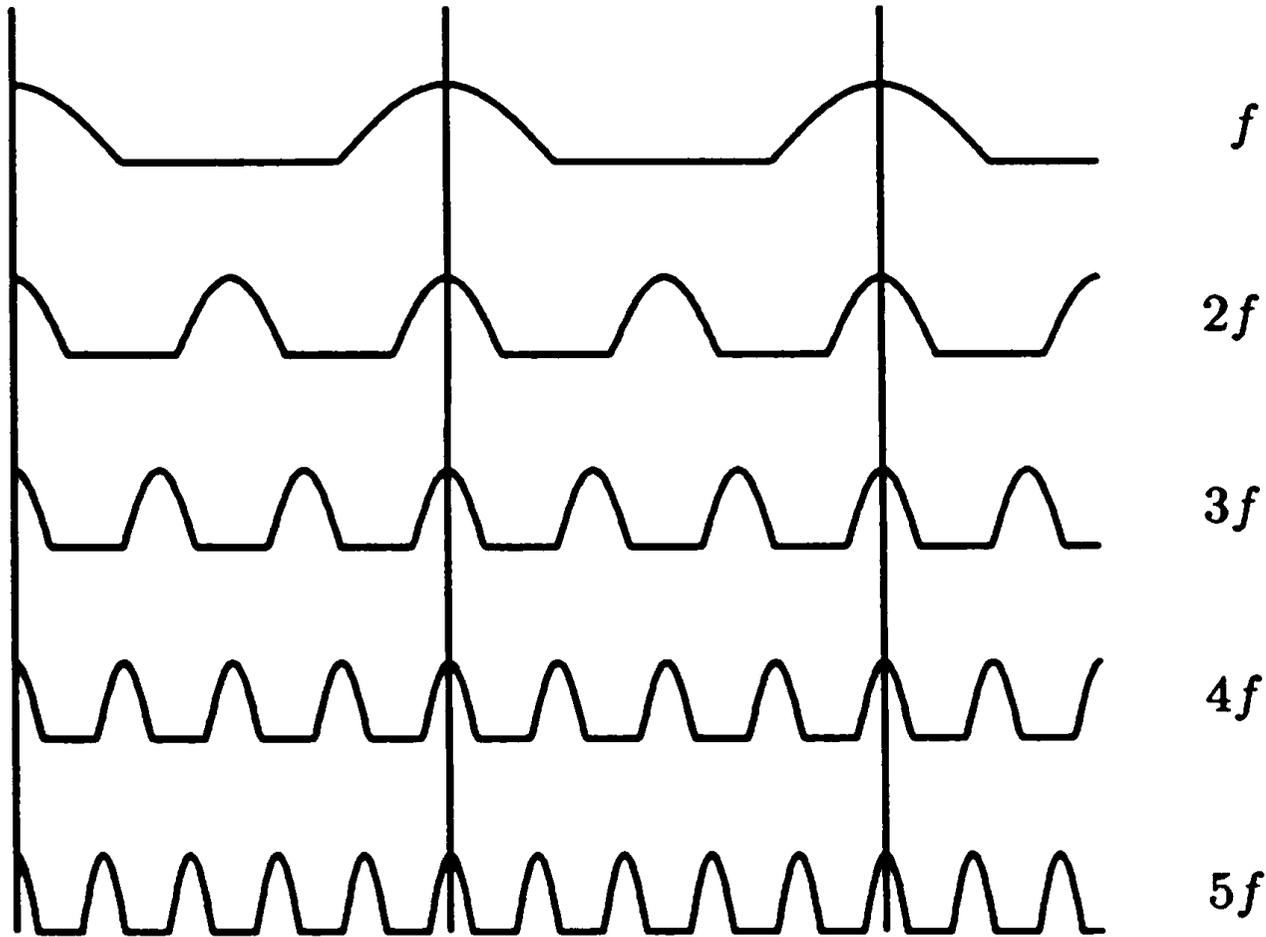


Amplitude





Summed waveform repeats at pitch frequency.

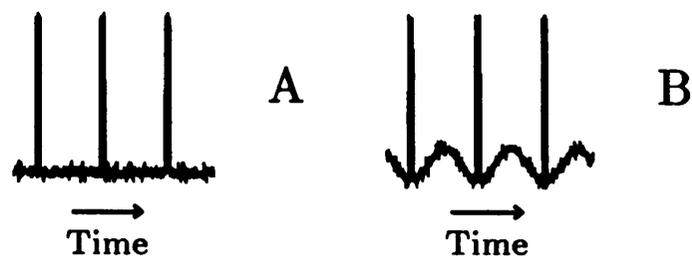


Frequencies of partials are integer multiples of an underlying fundamental.

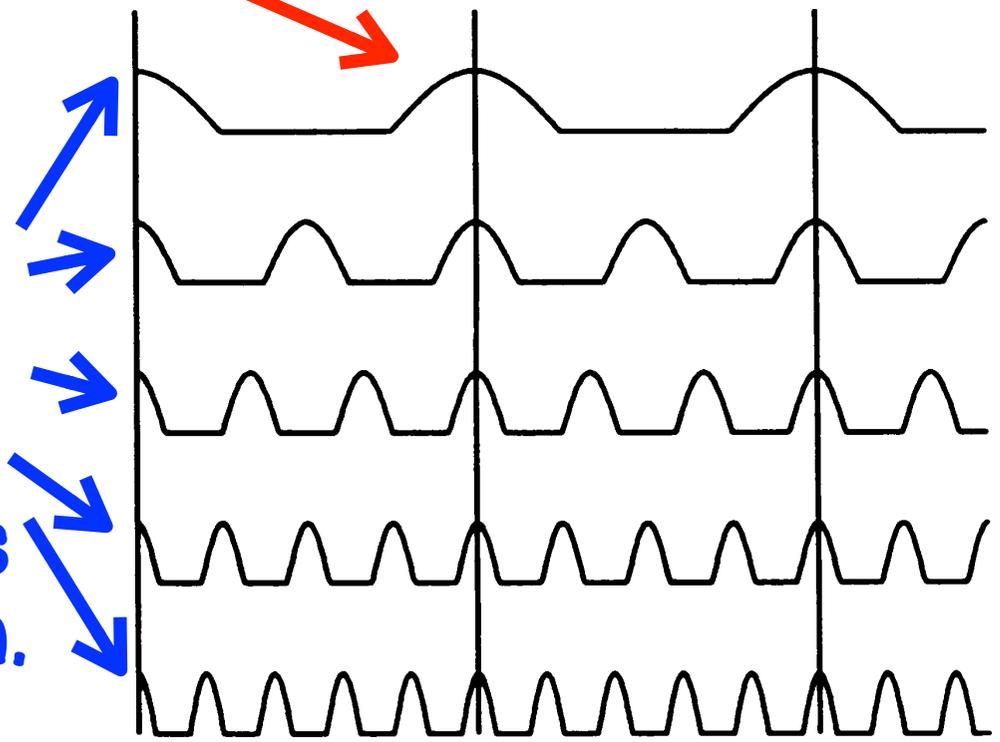


Pitch Period =  $1 / (\text{Pitch Frequency})$

**Caveats:** First partial not necessary to detect pitch - A and B → are heard with same pitch.



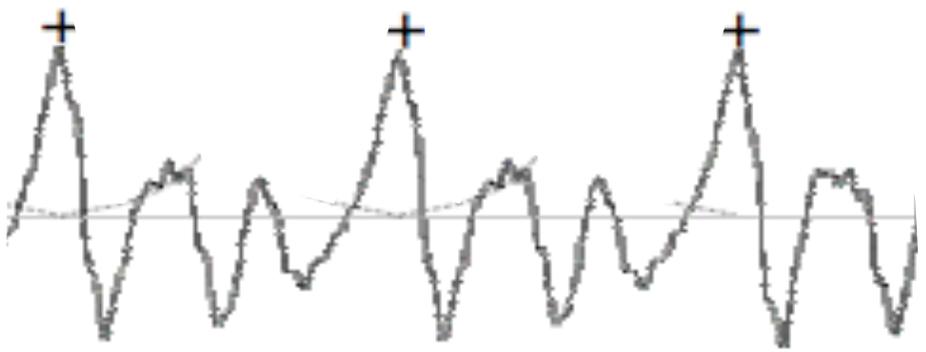
**Relative phases of partials need not be aligned - any phase relation yields a strong pitch.**



$f$   
 $2f$   
 $3f$   
 $4f$   
 $5f$

**Sounds whose partials are not quite integer-related still yield a sense of pitch -**

**Thus ... repeating shape may be subtle to detect directly.**

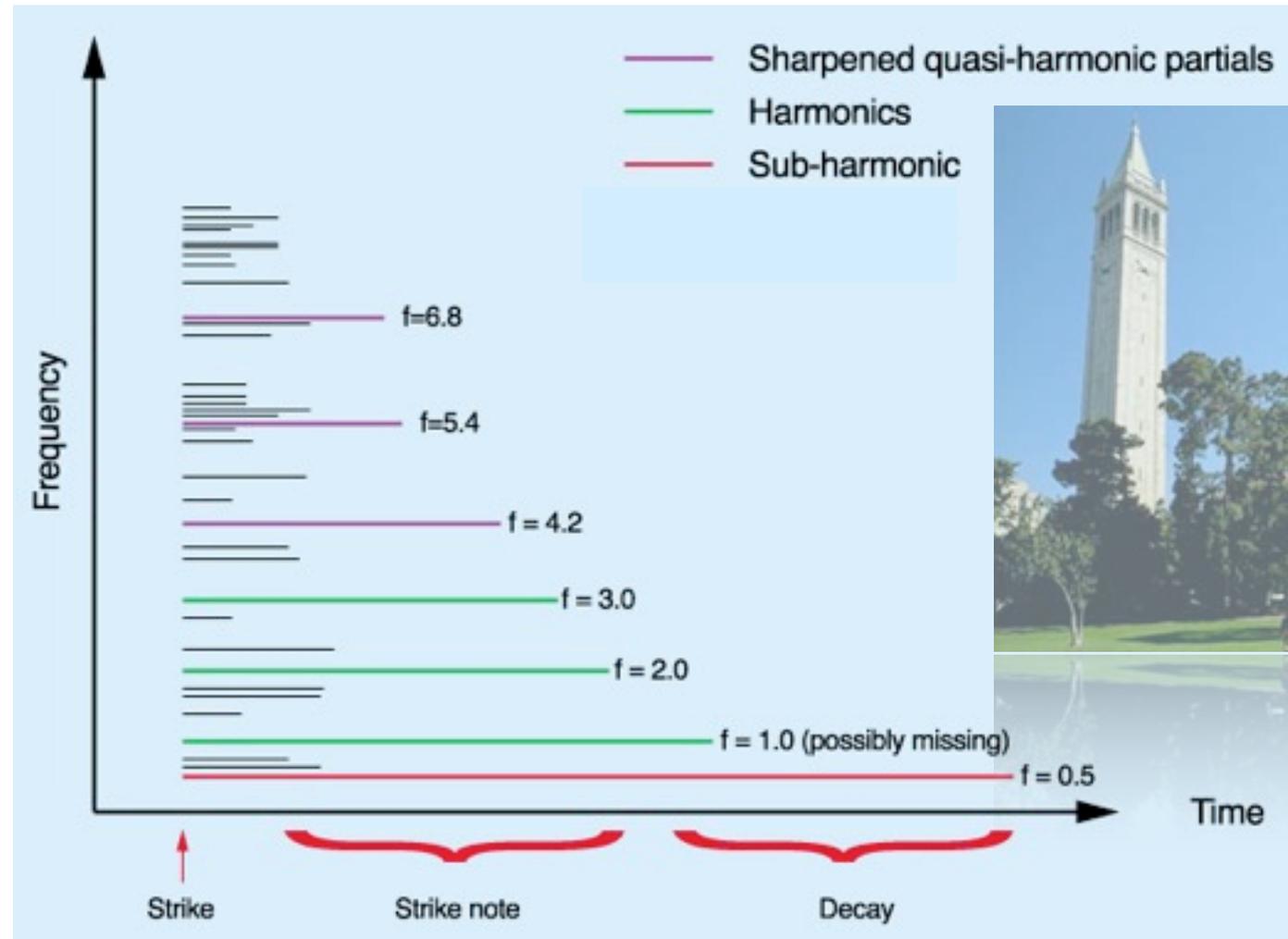


# Bells

Lowest partials are exact integers, but higher partials are quasi-harmonic (4.2, 5.4, 6.8).

We still hear the bells as having a definite pitch.

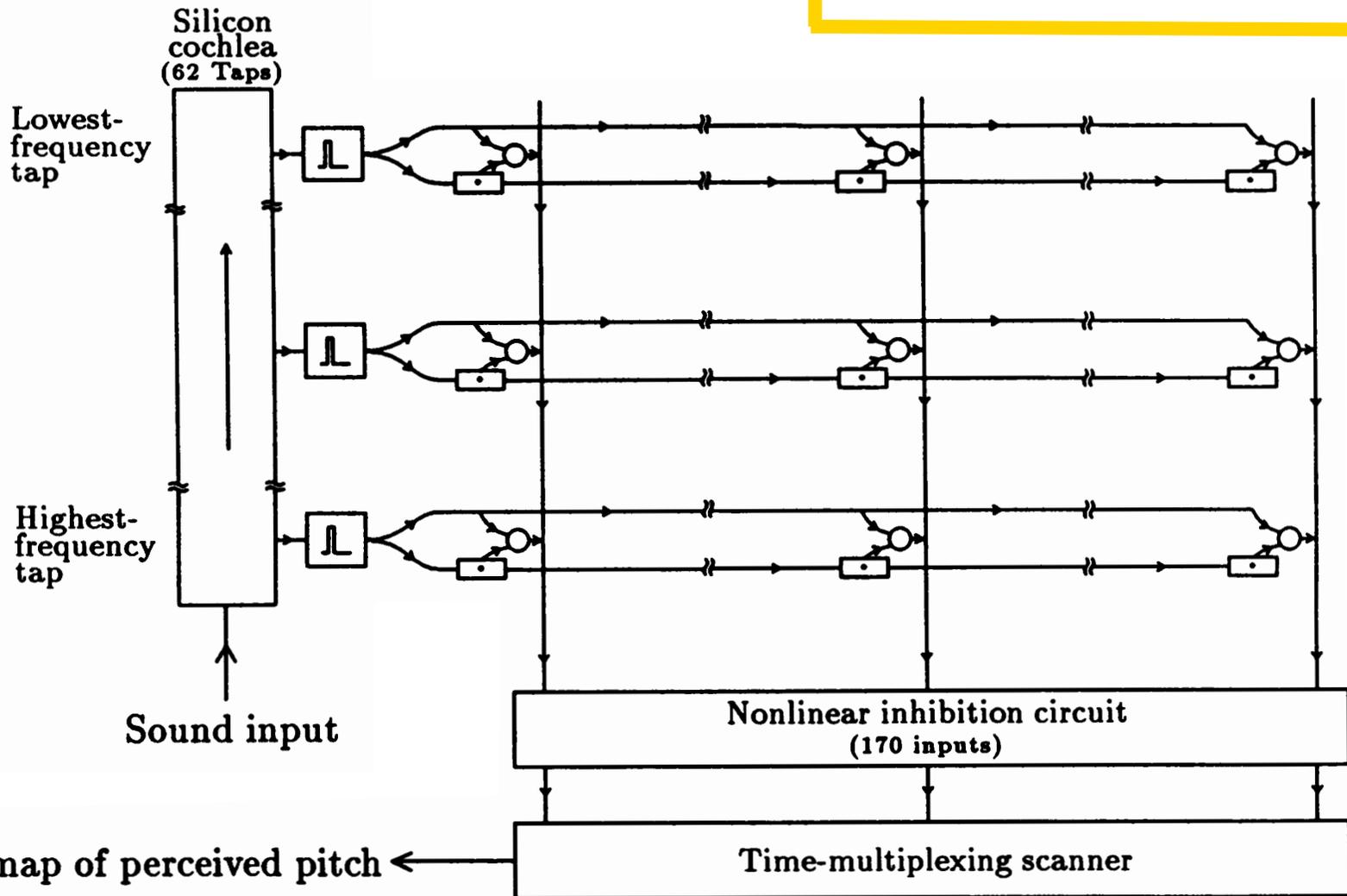
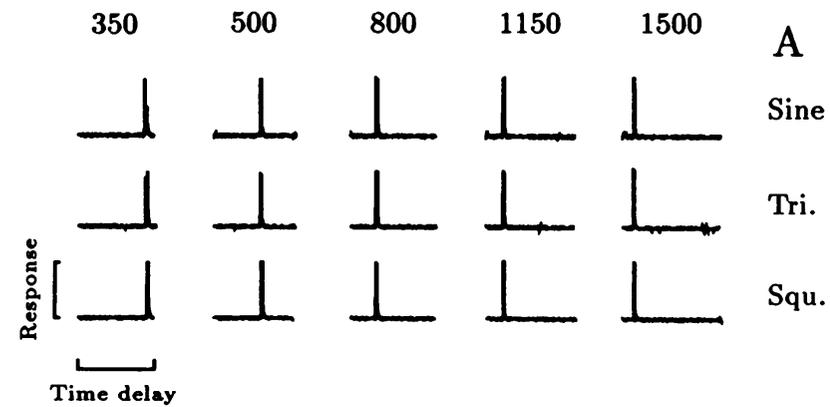
Play.



But bell "chords" often sound **atonal**.

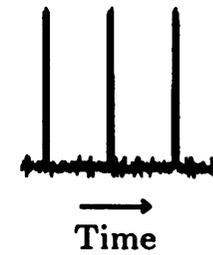
# Licklider Pitch Model

Autocorrelate filtered versions of the audio waveform.

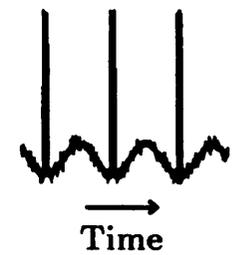


Recall:

First partial not necessary to detect pitch - A and B → are heard with same pitch.



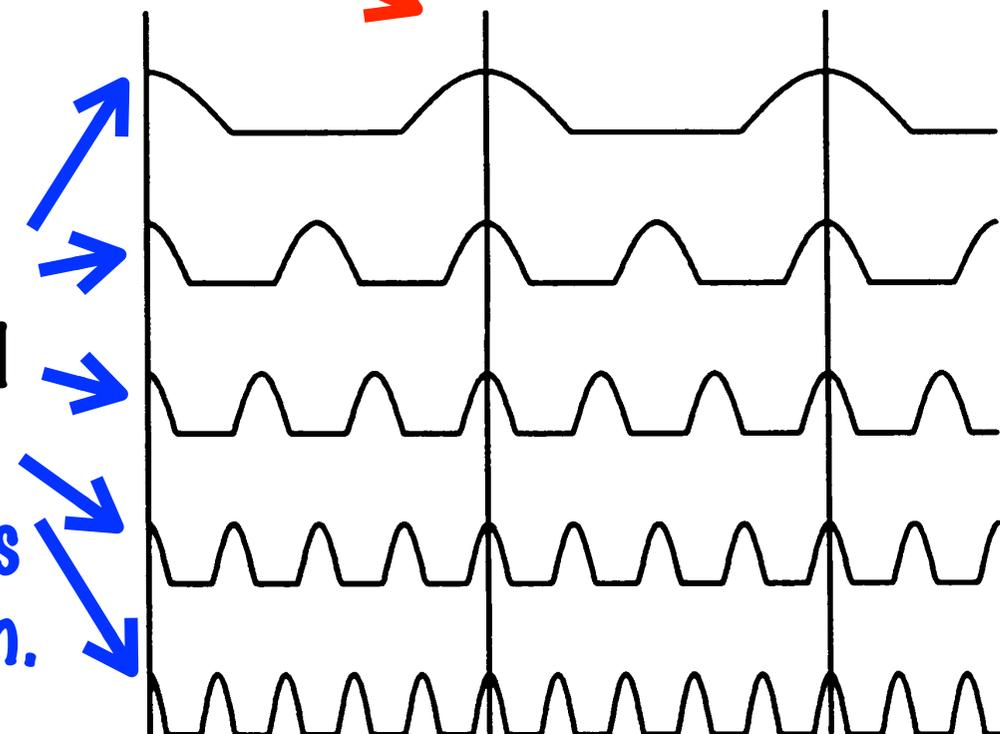
A



B



Relative phases of partials need not be aligned - any phase relation yields a strong pitch.



$f$   
 $2f$   
 $3f$   
 $4f$   
 $5f$

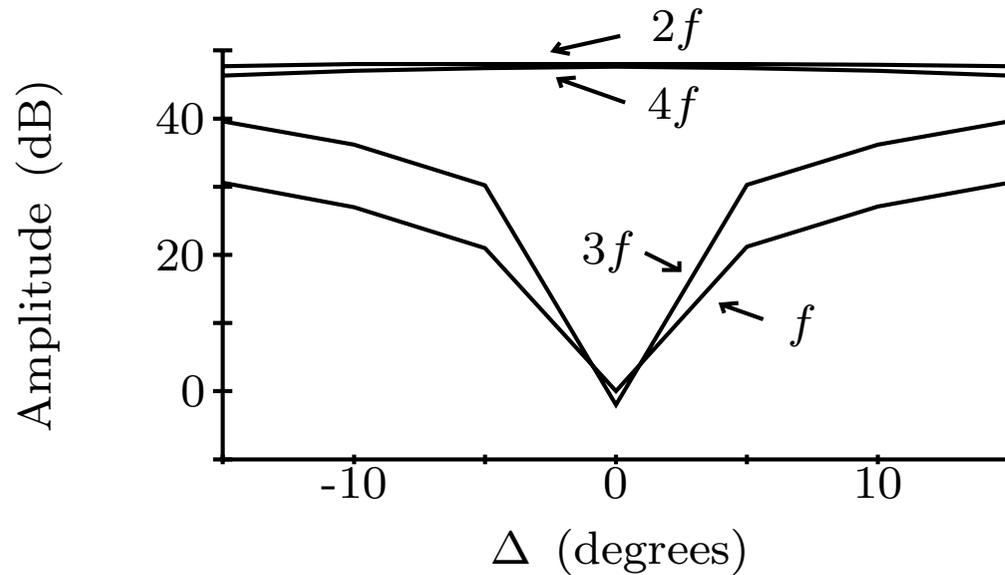
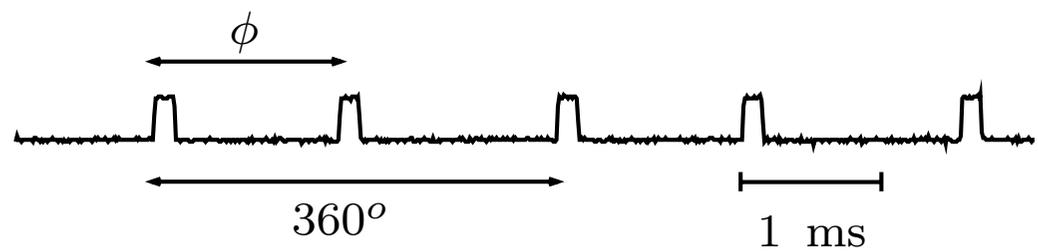
Sounds whose partials are not quite integer-related still yield a sense of pitch -

Autocorrelation model addresses all of these issues.

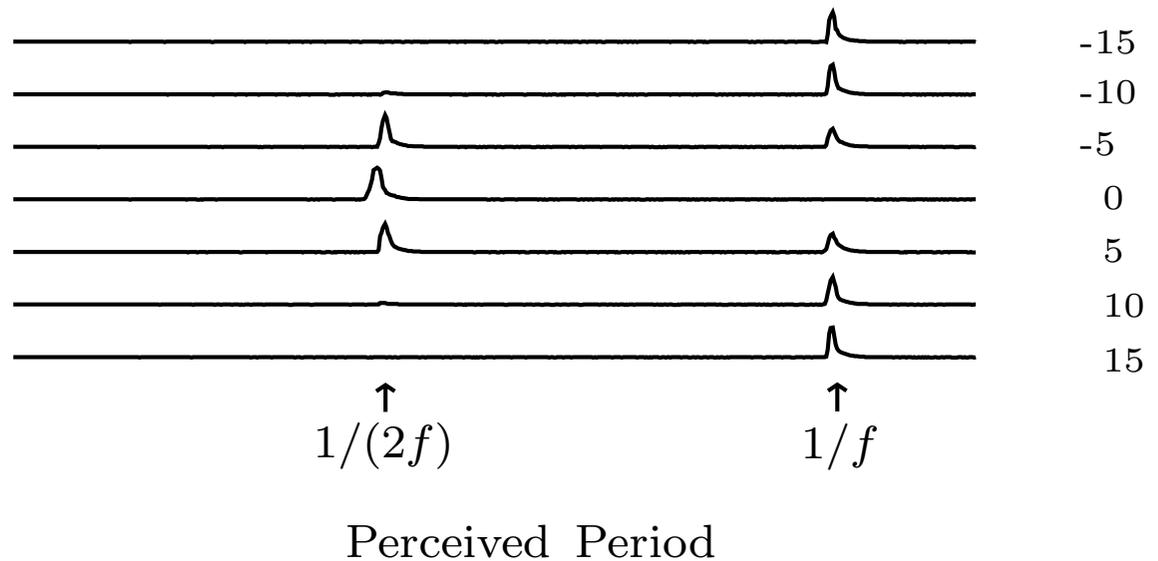
# Seebeck's Siren

When  $\phi$  is offset slightly from  $180^\circ$ , the pitch **drops** one octave. Why? The repetition period of the waveform **doubles**.

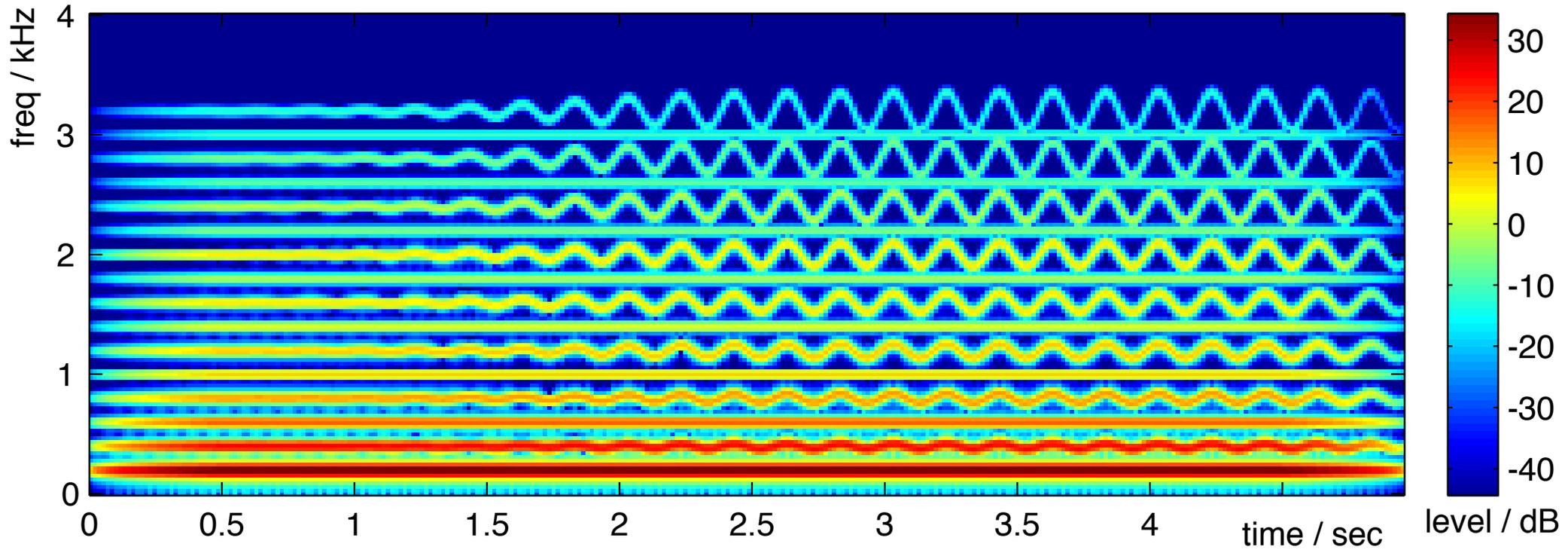
Autocorrelation "hears" this signal the **same way humans do**.



Play.



# Related: Reynolds/McAdams Oboe



Adding vibrato to even partials  
"creates" a second sound  
whose pitch is raised by one  
octave (spectrum by Dan Ellis).

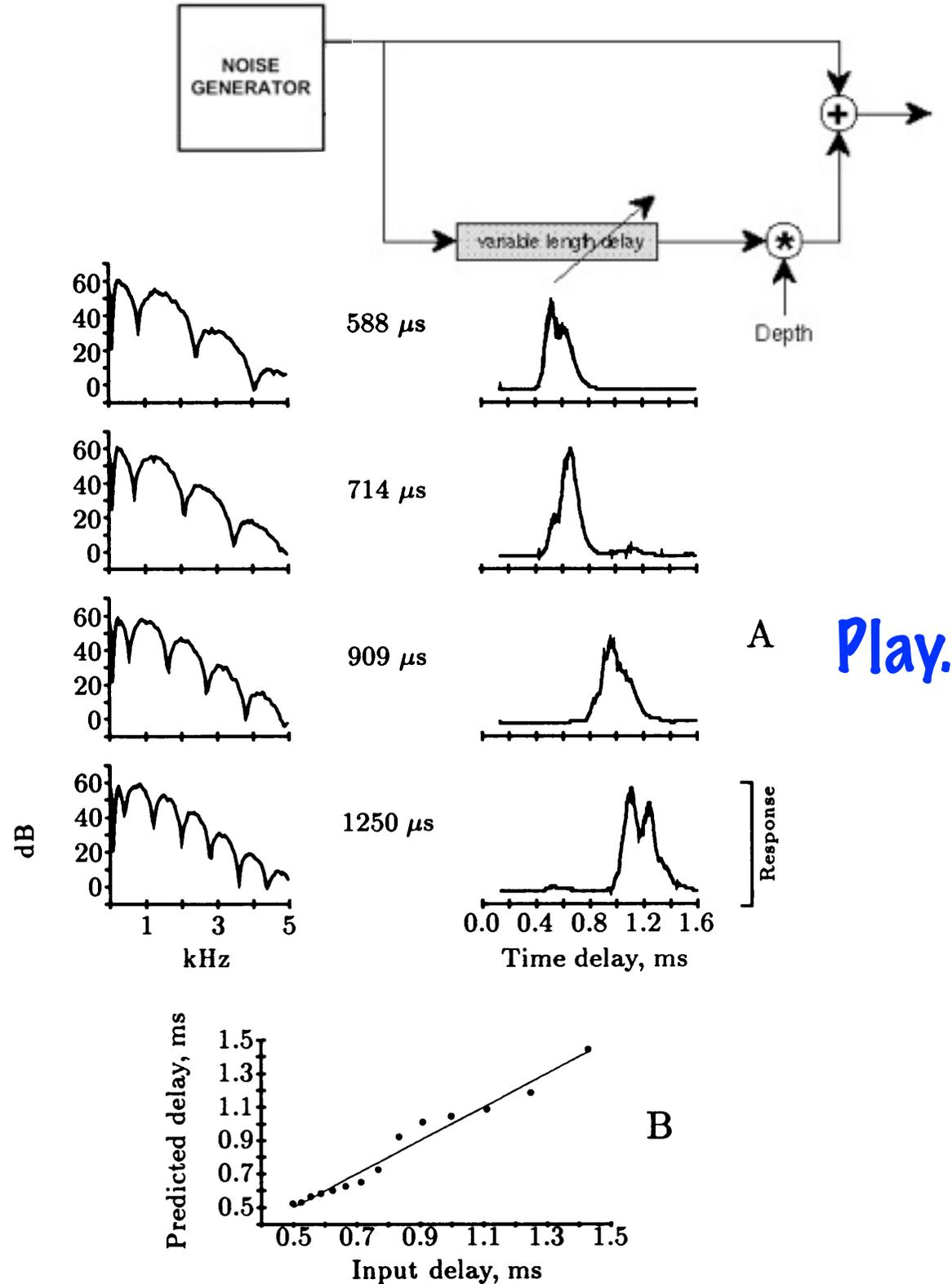
[Play](#)

# Comb-Filtered Noise

We hear a weak pitch in **comb-filtered noise**, corresponding to the period of the comb delay.

This is unusual because the **waveform** of each **period** is **unique**.

Autocorrelation **"hears"** the same pitch humans perceive.



Play.

# Amplitude Modulation

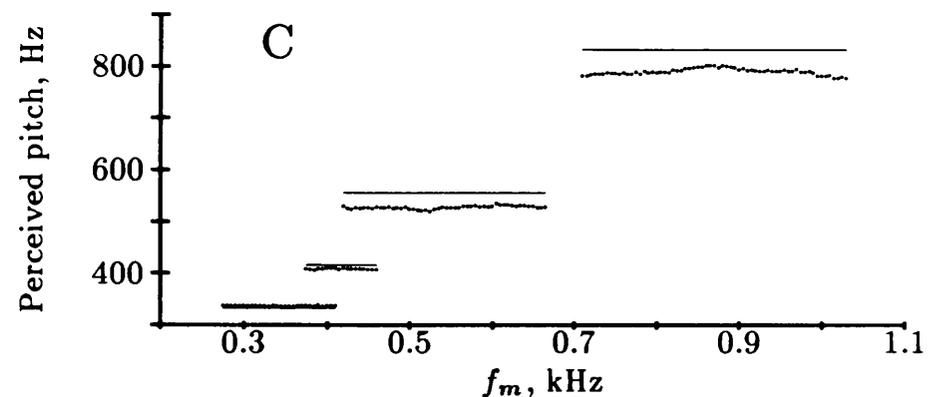
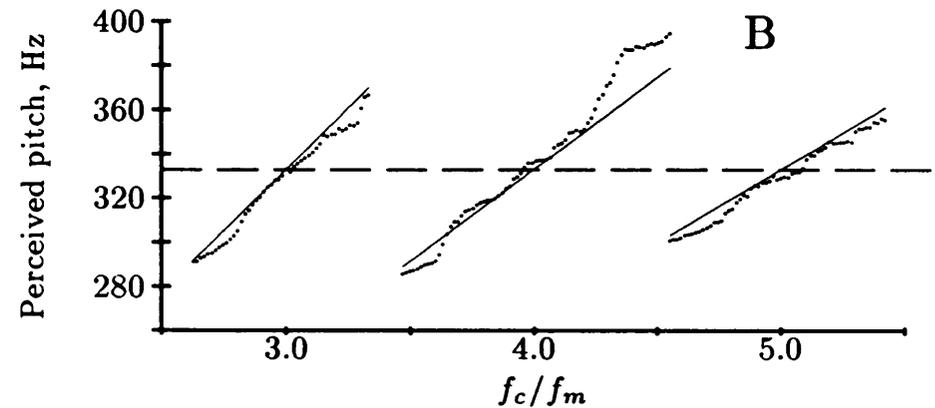
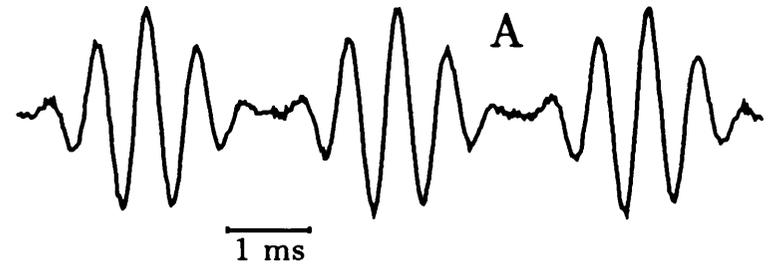
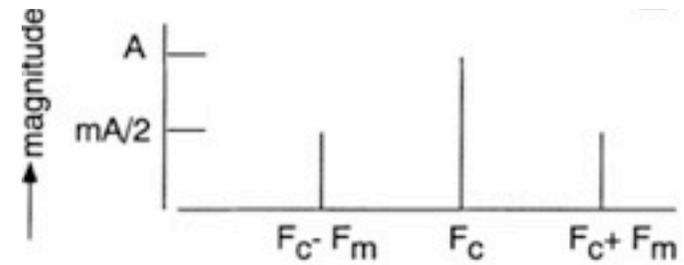
This sound has components at

$F_c - F_m$ ,  $F_c$ , and  $F_c + F_m$ .

To a first order, the pitch we hear is  $F_m$  (the repetition frequency).

Autocorrelation matches this **first-order** result.

But fails on **second-order** phenomena.  
(slope of pitch for small changes in  $F_c$ ,  $F_m$ ).

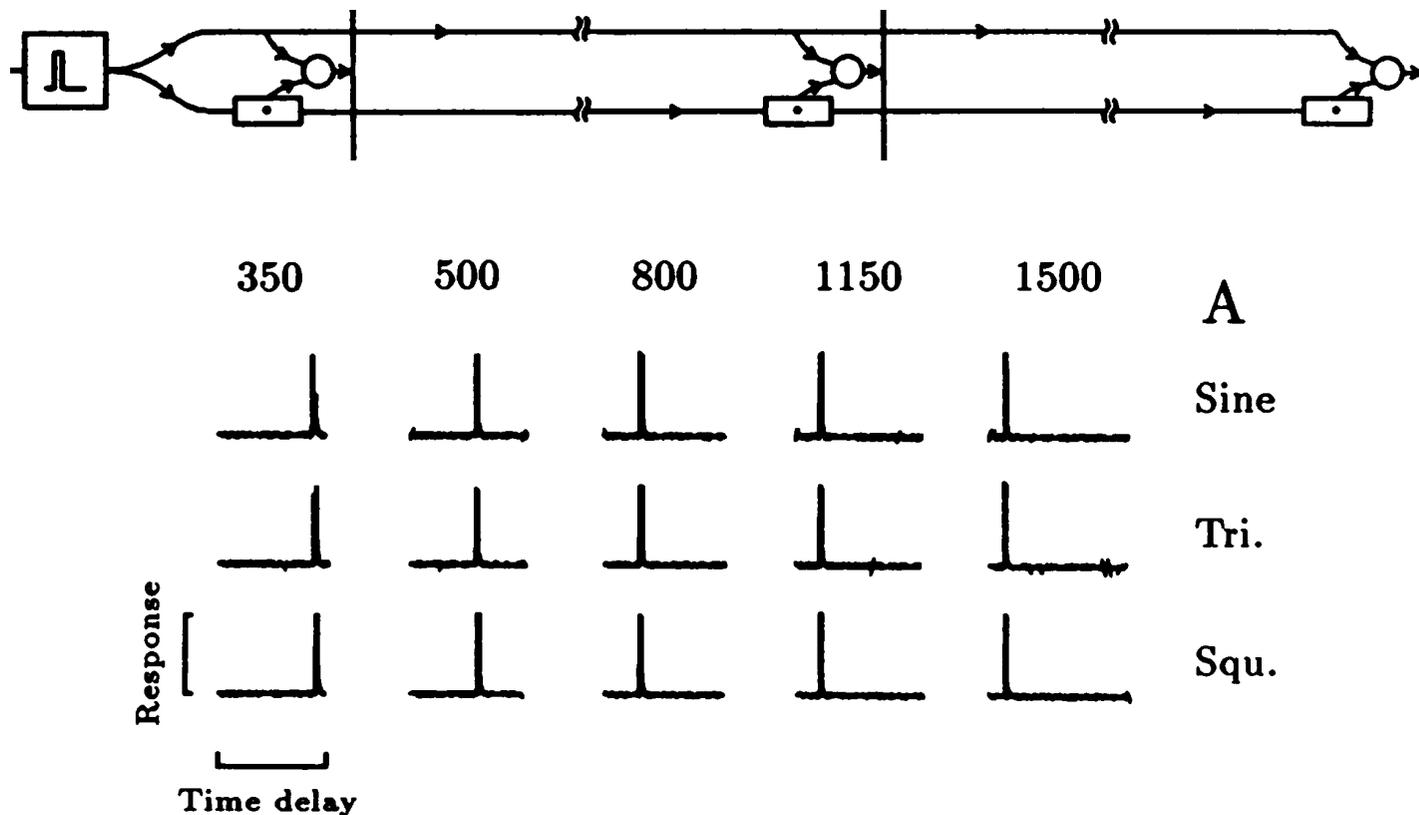


# Today's lecture: Pitch

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- \* **Basic concepts in pitch detection**
- \* **Practical issues in pitch tracking**
- \* **The quiz ...**

Modern engineering pitch trackers are based on **multi-tap autocorrelation** (or similar operators).



Algorithm enhancements mostly take the form of **pre-processing** the audio input or **post-processing** the auto-correlation tap outputs, to better handle the **"difficult"** pitch signals we see in **real-world** engineering applications.

# Real-World Issues

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Dynamic range of pitch

(a)



Pitch variations in time

(b)



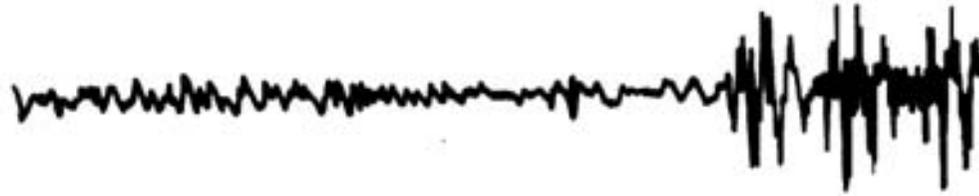
Vocal tract variations in time

(c)

10 ms

# Real-World Issues

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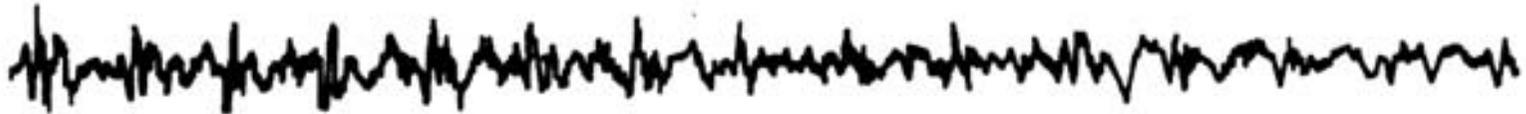
Voiced-unvoiced transition

(*d*)



Telephone speech

(*e*)

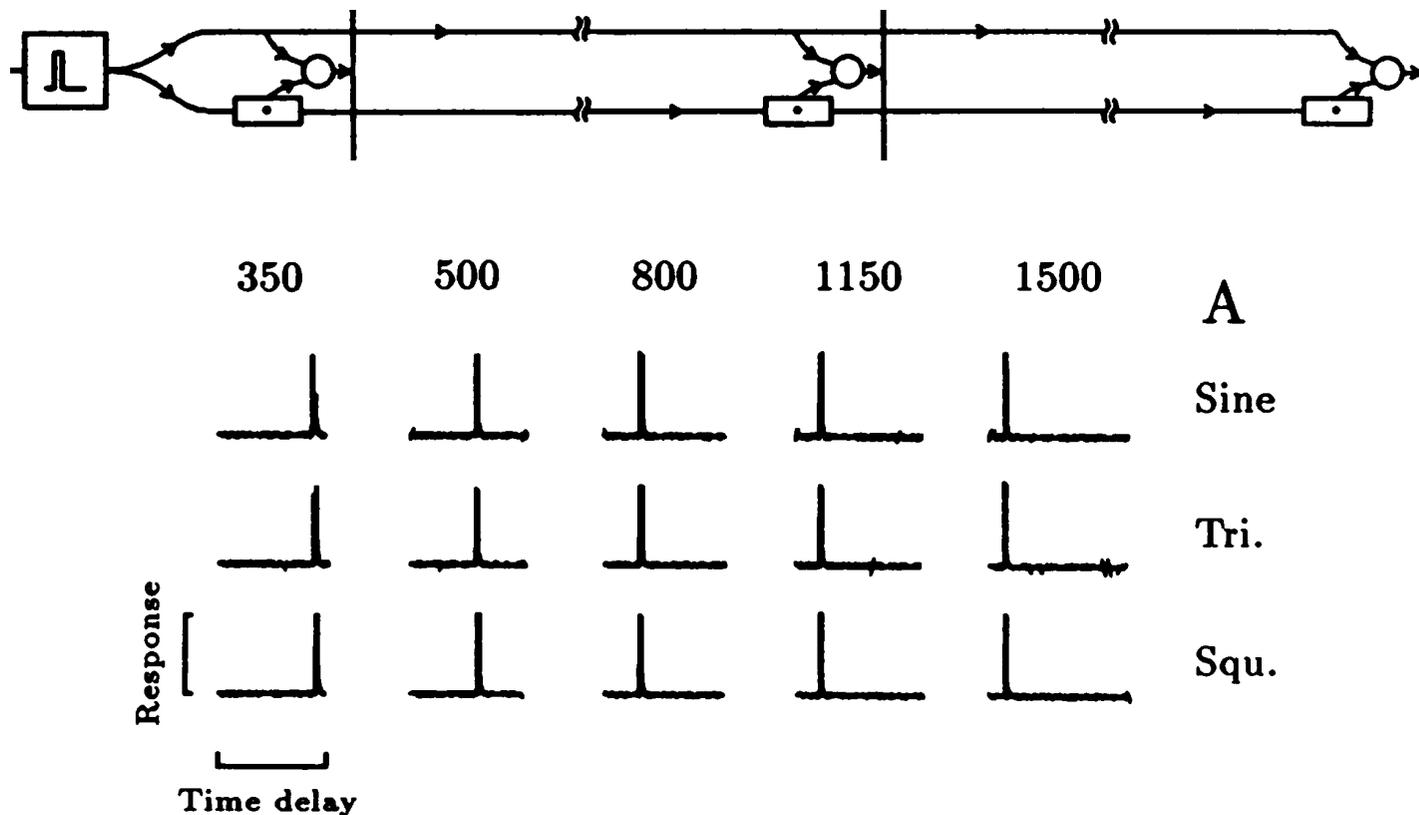


Acoustic noise background

(*f*)

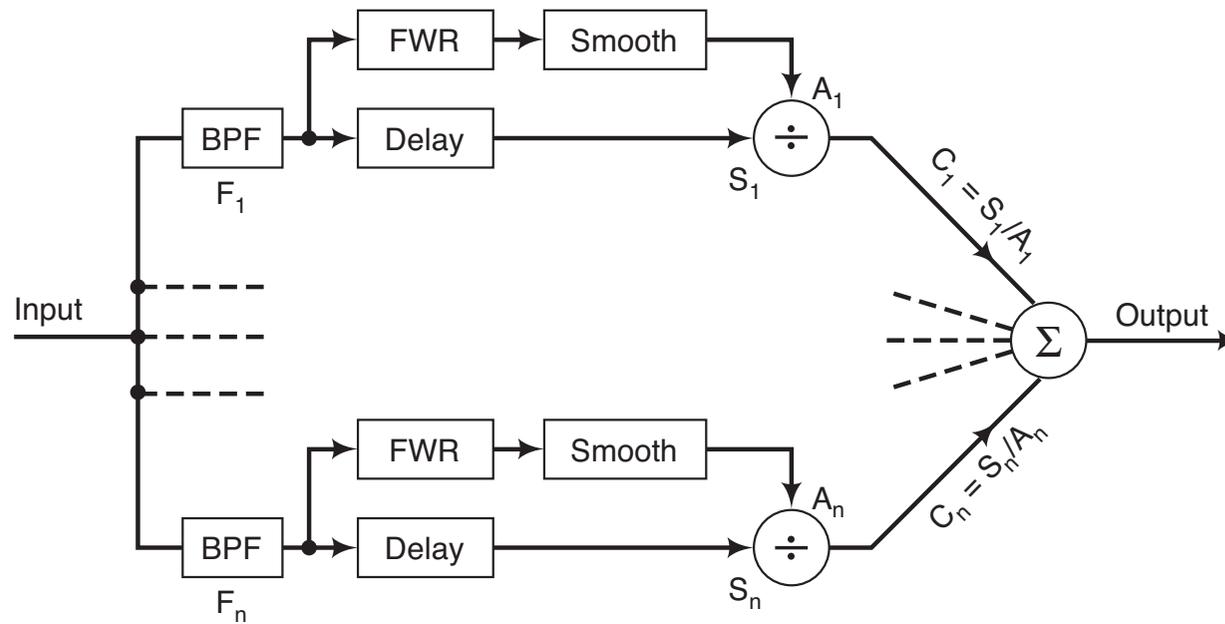
10 ms

Modern engineering pitch trackers are based on **multi-tap autocorrelation** (or similar operators).



Algorithm enhancements mostly take the form of **pre-processing** the audio input or **post-processing** the auto-correlation tap outputs, to better handle the "difficult" pitch signals we see in **real-world** engineering applications.

# Pre-Processing : Spectral Flattening

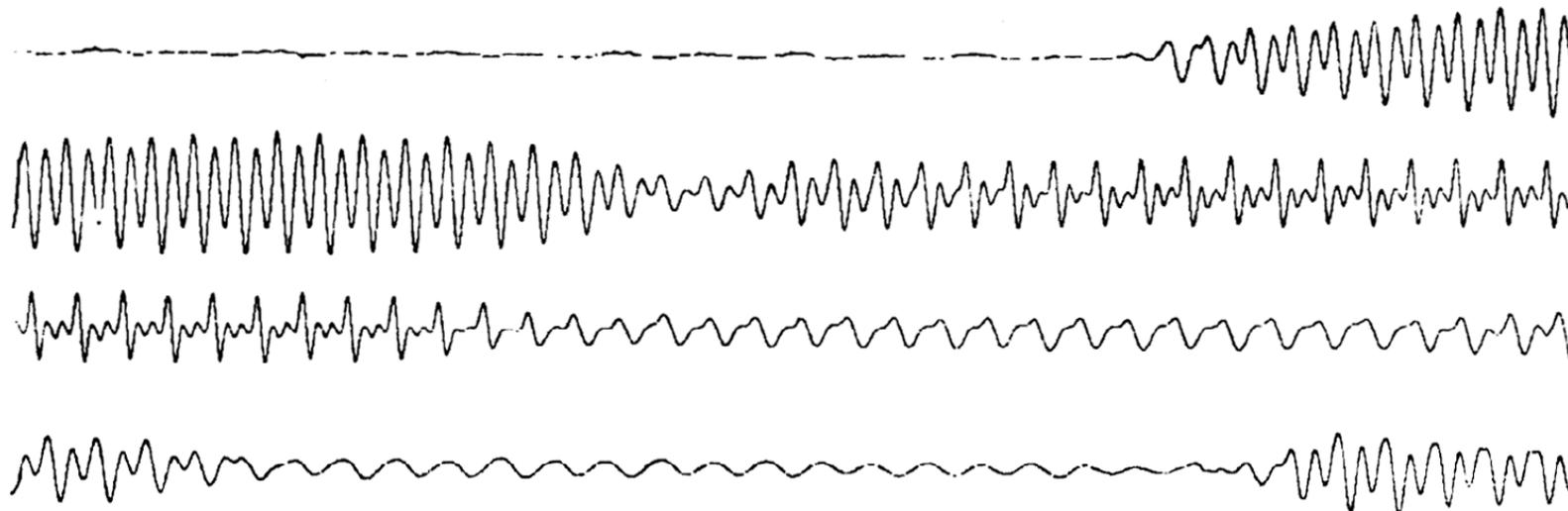


# Pre-Processing : Low-pass Filtering

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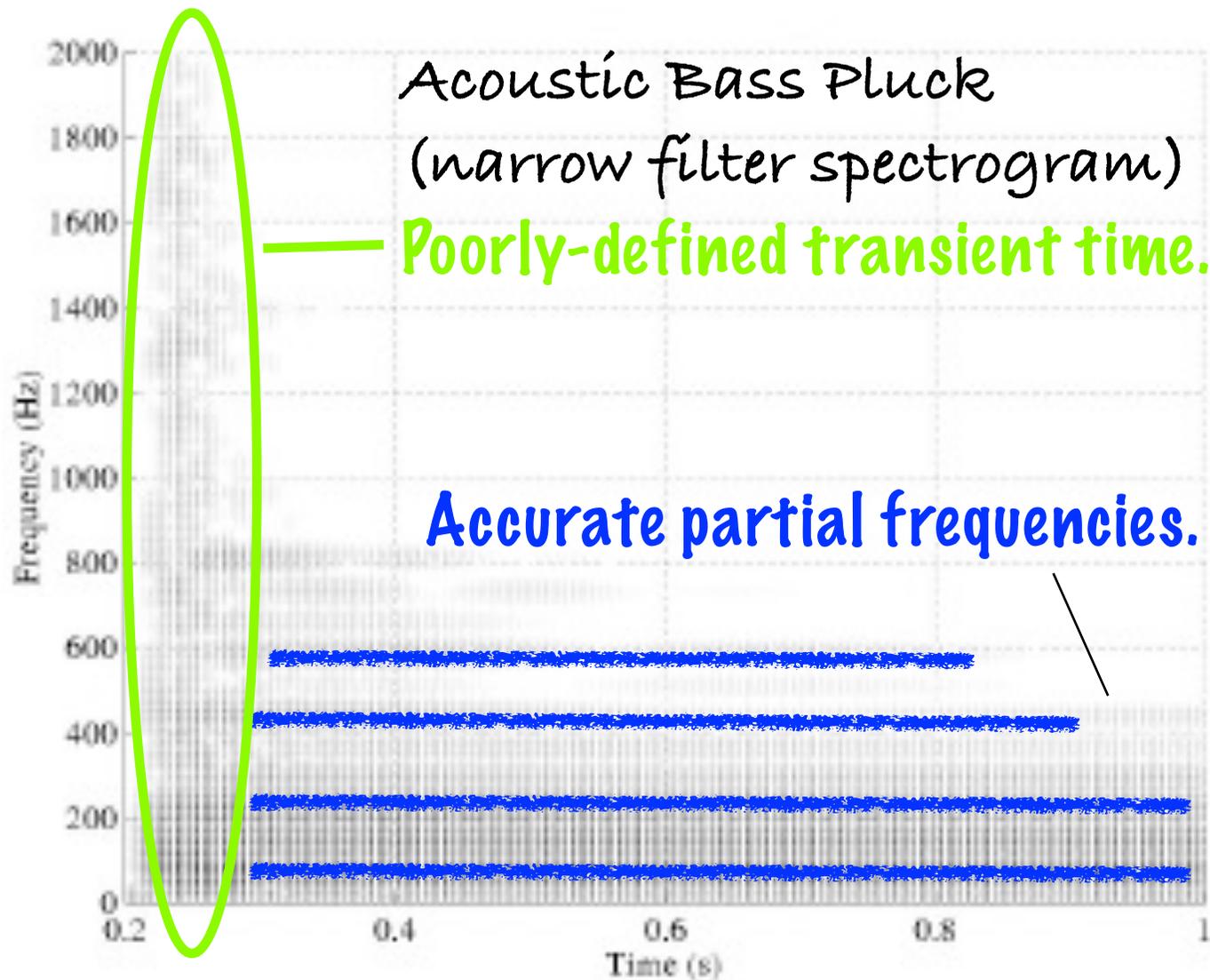
**FIGURE 31.5** Full-band speech signal.



**FIGURE 31.6** Low-pass filtered speech signal.

# Time/Frequency Tradeoffs

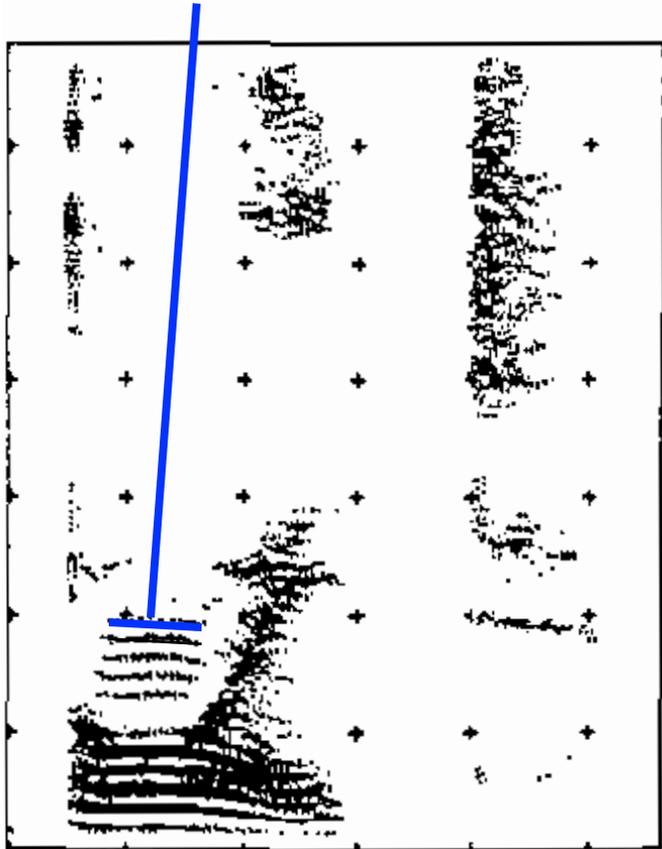
**Narrow linear filters are slow**  
**Fast linear filters are wide**



# Filters: Wide vs Narrow

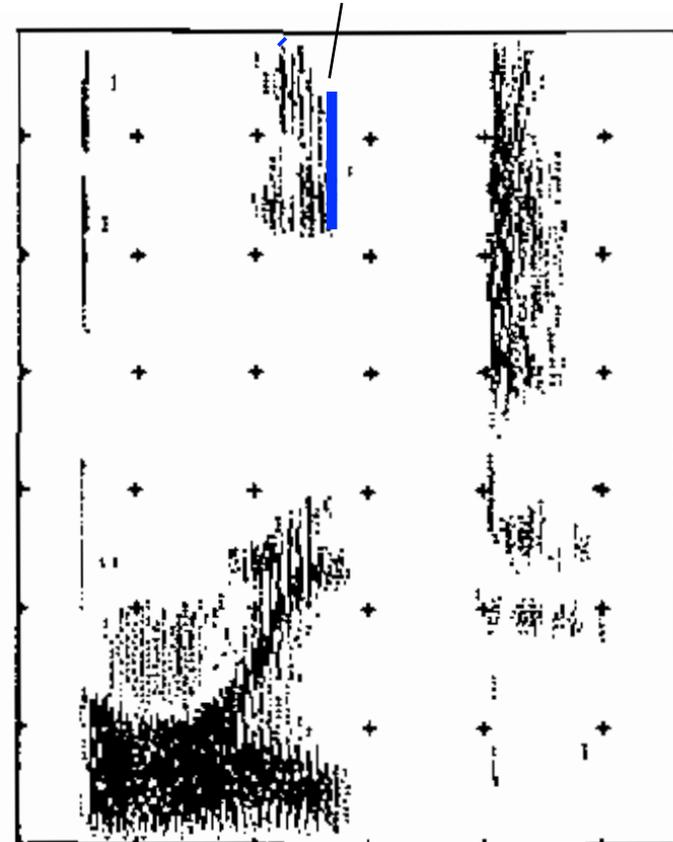
Spoken word "boyt"  
processed by **two**  
filterbanks.

Accurate pitch harmonics.



Narrow filters

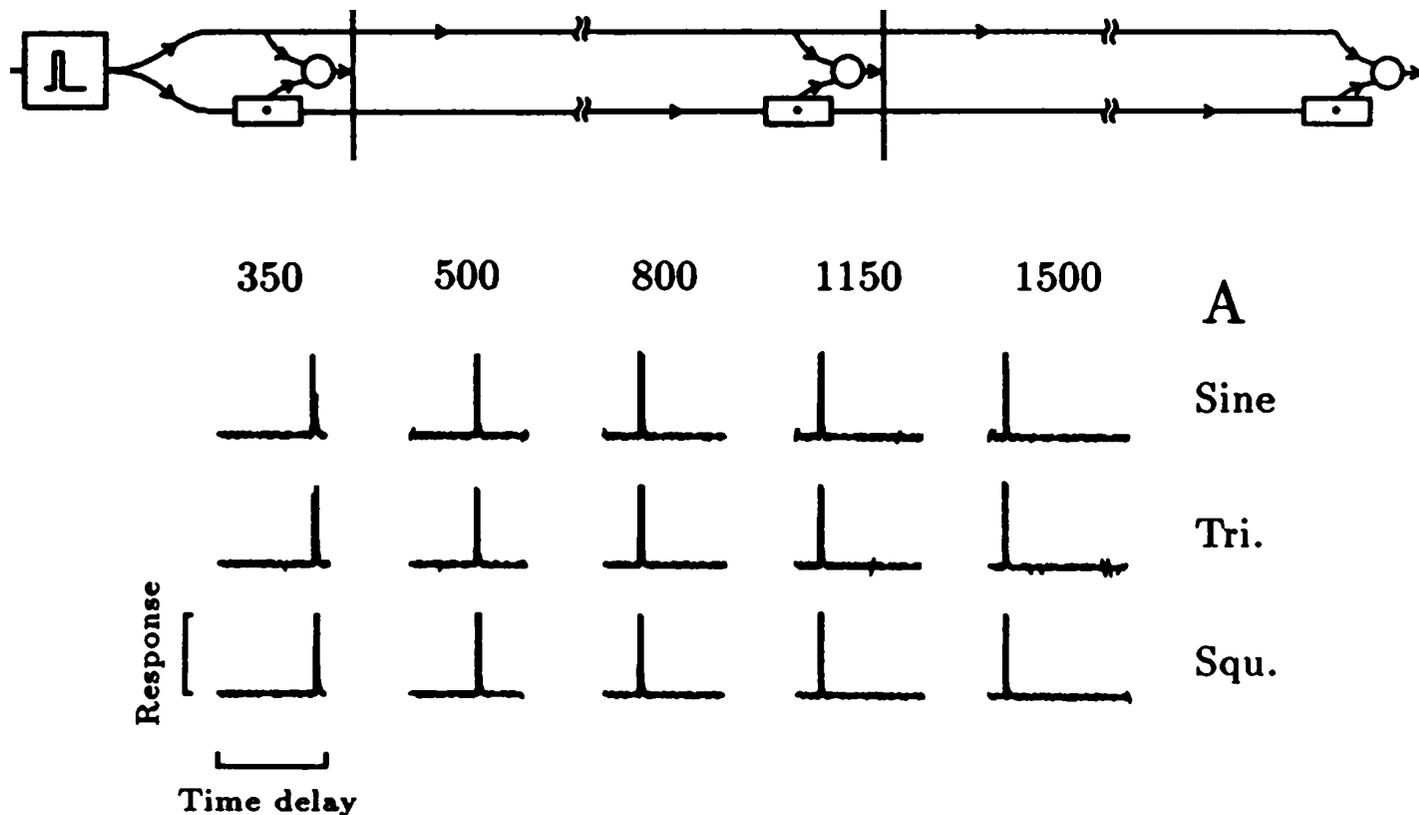
Good glottal pulse timing.



Fast filters

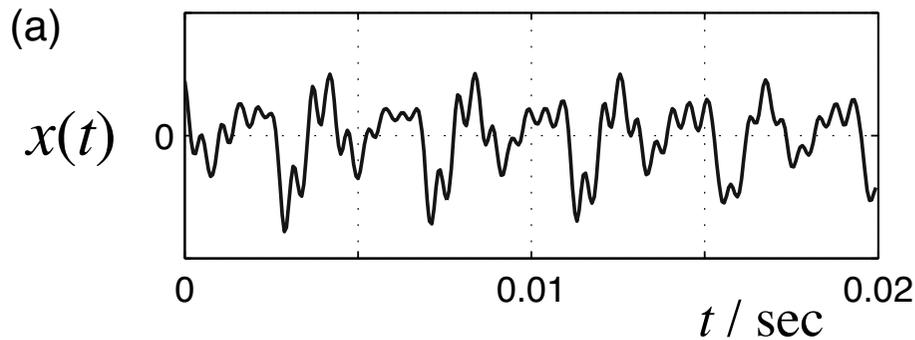
Data from Hong Leung and Victor Zue

Modern engineering pitch trackers are based on **multi-tap autocorrelation** (or similar operators).

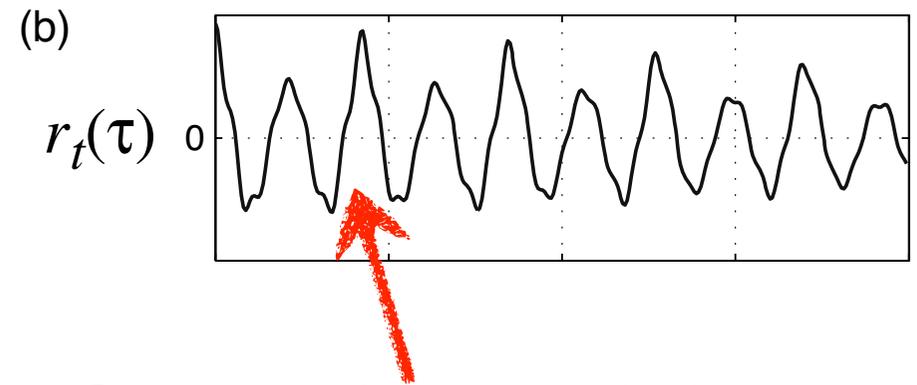


Algorithm enhancements mostly take the form of **pre-processing** the audio input or **post-processing** the auto-correlation tap outputs, to better handle the "difficult" pitch signals we see in **real-world** engineering applications.

# Post-Processing : Yin Normalization

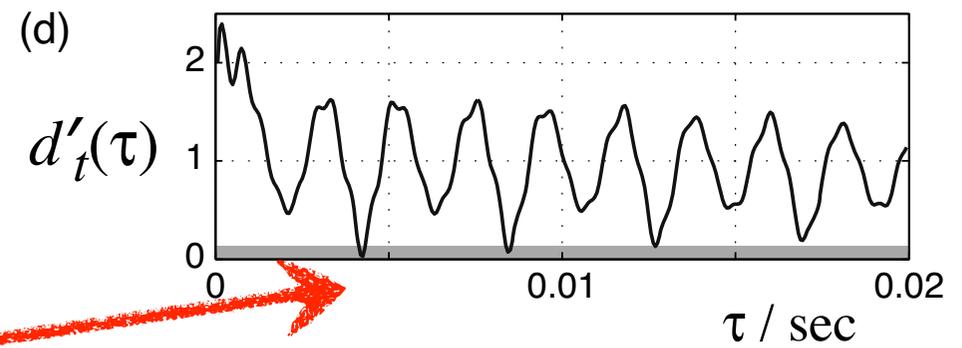


Female voiced speech,  
time domain waveform



Raw autocorrelation.  
Requires "peak" picking.

Yin normalization:  
autocorrelation peaks  
fall in a small  
threshold around "0"



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