An Edinburgh Speech Production Facility

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3.1 Sensor Positions

Sensors were attached behind the ears, to the bridge of the nose, to the upper jaw, lower jaw, upper lip, lower lip, tongue front, tongue mid and tongue back.

3.2 Speech Styles

Dialogue

Story reading (Connu Gets a Cure, McCaugh, Sommerville & Honnold, 2000). Well-stated lexical sets, spontaneous story telling, dichotomous tasks

Map tasks (Anderson et al., 1991). Spot the Difference picture tasks (Bradlow et al., 2007). Story-recall

Shadowing

One participant tells a familiar story, the other shadows.

3.3 Annotation

Annotation files include orthographic transcription and long pauses. Disfluency annotation is in preparation, and we are developing a guide for prosodic labeling (simplified ToBI).

4.4 Data Preview

The facility is designed for the collection of articulatory and acoustic data from two synchronised dialogue participants, or single speakers. It will be open to the international research community for funded use as of September, 2010. Services will include data collection (preparation, sensor attachment, and recording), sensor position estimation at each sample point, head movement correction, synchronization (articulation to acoustics, speaker to speaker), and data archiving. The first product of the facility is a corpus of recorded dialogue, also available in September, 2010.

2 The Facility

The facility is built around two Carstens' AG950 electromagnetic articulographs (EMA) and acoustic recording equipment (see Fig. 1). EMA recordings provide detailed information about speech movements. Each machine records 3D positions and rotations of 12 sensors every 5 ms. These sensors can be glued anywhere on the lips, tongue, jaw, and head. Acoustic recordings are made via an AKG CK98 hypercardioid mic, sampling rate 32 kHz, bit rate 16. The EMA machines are positioned 8.5 m apart to avoid electromagnetics inter-machine interference. Communication among participants and experimenters is regulated via a talkback system (see Fig. 2).

2.1 Synchronization

Synchronization of both EMA data sources and the acoustic waveforms of both speakers is achieved by capturing synch impulses of both machines and (b) the acoustic waveforms of both speakers by means of Articulate Instruments Ltd. hardware. After correcting for TCP-IP inter-machine communication delays, our inter-machine asynchrony of Articulate Instruments Ltd. hardware is less than 1 ms. The hardware is also capable of synchronizing inter-machine communication delays, our inter-machine asynchrony of Articulate Instruments Ltd. hardware.

2.2 Data Accuracy

Position-estimation procedures include those described in Hauke & Zünk (in press) (TAPAD) and unscented Kalman filtering-based algorithms, developed by K. Richmond. Analyses for rigid body sensors suggest that accuracy is within 1 mm (see Fig. 3). Data accuracy for non-rigid body sensors is assumed by comparing position results from TAPAD vs. Kalman filtering methods (cf. Fig. 3).

2.3 Data Analysis

Data analysis software (Articulate Assistant, Advancement, EMA mobile) has been commissioned from Articulate Instruments Ltd. (2009). This software allows data visualisation, annotation and measurement extraction. It is user-friendly and does not require programming skills. The user interface provides a common platform for EMA, EPG and Ultrasound data. Analysts need only master one piece of software for all three techniques, and can transfer annotations between them.

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3 The Dialogue Corpus

So far, we have recorded 9 dual participant sessions primarily between Scottish and Southern British English speaking participants. Each session involves synchronized recordings of both EMA and acoustic data, and includes 30-60 minutes of speech. The corpus will be available in Sept. 2010 via a web-based, searchable archive system.

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Acknowledgements

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