Applied Soft Computing 15 (2014) 80–87

Contents lists available at ScienceDirect

Applied Soft Computing

journal homepage: www.elsevier.com/locate/asoc

Nonlinear feedback active noise control for broadband chaotic noise

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ARTICLE INFO

Article history:
Received 4 March 2013
Received in revised form 24 October 2013
Accepted 27 October 2013
Available online 4 November 2013

Keywords:
Active noise control
Feedback ANC
FLANN
Chaotic noise

ABSTRACT

Feedback active noise control has been used for tonal noise only and it is impractical for broadband noise. In this paper, it has been proposed that the feedback ANC algorithm can be applied to a broadband noise if the noise characteristic is chaotic in nature. Chaotic noise is neither tonal nor random; it is broadband and nonlinearly predictable. It is generated from dynamic sources such as fans, airfoils, etc. Therefore, a nonlinear controller using a functional link artificial neural network is proposed in a feedback configuration to control chaotic noise. A series of synthetic chaotic noise is generated for performance evaluation of the algorithm. It is shown that the proposed nonlinear controller is capable to control the broadband chaotic noise using feedback ANC which uses only one microphone whereas the conventional filtered-X least mean square (FXLMS) algorithm is incapable for controlling this type of noise.

1. Introduction

Active noise control (ANC) [1–3] is becoming an interesting research topic for the past few decades due to the concern on the adverse effect of acoustic noise due to the rapid growth of population and machineries. Passive noise control techniques work well at high frequencies, but are ineffective or impractical at low frequencies. The ANC is an alternative, wherein an anti-noise is generated to kill the undesired noise by using the principle of destructive interference. The controller of the ANC systems can be either non-adaptive or adaptive depending on the properties of the noise field. The amplitude and frequency of the unwanted noise does not remain constant in practical situations. The noise may distort with the change in the environmental conditions like pressure, temperature and component aging, etc. Therefore, for the effectiveness of the ANC system to these changed conditions, the controller needs to be adaptive. The ANC system is further classified as feedforward and feedback depending upon the availability of the coherent reference input. In feedforward ANC systems, the reference input is provided by a reference microphone. But in feedback ANC, there is no reference microphone and the reference input is estimated from the error microphone signal. The drawback of the feedforward ANC system is that because of the presence of the reference microphone, the secondary source (loudspeaker) output may get feedback to the reference microphone signal and it may degrade the performance of the ANC system. But since there is no reference microphone in feedback ANC, there is no such feedback of the secondary source output. Another drawback of the feedforward ANC system is that, if there are multiple noise sources, then multiple reference microphones are required to provide multiple reference inputs and multiple adaptive filters are required for the adaptation purpose of each input. So in such cases, the system becomes complicated and also costly. But in feedback ANC system, there is no reference microphone, and hence only one adaptive filter is required. Therefore, it is computationally efficient and economical for multiple references.

Feedback ANC is mainly used for predictable noise which is tonal [4–6] and it cannot be used for random broadband noise. However, another type of noise which is called chaotic noise has gained importance these days. No work has been reported as yet where feedback ANC is used for controlling chaotic noise which is broadband in nature. The chaotic noise is a nonlinear deterministic noise and is generated from dynamic systems such as fans, blowers, grinders and airfoils, etc. [7–14]. Furthermore, the secondary path, which is the path from the output of the controller till the error microphone input, shows non-minimum phase response. This imposes the ANC to act as a predictor. This is because, the secondary path is placed after ANC block and hence ANC ultimately has to model the inverse of the secondary path. If the secondary path is non-minimum phase, whose inverse does not exist, but a causal inverse exists, forces the ANC to be predictable. Therefore, a chaotic noise which is nonlinearly predictable noise can be controlled by a nonlinear controller. Conventional ANC systems with linear controller using filtered-x least mean square (FXLMS) algorithm provides poor performance, and sometimes even fail to control such type of noise. Therefore, for the mitigation of chaotic noise, nonlinear controllers are employed which provide better

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http://dx.doi.org/10.1016/j.asoc.2013.10.025

result than that obtained with linear controllers. Researchers have proposed various nonlinear controllers such as radial basis function neural network [7], artificial neural networks (ANN) [8–11], functional link artificial neural networks (FLANN) based on trigonometric [13,16–18] or piecewise linear functional expansions [15], functional link neural networks (FLNN) [20] and adaptive Volterra filters [12], bilinear filter [21], etc. ANC systems with the FLANN using filtered-s least mean square (FSLMS) algorithms are more advantageous than the ANC systems using Volterra filtered-x least mean square (VFXLMS) algorithms because of their better performance and less computational complexity. However, the ANC systems developed with these nonlinear controllers are feedforward systems with logistic chaotic noise as the input signal.

Behavior of acoustic noise as chaotic has been studied in many papers. Few of them are cited here. Sound generated aerodynamically has chaotic property which has been shown in [22]. Frequency spectra of acoustic ambient noise in ocean and their sources are shown in [23]. Acoustic chaos and nonlinear dynamics have been investigated in [24–26]. Results of experimental investigation of chaotic sound waves are shown in [27]. Control of chaotic motion of a airfoil is presented in [28]. In [29], numerical study of sound emission by 2D regular and chaotic vortex configurations has been made. Study of wave chaos in acoustics and elasticity is presented in [30].

It is apparent from the literature survey that the acoustic/sound waves can be chaotic which means these may be nonlinearly deterministic. Therefore, there is a need of actively controlling these noise and hence in this paper, a feedback ANC system is proposed based on the FSLMS algorithm for controlling nonlinear noise process i.e. logistic chaotic noise. In addition, a series of modified logistic chaotic noises are generated for the simulation study with the proposed algorithm. For every type of noise, the response of the proposed algorithm is compared to the FXLMS based one.

Organization of the paper is as follows. Section 2 presents the mathematical formulation of a series of modified logistic chaotic noises and their characterization. The proposed nonlinear control algorithms are presented in Section 3. Section 4 deals with the exhaustive computer simulation. Section 5 concludes the paper.

2. Chaotic noise

Chaotic signal has been an important topic of research these days in communication engineering. As chaotic signals are typically broadband, random-like and difficult to predict, they are utilized for masking information-bearing waveforms such as modulating waveforms in spread spectrums systems. However, the acoustic noise generated from dynamic systems can also be chaotic in nature. It has been shown in [7,11–13,19] that noise generating from fans, airfoils, etc. are chaotic in nature. In all these papers, the logistic chaotic noise has been used for evaluating the performance of their nonlinear controllers. The equation representing the logistic chaotic noise [13] is as follows

$$x(n) = \lambda x(n-1)[1 - x(n-1)] \tag{1}$$

with $\lambda = 4$ and $x(0) = 0.9$, $n = 1, 2, 3, \ldots$

In this noise, the next state depends only on its present state. The sequence generated from Eq. (1) is named as logistic chaotic noise 1. Therefore, a one step predictor can predict the noise. However, there may be cases where the next state depends on the past states. Accordingly, Eq. (1) is modified to generate various other types of noise series.

For example:

The equation representing the modified logistic chaotic noise 2 is

$$x(n) = \lambda x(n-2)[1 - x(n-2)], \quad n = 2, 3, 4, \ldots \tag{2}$$

with $\lambda = 4$, and $x(n) = 0.9$, *if* $0 \le n \le 1$.

The equation representing the modified logistic chaotic noise 3 is

$$x(n) = \lambda x(n-3)[1 - x(n-3)], \quad n = 3, 4, 5, \ldots \tag{3}$$

with $\lambda = 4$, and $x(n) = 0.9$, *if* $0 \le n \le 2$.

The equation representing the modified logistic chaotic noise 4 is

$$x(n) = \lambda x(n-4)[1 - x(n-4)], \quad n = 4, 5, 6, \ldots \tag{4}$$

with $\lambda = 4$, and $x(n) = 0.9$, *if* $0 \le n \le 3$.

The equation representing the modified logistic chaotic noise 5 is

$$x(n) = \lambda x(n-5)[1 - x(n-5)], \quad n = 5, 6, 7, \ldots \tag{5}$$

with $\lambda = 4$, and $x(n) = 0.9$, *if* $0 \le n \le 4$.

The equation representing the modified logistic chaotic noise 6 is

$$x(n) = \lambda x(n-6)[1 - x(n-6)], \quad n = 6, 7, 8, \ldots \tag{6}$$

with $\lambda = 4$, and $x(n) = 0.9$, *if* $0 \le n \le 5$.

For comparison purpose, the tonal noise is generated by the equation

$$x(n) = \sin\left(\frac{2\pi f n}{f_s}\right) \tag{7}$$

where $f = 500$ Hz and the sampling frequency $f_s = 10,000$ Hz.

And the uniform random noise is generated between −0.5 and 0.5 using Matlab function

$$x(n) = (rand - 0.5) \tag{8}$$

2.1. Properties

Phase plots: To analyze the chaoticness of the signals, the phase plots of the logistic chaotic noise 1 and its modified versions are plotted in Fig. 1 where the sample $x(n)$ is plotted against the delayed sample $x(n-1)$. Fig. 2(a) and (b) represents the phase plots of tonal and random noise respectively for comparison purpose.

From Fig. 1, it is seen that the phase plot of the logistic chaotic noise 1 has dense periodic orbits which means the points on the orbit are approached randomly. This also indicates that, a chaotic noise has a set of stable states, but these states are not periodically repeated as is seen in tonal noise case. But random signal doesn't display any such periodic orbits in the phase plot as shown in Fig. 2(b) where the points on the phase plot are scattered and don't form any particular pattern. The phase plot of tonal noise has an orbit. But the points on the phase plot of tonal noise are approached sequentially on the same orbit, which means they are neither random nor chaotic. Therefore, from the above discussion, it is clear that for a signal to be chaotic, the points on the phase space should lie within a particular pattern, i.e. they are neither randomly nor sequentially approached. The phase plots of the modified versions of the logistic chaotic noise 1 contain square, rectangular and parabolic patterns and are thus chaotic.

Time domain: In time domain all these noises are plotted for 10 samples in Fig. 3 to see their stable states. It is found that in case of original logistic chaotic noise 1, there is no repetition in consecutive samples, where as the dependence with the delayed sample increases as the consecutive samples are repeated in the chaotic noises 2–6. This may be treated as sampling the same steady state at a higher sampling rate. However, better chaotic noise can be derived which would not have these repetitions. This is kept for the scope of the future research.

Frequency content: All these above chaotic noises are plotted in frequency domain using Welch power spectral density