LOCATA

IEEE-AASP Challenge on Acoustic Source Localization and Tracking

- Documentation of Final Release -

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`www.locata-challenge.org`

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Abstract

The challenge of sound source localization and tracking in realistic environments has attracted widespread attention in the Audio and Acoustic Signal Processing (AASP) community in recent years and lead to the publication of numerous algorithms. The aim of the IEEE-AASP challenge on acoustic source *LOCalization And TrAcking* (LOCATA) was to conduct for the first time an objective benchmarking campaign of state-of-the-art algorithms using a data corpus with real-life recordings for various scenarios. Another main goal was to provide researchers in acoustic source localization and tracking with a common, publicly released data corpus and a corresponding framework to objectively benchmark their results against competing algorithms. This document describes the final release of the datasets and MATLAB programs created for these purposes.

1 The LOCATA Challenge

The substantial interest in sound source localization and tracking approaches has motivated the IEEE-AASP challenge on acoustic source *LOCalization And TrAcking* (LOCATA). Its aim was to conduct an objective benchmarking campaign of state-of-the-art algorithm for acoustic source localization and tracking. The LOCATA data corpus created for this challenge includes real-life recordings for a range of scenarios, like a single or multiple sound sources

which are either fixed or moving, with ground-truth data of the positional information of the sources and sensors.

The IEEE-AASP LOCATA Challenge has offered the following six tasks [1]:

Task 1: Localization of a single, static loudspeaker using static microphone arrays

Task 2: Localization of multiple static loudspeakers using static microphone arrays

Task 3: Tracking of a single, moving talker using static microphone arrays

Task 4: Tracking of multiple, moving talkers using static microphone arrays

Task 5: Tracking of a single, moving talker using moving microphone arrays

Task 6: Tracking of multiple moving talkers using moving microphone arrays.

A detailed description on the provided information and requirements for the challenge submissions is given in [2].

The submissions and results of the challenge were presented at the LOCATA workshop on Sept. 18, 2019, which was a satellite event of the International Workshop on Acoustic Signal Enhancement (IWAENC 2018) in Tokyo. The workshop proceedings with the submitted challenge papers are available on the LOCATA website [3] where also further information about the can be found.

A comprehensive evaluation of the challenge results and a description of the used evaluation metrics is provided by in [4].

2 Datasets

The following datasets were available to the participants of the LOCATA Challenge [2]:

Development (Dev) dataset (Release: Feb. 2018): Multichannel audio recordings and ground-truth data for microphone positions, array orientations and source positions of all provided recordings. It comprises 3 recordings for each of the 6 tasks and each of the 4 microphone configurations, i.e., 72 recordings in total. The played back source signal as well as the multi-channel recordings were provided. In addition, a separate database containing the voice activity (VA) labeling for each recorded signal and the source signals was provided.

Evaluation (Eval) dataset (Release: Apr. 2018): Multichannel audio recordings and ground-truth data for the microphone positions and array orientations of all provided recordings. For Task 1 and 2, it comprises 13 recordings for each microphone configuration and

task (static scenarios), and 5 recordings per task and array otherwise, i.e., 184 recordings in total. The source signals and a voice activity labeling were not provided.

The finally released data corpus differ from these datasets as follows: It turned out that source signals for Recording 2 and 3 of Task 2 were erroneous. (The challenge participants had been informed about that error and were given the opportunity to revise the concerned challenge submission results.) The final release of the Dev dataset contains therefore no Recording 2 for Task 2 and a corrected source signal and voice activity labeling for Recording 3 of Task 2.

The Eval dataset contains now all the ground-truth data as the Dev dataset (VA labeling, ground-truth source positions and source signals). For both data sets, the VA labeling is now part of the dataset and not provided in a separate dataset as for the first version of the Dev dataset. A more detailed descriptions of the provided datasets and their structure is provided by Sec. 6. The final release can be downloaded via the following links:

- Dev and Eval dataset with all ground-truth data
  `https://doi.org/10.5281/zenodo.3630470`
- MATLAB framework to read datasets and run localization algorithms
  `https://github.com/cevers/sap_locata_eval`
- MATLAB framework for evaluation of participants' submissions
  `https://github.com/cevers/sap_locata_io`
- Documentation (PDF file)
  `https://locata.lms.tf.fau.de/datasets`.

The LOCATA challenge and its database are described in the following publications:

- H. W. Löllmann, C. Evers, A. Schmidt, H. Mellmann, H. Barfuss, P. A. Naylor, and W. Kellermann, "The LOCATA Challenge Data Corpus for Acoustic Source Localization and Tracking," *IEEE Sensor Array and Multichannel Signal Processing Workshop (SAM)*, Sheffield, UK, July 2018
- C. Evers, H. W. Löllmann, H. Mellmann, A. Schmidt, H. Barfuss, P. A. Naylor, and W. Kellermann, "The LOCATA Challenge: Acoustic Source Localization and Tracking," *IEEE Trans. on Audio, Speech, and Language Processing*, 2019, submitted for publication, pre-print available on arXiv: https://arxiv.org/abs/1909.01008.

Authors who use the provided databases for their work are asked to cite these papers.

3 Microphone Arrays and Sound Sources

This section provides a brief overview about the microphone arrays and sound sources used to record the development and evaluation dataset for the LOCATA Challenge based on [2].

3.1 Acoustic Sources & Speech Material

All recordings were conducted in a computing laboratory of the Department of Computer Science at Humboldt University Berlin. A floor plan of the recording area is provided by Fig. 1. The reverberation time of the room was about 0.5 s. The room is equipped with an optical tracking system, which is typically used to track the positions of NAO robots in preparation of the soccer competition RoboCup. This tracking system has provided the positions and orientation of the speakers (talkers and loudspeakers) and microphone arrays as described in Sec. 4 in more detail.

The position of each object (speakers and microphone arrays) is determined by a reference point and its orientation by a reference vector. A local coordinate system (local reference frame) is defined for each object where the reference point of the object coincides with its origin and the reference vector lies on the positive axis as shown in Fig. 2. An elevation of $\theta = 0$ corresponds to the positive $z-$ axis and an azimuth of $\phi = 0$ to the $y-$axis. This local coordinate system is considered in the following to describe the microphone positions for each array. Positional information about the speakers and microphone arrays will be described by a global coordinate system as explained later in Sec. 7.

For the recordings of Task 1 and Task 2, loudspeakers of type Genelec 8020C and Genelec 1029A were used as acoustic sources as shown in Fig. 3. The location of the local coordinate system is marked in Fig. 3 by red color. The reference vector coincides with the acoustic axis of the loudspeakers as specified by the data sheets of the manufacturer [5].

The reference point of the human talkers corresponds to the center of the mouth and the reference vector points towards the look direction of the head as indicated in Fig. 4.

For the recordings for Task 1 and Task 2, sentences selected from the CSTR VCTK database [6] were played back by static loudspeakers. The VCTK database provides over 400 newspaper sentences spoken by 109 native English speakers, recorded in a semi-anechoic environment with a sampling frequency of 96 kHz where the files used for the LOCATA challenge were downsampled to a sampling frequency of 48 kHz. The VCTK database is distributed under the Open Data Commons Attribution License, therefore permitting open access for participants. For the recordings for Tasks 3 to 6, speech utterances spoken by different persons were recorded. They spoke sentences which were randomly selected from the

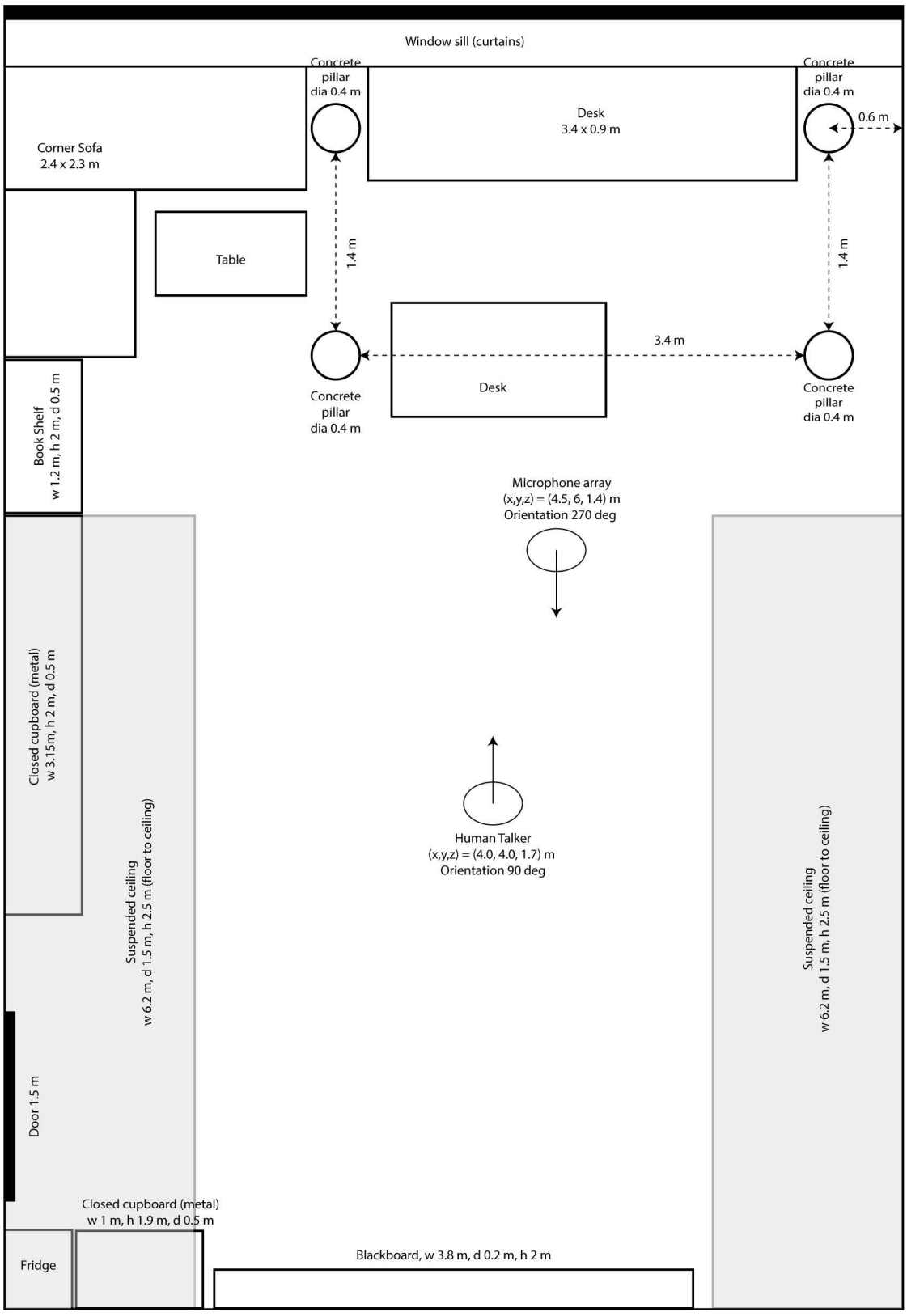


Figure 1: *Floor plan of the recording environment.*

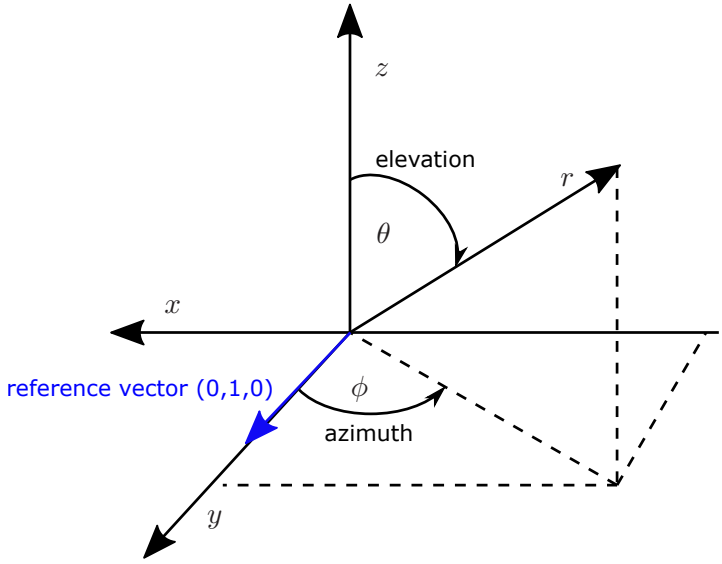


Figure 2: *Local coordinate system.*

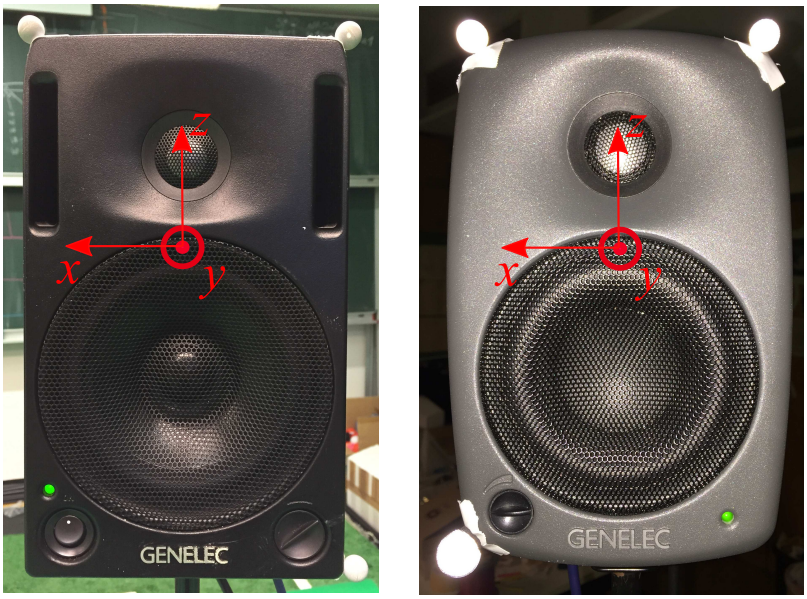


Figure 3: *Loudspeakers with markers: Genelec 1029A (left) and Genelec 8020C (left). The local coordinate system is marked by red color.*

VCTK database. The recordings are representative of the practical challenges of data processing of conversational speech, such as natural speech inactivity during sentences, sporadic utterances as well as dialogues between multiple talkers. The recordings were conducted in a real environment and are hence affected by measurement noise, traffic noise outside the recording environment, noise of the moving trolley in case of moving microphone arrays, etc.

Each talker was equipped with a microphone near the mouth[1] as shown in Fig. 4 to record

[1]Microphones used: AKG CK 92 with AKG SE 300 B; DPA microphone d:screet 4060

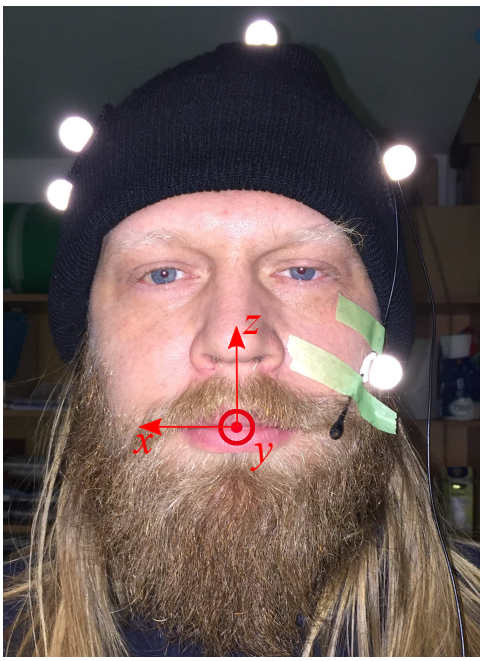


Figure 4: *Human speaker with markers. The local coordinate system is marked by red color.*

close-talking speech signals. It should be noted that the recorded close-talking speech signals are partly affected by noise due body-borne sound caused by contact of the microphone with the skin or beard of the walking person. The close-talking speech signals are contained in the final release of the Eval database, but were not contained in the Eval database provided to the challenge participants.

3.2 Microphone Arrays

Four different microphone arrays were used for the measurements:

- Planar array with 15 microphones (DICIT array) which comprises different uniform linear sub-arrays
- Hearing aid dummies (Siemens Signia) with 2 microphones per hearing aid
- Pseudo-spherical array of 12 microphones integrated in the head of a humanoid robot
- Spherical array with 32 microphones (Eigenmike).

A picture of the used microphone arrays is shown in Fig. 5. All audio recordings have been performed with a sampling frequency of 48kHz. For the measurements of Task 5 and 6, the arrays have been moved by the depicted trolley.

Figure 5: *Microphone arrays (with markers) used for the recordings: DICIT array, robot head, Eigenmike (left), and hearing aid dummies on an artificial head (right).*

The deployed microphone arrays account for typical application scenarios of acoustic source localization and tracking algorithms like, e.g., smart TVs and homes, hearing aids, robot audition, or tele-conference systems.

3.2.1 Planar array

The planar array with 15 microphones has been developed as part of the EU-funded project Distant-talking Interfaces for Control of Interactive TV (DICIT), cf., [7], hence denoted as DICIT array in the following. It was selected to account for the opportunities and challenges of arrays with large microphone spacings. It contains four linear uniform sub-arrays with microphone spacings of 4, 8, 16 and 32 cm. A technical drawing of the microphone geometry and the axis of the local coordinate system (local reference frame) is provided in Fig. 6. The locations of the microphones w.r.t. to the local reference frame are listed in Table 1. The listed spherical coordinates are related to the Cartesian coordinates according to Fig. 2. As for all objects, the normalized reference vector lies on the positive y-axis and the reference point coincides with the origin of the local coordinate system (local reference frame). The signals recorded by the DICIT arrays (after A/D conversion) have been processed by an equalizer to account for the individual transmission characteristic of its microphones.

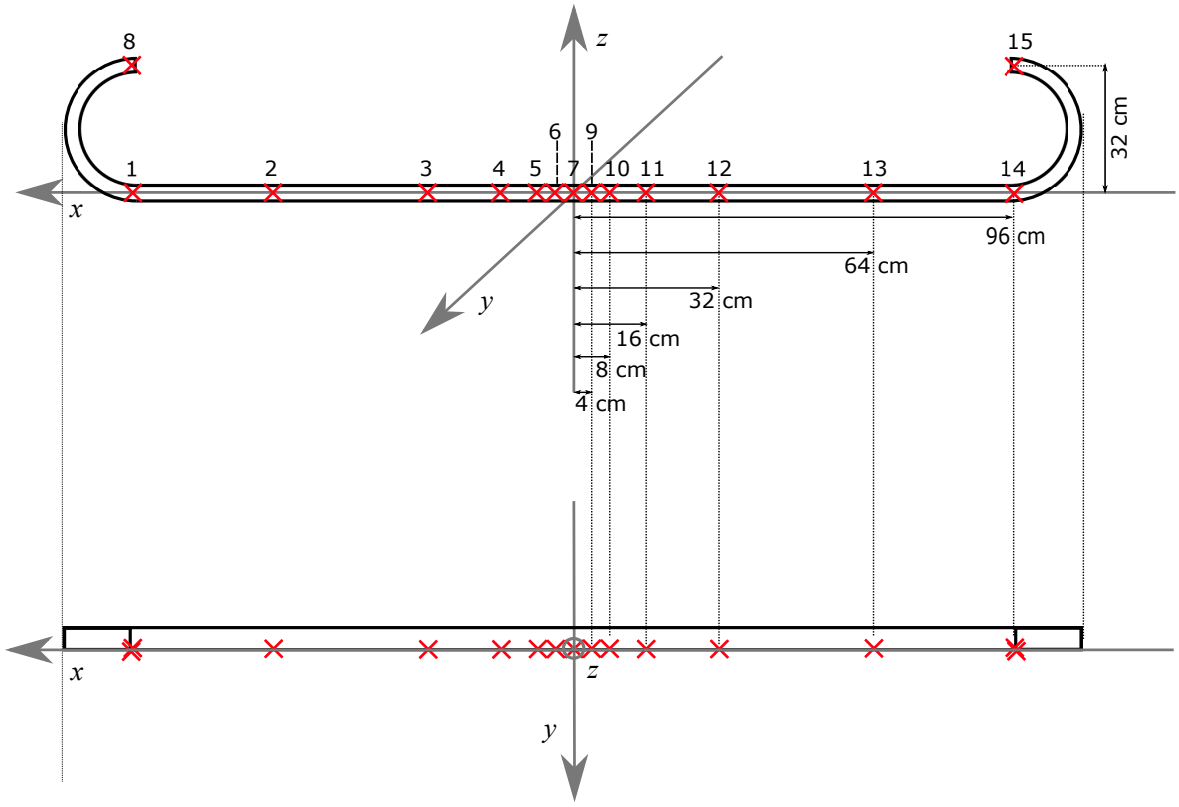


Figure 6: *Microphone positions for the DICIT array (marked by red crosses).*

3.2.2 Hearing aids

Hearing aid dummies of type Pure 7mi (Siemens Signia) of the hearing aid manufacturer Sivantos were mounted on an artificial head (HMS II.3 of HEAD acoustics) for the measurements. Each hearing aid contains two microphones (Sonion, type 50GC30-MP2) with a distance of 9 mm. A technical drawing of the microphone positions is shown in Fig. 7. The coordinates of the microphone positions are listed in Table 2.

3.2.3 Robot head

The deployed prototype head of the humanoid robot NAO, manufactured by Softbank Robotics (former Aldebaran Robotics), was developed as part of the EU-funded project Embodied Audition for Robots (EARS).[2] This prototype head is equipped with 12 microphones positioned in a pseudo-spherical arrangement.[3] The microphone positions, which have been determined by numerical optimization, cf., [8, 9], are listed in Table 3 and a drawing of the microphone

[2] `https://robot-ears.eu/`

[3] The commercially available head for this robot contains 4 microphones.

	Cartesian Coordinates			Spherical Coordinates		
Mic. no.	x [m]	y [m]	z [m]	ϕ [deg]	θ [deg]	r [m]
1	0.960	0.000	0.000	-90	90	0.960
2	0.640	0.000	0.000	-90	90	0.640
3	0.320	0.000	0.000	-90	90	0.320
4	0.160	0.000	0.000	-90	90	0.160
5	0.080	0.000	0.000	-90	90	0.080
6	0.040	0.000	0.000	-90	90	0.040
7	0.000	0.000	0.000	-90	90	0.000
8	0.960	0.000	0.320	-90	72	1.012
9	-0.040	0.000	0.000	90	90	0.040
10	-0.080	0.000	0.000	90	90	0.080
11	-0.160	0.000	0.000	90	90	0.160
12	-0.320	0.000	0.000	90	90	0.320
13	-0.640	0.000	0.000	90	90	0.640
14	-0.960	0.000	0.000	90	90	0.960
15	-0.960	0.000	0.320	90	72	1.012

Table 1: *Microphone positions for the DICIT array.*

	Cartesian Coordinates			Spherical Coordinates		
Mic. no.	x [m]	y [m]	z [m]	ϕ [deg]	θ [deg]	r [m]
1	-0.079	0.000	0.000	90	90	0.079
2	-0.079	-0.009	0.000	97	90	0.079
3	0.079	0.000	0.000	-90	90	0.079
4	0.079	-0.009	0.000	-97	90	0.079

Table 2: *Microphone positions for the hearing aid dummies.*

geometry is provided by Fig. 8.[4]

[4]Modification of a technical drawing kindly provided by Softbank Robotics

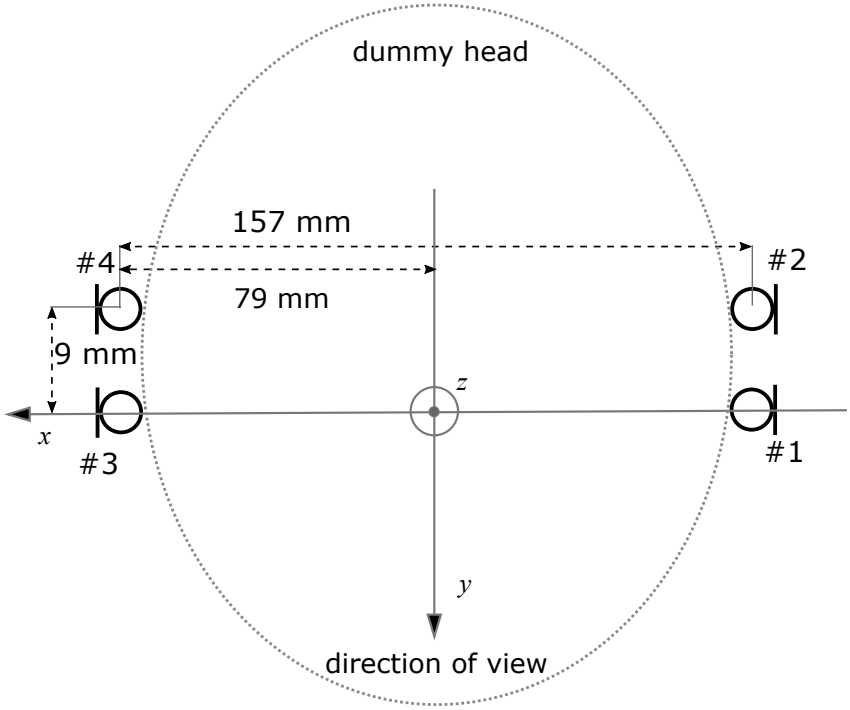


Figure 7: *Microphone positions of the hearing aids mounted on an artificial head.*

	Cartesian Coordinates			Spherical Coordinates		
Mic. no.	x [m]	y [m]	z [m]	ϕ [deg]	θ [deg]	r [m]
1	-0.028	0.030	-0.040	43	134	0.057
2	0.006	0.057	0.000	-6	90	0.057
3	0.022	0.022	-0.046	-46	146	0.056
4	-0.055	-0.024	-0.025	114	112	0.065
5	-0.031	0.023	0.042	54	43	0.057
6	-0.032	0.011	0.046	71	36	0.057
7	-0.025	-0.003	0.051	98	26	0.057
8	-0.036	-0.027	0.038	127	50	0.059
9	-0.035	-0.043	0.025	141	66	0.060
10	0.029	-0.048	-0.012	-149	102	0.057
11	0.034	-0.030	0.037	-131	51	0.059
12	0.035	0.025	0.039	-55	48	0.058

Table 3: *Microphone positions for the robot head.*

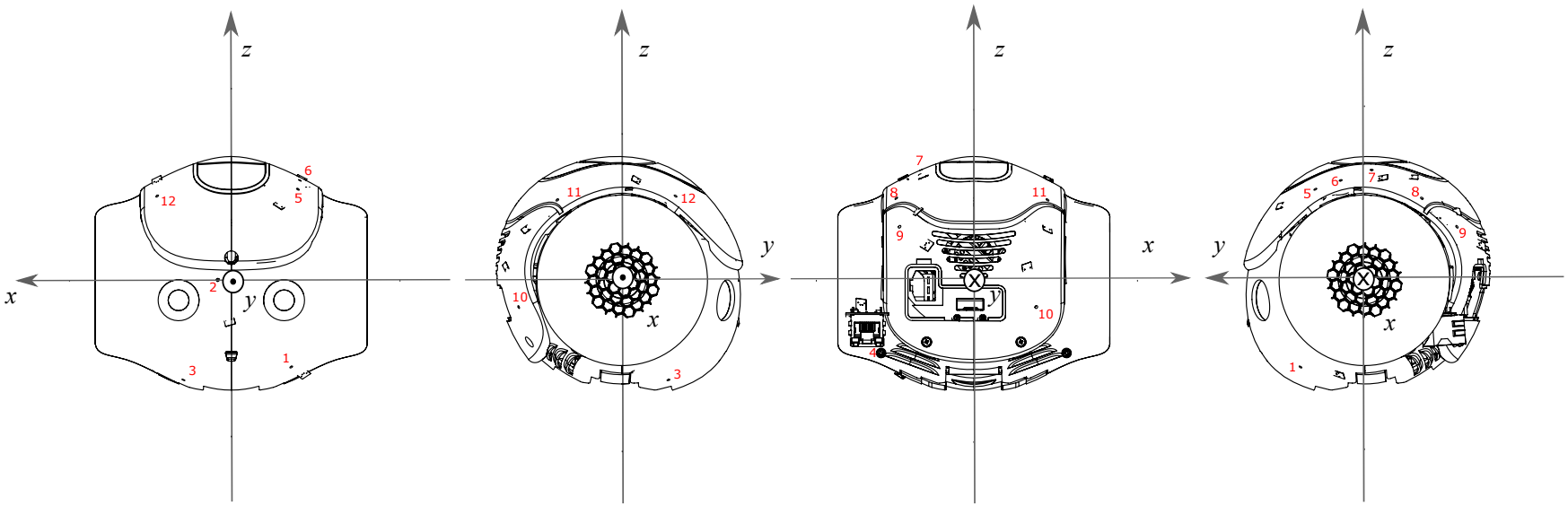


Figure 8: *Microphone positions for the robot head.*

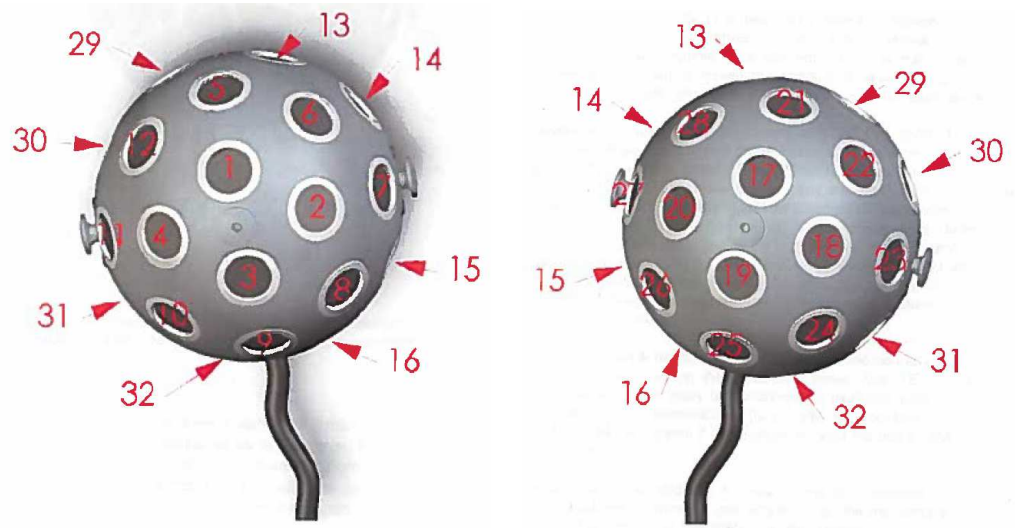


Figure 9: *Microphone positions for mh-acoustics Eigenmike [10].*

3.2.4 Spherical array

A spherical array of type Eigenmike[5] manufactured by mh acoustics was used for the recordings. The Eigenmike contains 32 microphones mounted on a sphere with a diameter of 84mm [10]. The positions of the microphones are listed in Table 4.

The reference point is located at the center of the sphere. Each microphone therefore corresponds to a radius of 0.042m relative to the local reference frame. The microphone geometry is illustrated in Fig. 9. Microphones $1-4$ are positioned towards a blue anodized shock mount [10]. It is important to notice that the blue anodized shock mount was pointed along the y-axis during the recordings (see also Fig. 10).

[5]Purchased in 2009, corresponding to release notes v8.0.

	Cartesian Coordinates			Spherical Coordinates		
Mic. no.	x [m]	y [m]	z [m]	ϕ [deg]	θ [deg]	r [m]
1	0.000	0.039	0.015	0	69	0.042
2	-0.022	0.036	0.000	32	90	0.042
3	0.000	0.039	-0.015	0	111	0.042
4	0.022	0.036	0.000	-32	90	0.042
5	0.000	0.022	0.036	0	32	0.042
6	-0.024	0.024	0.024	45	55	0.042
7	-0.039	0.015	0.000	69	90	0.042
8	-0.024	0.024	-0.024	45	125	0.042
9	0.000	0.022	-0.036	0	148	0.042
10	0.024	0.024	-0.024	-45	125	0.042
11	0.039	0.015	0.000	-69	90	0.042
12	0.024	0.024	0.024	-45	55	0.042
13	-0.015	-0.000	0.039	91	21	0.042
14	-0.036	0.000	0.022	90	58	0.042
15	-0.036	0.000	-0.022	90	121	0.042
16	-0.015	0.000	-0.039	89	159	0.042
17	0.000	-0.039	0.015	180	69	0.042
18	0.022	-0.036	0.000	-148	90	0.042
19	0.000	-0.039	-0.015	180	111	0.042
20	-0.022	-0.036	0.000	148	90	0.042
21	0.000	-0.022	0.036	180	32	0.042
22	0.024	-0.024	0.024	-135	55	0.042
23	0.039	-0.015	0.000	-111	90	0.042
24	0.024	-0.024	-0.024	-135	125	0.042
25	0.000	-0.022	-0.036	180	148	0.042
26	-0.024	-0.024	-0.024	135	125	0.042
27	-0.039	-0.015	0.000	111	90	0.042
28	-0.024	-0.024	0.024	135	55	0.042
29	0.015	-0.000	0.039	-91	21	0.042
30	0.036	0.000	0.022	-90	58	0.042
31	0.036	0.000	-0.022	-90	122	0.042
32	0.015	0.000	-0.039	-89	159	0.042

Table 4: *Microphone positions for the Eigenmike.*

4 Ground-Truth Position Data

The positions of all microphone arrays and sound sources were recorded during the measurements with the help of an optical tracking system. This section describes briefly the process by which the positioning data was obtained and discusses its accuracy.

The ground truth for the positions and orientations of all microphone arrays and sound sources was determined by means of the optical tracking system *OptiTrac* [11]. For this purpose, reflective markers with diameters of 11.1 mm and 15.9 mm were attached to each object (i.e., loudspeakers, microphone arrays and human talkers) as shown, e.g., in Fig. 3, Fig. 4 and Fig. 5. These markers were detected by 10 spatially distributed infrared cameras of type *Flex 13*.[6] The synchronized camera signals allowed to determine the marker positions by triangulation using the software *Tracking Tools* (version 2.5.3). At least three markers were attached to each object to track their positions and orientations. Unique marker geometries were used to distinguish between the objects. Human talkers wore hats with attached markers. In addition, one marker was attached to the cable of each DPA mouth microphone close to the mouth as shown in Fig. 4.

A group of markers marking one object was identified as a singular rigid pattern called *trackable* by the tracking software. Thus, each object was described by a trackable whose position and orientation were tracked as a unit by the *OptiTrac* software in addition to the positions of the individual markers. The used tracking system is able to simultaneously track the positions and the orientations of multiple trackables. A trackable can be successfully tracked even if some of the markers are occluded as long as at least three markers are visible for the cameras. All trackables and markers were tracked with respect to a global coordinate system whose origin and orientation was defined by a 'calibration square' placed on the floor.[7] The positions of the markers and trackables were captured with a rate of 120 frames per second and the audio recordings were performed with a sampling rate of 48 kHz. All data streams were stored on the same computer whose timestamps generated by its system clock were stored for each data sample. These timestamps were used in a post-processing step to synchronize the position data and audio data streams with an accuracy of about ± 1 ms.

The recorded (noisy) measurements for the marker positions have been used in a post-processing step to determine the ground-truth positions and orientations of all objects (trackables), i.e., the reference points and reference vectors as defined in Sec. 7.1. While a detailed description of this post-processing step is beyond the scope of this manual, the main sources for erroneous position data should be briefly discussed to provide an assessment for the accuracy of the tracking procedure.

[6] `http://optitrack.com/products/flex-13/specs.html`

[7] `https://v20.wiki.optitrack.com/index.php?title=Calibration`

The main cause for measurement errors were reflections of the infrared light, which was emitted by the tracking system, at the surfaces of the microphone arrays. Such reflections led to the detection of non-existing markers ('ghost markers') as well as missing detections of markers. In addition, some markers were occasionally occluded during the measurements with multiple moving objects. These erroneous detections led in isolated instances to a tracking loss or misalignment by the *OptiTrac* system for some objects, resulting in outliers for the orientation and position of the trackables. In some cases, the missing marker detections also resulted in high frequency noise (jitter) for the measured trajectories in the range of a few millimeters. Outliers and missing data points have been replaced by estimated values in the course of the post-processing step.

In order to estimate how well the reconstructed trajectories correspond to the originally recorded marker positions, the mean-square error between the recorded marker positions and the marker positions of the reconstructed trackables were calculated for all positions. The results indicate deviations of less than 12mm for all objects, where the deviations for most objects are below 6mm.

The positions of the microphones in relation to the marker positions were derived by means of technical drawings of the microphone positions and caliper measurements with an estimated accuracy of a few millimeters. The movement of the arrays might have caused additional measurement errors: The DICIT array was slightly bending back and forth while being moved during the measurements for Task 5 and Task 6 due to its large dimensions(cf., Fig. 5), where a rigid array was assumed for the determination of the microphone positions.

The Eigenmike used in the measurements is a 2009 version, and is therefore mounted in a Samson SP01 spider shockmount holder using rubber bands. To minimize the effects of shadowing and scattering, the markers were attached to the edges of the shockmount holder as shown in Fig. 10. The use of the rubber bands can lead to small rotations and offsets of the microphone array relative to the measured marker positions.

5 Voice Activity Labeling

Determining the Voice-Active Periods (VAPs) from the recorded signal is prone to errors due to room reverberation and recorded noise. Therefore, the VAPs were determined manually for the sound files played back by the loudspeakers for Task 1 and Task 2, and the recorded close-talking microphone signals for Task 3 to Task 6. The VAP labels for the recorded signals were derived from VAP labels created for the source signals by accounting for the delay due to the sound propagation from each source to each microphone array as well as the overall processing delay to perform the recordings. The delay due to the sound propagation was determined by means of the ground-truth positional data for the sources and microphone

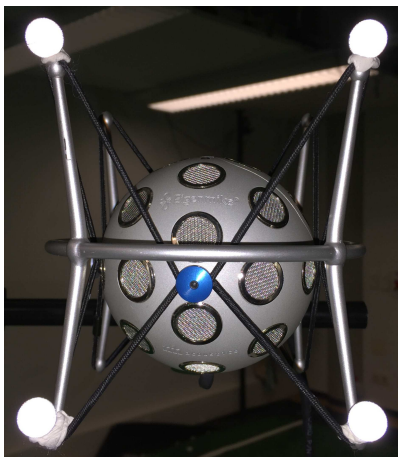


Figure 10: *Eigenmike mounted in a spider shockmount holder with attached markers.*

arrays. The processing delay for the scenarios with static loudspeakers (Task 1 and 2) was determined by calculating the cross-correlation between the source signal and recorded signal for the single-source Task 1. The processing delay for Tasks 3 to 6 was determined by the cross-correlation between the recorded close-talking microphone signal and the recorded array signal for the single-source Task 3.

The ground-truth VAPs were provided to the participants of the challenge as part of the development dataset but were excluded from the evaluation dataset. The final release contains the VA labeling for both databases.

6 Data & Software

This section provides a description of the finally released datasets.

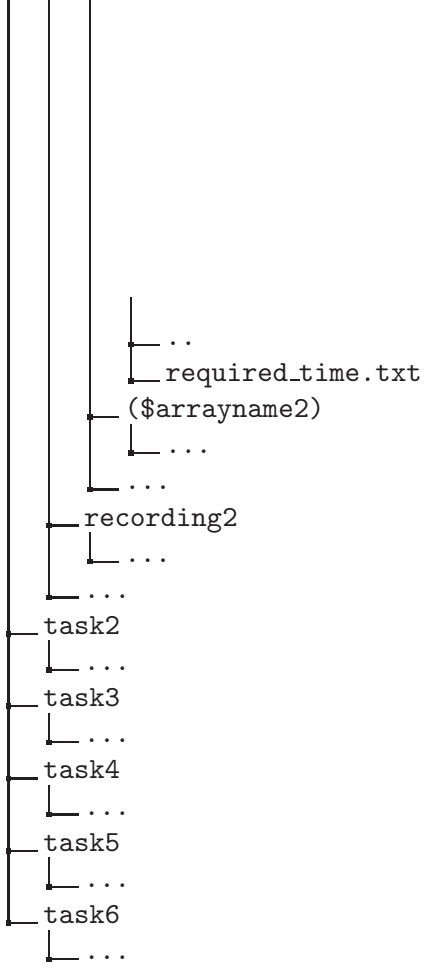
The evaluation and development databases are provided as zip-archives (dev.zip and eval.zip). After extraction of the zip-archives, the following files are provided for each recording of the development and evaluation database:

- One file named `required_time.txt`, containing the synchronized system timestamps. (Challenge participants had to provide estimates for each timestamp specified in the txt-file `required_time.txt` of the evaluation database.)
- One file named `audio_array_$array.wav` for each array, containing the multichannel recordings of the respective microphone array (`dicit`, `benchmark2`, `eigenmike`, `dummy`).
- One file named `audio_array_timestamps_$array.txt` for each array, containing the synchronized system timestamps for each sample in the corresponding file `audio_array_$array.wav`.

- One file named `position_array_$array.txt` for each array, containing the ground-truth position and orientation of the array reference point and microphone positions as documented in Sec. 3.2. Note that the positions are synchronized with the audio data with a sampling frequency of 120 Hz, cf., Sec. 4.
- One file named `audio_source_$source.wav` for each source, containing the single-channel source signals. For Tasks 1 and 2, the clean speech signals from the VCTK database are provided. For the remaining tasks, the close-talking signals recorded by the reference microphones are provided (see also Sec. 3.1).
- One file named `audio_source_timestamps_$source.txt` for each source, containing the synchronized system timestamps for each sample in the corresponding file `audio_source_$source.wav`.
- One file named `position_source_$source.txt` for each source, containing the ground-truth position and orientation of the source reference point as documented in Sec. 3.1 and Sec. 7.
- One file named `VAD_$array_$source.txt` for each recorded source signal containing a voice activity labeling (0 or 1) for each timestamp (see also Sec. 5).
- One file named `VAD_source_$source.txt` for each source signal containing a voice activity labeling (0 or 1) for each timestamp.

MATLAB programs are provided to demonstrate the use of the LOCATA databases. They read in the data of the datasets, run a baseline algorithm and write the results to a file.The unarchived data for the Dev and Eval database should have the following structure:

```
matlab
data
  task1
    recording1
      ($arrayname1)
        audio_array_benchmark2.wav
        audio_source_($sourcename1).wav
        audio_source_($sourcename2).wav
        ...
        audio_array_timestamps.txt
        audio_source_($sourcename1).wav
        audio_source_($sourcename2).wav
        ...
        position_array_benchmark2.txt
        position_source_($sourcename1).txt
        position_source_($sourcename2).txt
        ...
        VAD_($arrayname)_($sourcename1).txt
        VAD_($arrayname)_($sourcename2).txt
        ...
        VAD_source_($sourcename1).txt
        VAD_source_($sourcename1).txt
```



A folder `recording$` contains speech recordings and source signals for the same speaker(s).

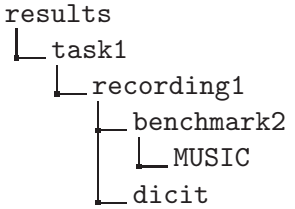
In the following, a brief description of the MATLAB programs to read in the datasets and run a localization algorithm is provided. The main function is `main.m` and its interface reads:

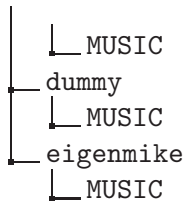
`main( data_dir, results_dir, is_dev, arrays, tasks).`

The path string for either the development or evaluation database is given by `data_dir` and the path string pointing to the directory where the results of the program `main.m` are to be written to is given by `results_dir`. A value of 1 for `is_dev` indicates that the development database is provided where a value of 0 indicates the use of the evaluation database. The cell array `arrays` and the vector `tasks` specify the microphone arrays and tasks for which the evaluation is performed. These two input arguments are optional; the default settings use all arrays ({`'benchmark2', 'eigenmike', 'dicit','dummy'`}) and tasks (`[1,2,3,4,5,6]`).

The function name for the user's localization algorithm is specified by the string variable `my_alg_name` within the main function (line 79) where the *Multiple SIgnal Classification* (MUSIC) algorithm (e.g., [12]) is provided as an example.

The results of `main.m` are written into csv text-files and stored in a folder structure similar to that of the LOCATA databases, further structured by array (`benchmark2`, `dicit`, `dummy`, `eigenmike`) and algorithm (e.g., `MUSIC` as in the example below). In the case of running `main.m` over Task 1 for all arrays, the folder structure will be as follows:





The sub-folder `MUSIC` contains N csv text-files with the localization results (`source_$.txt` where N denotes the number of estimated sound sources, and one file containing the elapsed computation time of the localization algorithm (`telapsed.txt`). MATLAB figures with localization results and ground-truth data are saved in addition.

The main function iterates over all recordings in `data_dir` for the specified tasks and arrays and calls the following functions:

- `./matlab/utils/load_data.m`: Loads audio data from wav-files recorded by the microphone arrays into the structure `audio_array`. For the development database, the reference microphone signals are loaded into the structure `audio_source`. In addition, ground-truth *OptiTrac* positions for the microphone arrays and sound sources are loaded into the structures `position_array` and `position_source`, respectively.

- `./matlab/utils/get_truth.m`: Evaluates the source directions (azimuth/elevation) w.r.t. the local coordinate system of each microphone array as specified in Sec. 3.2. The function demonstrates the use of rotation matrices and translation vectors where positional information about the sound sources is returned.

- `./matlab/utils/MUSIC.m`: Demonstrates the use of the LOCATA data for DOA estimation using MUSIC.[8] (For the LOCATA Challenge, DOA estimates were required at the timestamps defined by the *OptiTrac* system.) `MUSIC.m` also shows as an example how the DOA estimates obtained from the multichannel speech data can be interpolated to the *OptiTrac* update rate.

- `./matlab/utils/plot_results.m`: Plots the estimated results and MATLAB figures with the localization results and ground-truth data are saved in the folder with the results.

- `./matlab/utils/results2csv.m`: Checks if only valid fields are provided and saves the MATLAB struct with the results to csv files in the directory `results_dir`.

The provided MATLAB software has been created and tested with MATLAB version 9.3 (R2017b). The use of MATLAB version 8.6 (R2015b) or an older version may cause problems.

[8]The frequency-domain processing of multichannel recordings by MUSIC might require to increase the system swap space (virtual memory) such that MATLAB can allocate enough memory for the execution of this function.

7 Reference Frames & Coordinate Systems

This section explains how positional information about the sources and arrays are expressed as well as the required format for position estimates.

7.1 Reference Frames

The users are required to provide estimates of the source positional information relative to the microphone array used for the audio recordings. The coordinate system used for LOCATA, as illustrated in Fig. 11, is defined as follows: The origin of the global reference frame is defined as the origin of the *OptiTrac* system, which was defined by a calibration square lying on the floor, cf., Sec. 4. It should be noted that the position of the calibration square, and hence the location of the global reference frame origin within the enclosure, may have changed between recordings. This does no effect the results for the LOCATA Challenge since the information required for reference frame transformations is provided specific to each recording.

The x-, y-, and z-axes are defined as the East, North and Up direction relative to the global origin. The 3D position of the array reference point (see Sec. 3.2) in x-, y-, and z-coordinates is defined as the East, North and Up position, $(x_{t,r}, y_{t,r}, z_{t,r})$, of the reference point relative to the global reference frame. For each recording, the file `position_array_$array.txt` for the corresponding array provides the 3D position of the reference point by the field `position` as a $3 \times T$ matrix, where T is the number of *OptiTrac* samples for the corresponding recording. The 3D microphone positions, defined similar to the reference point, are provided in the field `mic` as a $3 \times T \times M$ matrix, where M is the number of microphones in the corresponding array. The rotation of the array is provided by a 3D rotation matrix, which is contained in the field `rotation` as a $3 \times T \times 3$ matrix. The normalized reference vector w.r.t. the global reference frame is provided by the $3 \times T$ matrix in `ref_vec`.

Fig. 11 shows an illustration of the LOCATA reference frames defined above. The global reference frame is shown in black. The local reference frame relative to any selected array is shown in green. Note that the origin of the local reference frame corresponds to a translation by the array reference point position and a rotation by the array orientation. The figures depict in red the spherical and Cartesian coordinates of a source relative to the microphone array.

7.2 Coordinate System

The positional source information is stored in the file `position_source_$source.txt` for each recording of the corresponding source. The file provides the absolute position in Cartesian

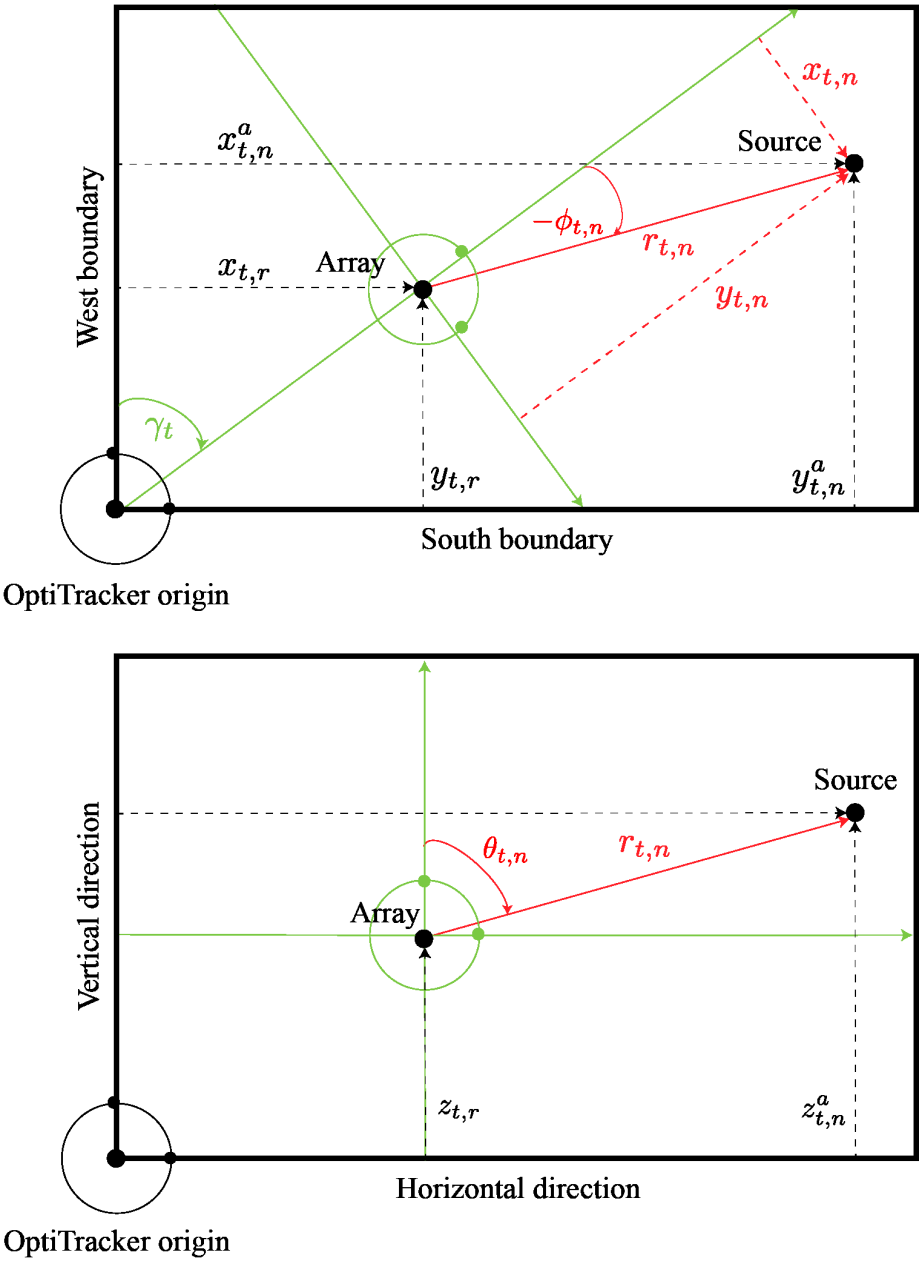


Figure 11: *Illustration of LOCATA reference frames.*

coordinates $(x_{t,n}, y_{t,n}, z_{t,n})$ of the source reference point in the global reference frame in the field `position` as a $3 \times T$ matrix for each of the T *OptiTrac* samples. The source rotation in the global reference frame is provided in the field `rotation` by a $3 \times T \times 3$ matrix. The normalized reference vector w.r.t. the global reference frame is provided by the $3 \times T$ matrix in `ref_vec`.

The spherical coordinates of any source in the local reference frame relative to any selected array are defined by the source azimuth, elevation and range in compliance with Fig. 2. The

source azimuth $\phi_{t,n}$ at any time step t of source n relative to an array is defined as the horizontal direction, where $\phi_{t,n} = 0$ rad is pointing along the positive y-axis of the local reference frame, i.e., in the 'look direction' of the array. The azimuth is rotated counter-clockwise and is defined between $-\pi \leq \phi_{t,n} < \pi$, i.e., the negative x-axis of the local reference frame corresponds to $\phi_{t,n} = \frac{\pi}{2}$ rad, the positive x-axis corresponds to $\phi_{t,n} = -\frac{\pi}{2}$ rad, and the negative y-axis corresponds to $\phi_{t,n} = \pi$ rad. The elevation, $0 \leq \theta_{t,n} \leq \pi$, is defined as the vertical direction, where $\theta_{t,n} = 0$ rad is pointed upwards along the positive z-axis of the local reference frame, $\theta_{t,n} = \pi$ rad is pointed downwards along the negative z-axis and $\theta_{t,n} = \frac{\pi}{2}$ is pointed along the horizontal plane, i.e., in the look direction of the array. The source-sensor range, $r_{t,n} \geq 0$, is defined as the Euclidean distance between the reference points of source and sensor.

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