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Description

[0001] The present invention relates to a method of designing a controller for a
5 hearing aid in order to compensate for the occlusion effect when emitting an acoustic
useful signal into the ear canal of a human ear.

[0002] The muffled perception of one's own voice is still a major problem with hearing
aids. This effect occurs when the ear canal is completely blocked, which is why it is
10 referred to as the occlusion effect (OE). Such blocking of the ear canal occurs
especially with hearing aids, which usually consist of a central unit fitted behind the
ear and an associated internal unit in the form of an earbud inserted into the auditory
canal and blocking it tightly.

15 [0003] The external unit generally comprises a power source in the form of one or
more batteries, one or more external microphones, and a processor for processing
and possibly amplifying the signal recorded by the external microphone, and an
interface to the internal unit that, in turn, has a speaker to which an output signal
processed by the processor is fed, which output signal corresponds at best to the
20 natural external sounds at the ear that are recorded by the external microphone so
that the wearer of the hearing aid can perceive these natural external sounds at a
pleasant volume, without distortion, and in good quality despite impaired hearing.
However, hearing aids are also known in which the external microphone is part of the
internal unit or in which the components of the external and internal unit form a single
25 compact internal unit.

[0004] The muffled perception of one's own voice essentially results from two factors.
First, the perception of one's own voice is always a combination of two main signals
with respect to the human ear itself. The first main signal is characterized by an
30 acoustic wave component, $x'_{AC}(t)$, that is conducted via the air (AC, Air-Conducted),
and the second main signal is characterized by an internal component, $x'_{BC}(t)$, that is
conducted via the bone and cartilage (BC, Bone-Conducted), as shown in FIG. 1.
Thus, one hears one's own voice in the ear from two sources, from the airborne
sound $x'_{AC}(t)$ and from the structure-borne sound $x'_{BC}(t)$. This is also the reason why

one hears one's own voice differently when speaking than when one hears oneself from a recording. After all, the structure-borne sound component $x'_{BC}(t)$ is missing from the recording. Second, the internal part of a hearing aid, i.e. the earbud, blocks the auditory canal and thus alters its acoustic terminating resistance. The internal

5 part also poses an obstacle to acoustic waves from outside the ear that damps the high frequencies of the airborne sound signal $x'_{AC}(t)$. Moreover, the low-frequency components introduced into the auditory canal by the structure-borne sound signal $x'_{BC}(t)$ cannot escape the auditory canal. This leads to an amplification of the low frequencies by up to 30 dB in extreme cases.

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[0005] Mechanical solutions for preventing the occlusion effect are known and include the ventilation of the ear canal or a deep insertion of the hearing aid into the ear canal, for example (see Thomas Zurbrügg, "Active Control Mitigating the Ear Canal Occlusion Effect caused by Hearing Aids," Ph.D. dissertation, EPFL Lausanne,

15 Lausanne, 2014). However, these are not without drawbacks. For instance, ventilation through a vent opening in the earbud increases feedback between the outside microphone and the speaker. Furthermore, deep insertion of the earbud into the auditory canal adversely affects wearing comfort.

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[0006] As an alternative to mechanical compensation for the occlusion effect, approaches have therefore been developed that employ active noise cancellation (ANC) in order to achieve "electronic ventilation." In these approaches, a second microphone is used that is located next to the speaker in the internal unit/earbud and records the acoustic signals in the auditory canal, with the recorded signal being fed

25 back negatively to the signal to be emitted by the speaker, and with a controller arranged in the feedback branch having the task of influencing the signal to be outputted by the speaker such that the occlusion effect is minimized.

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[0007] Such an approach is described, for example, in the above-described publication by Thomas Zurbrügg, in European patent application EP 2 640 095 A1, and in international patent application WO 2006/037156 A1, as well as in the publications "Active cancellation of occlusion: An electronic vent for hearing aids and hearing protectors," Journal of the Acoustical Society of America, vol. 124, No. 1, pp. 235-240, 2008 and M. Sunohara, M. Osawa, T. Hashiura, and M. Tateno, "Occlusion

reduction system for hearing aids with an improved transducer and associated algorithm," in 2015 23rd European Signal Processing Conference (EUSIPCO), 2015, pp. 285-289. However, this prior art uses a fixed, i.e. immutable, controller. The occlusion effect is however different for each person due to the shape and length of their auditory canal and in each application, since a user does not always insert the internal unit the same way into the auditory canal. Thus, both the orientation of the earbud/angle of the speaker and the insertion depth of the internal unit vary with each use. The use of a fixed controller in the individual user therefore does not lead to a good result.

[0008] In addition, solutions with adaptive controllers that have to be manually set or parameterized for a specific user are known from the publications "R. Borges, M. Costa, J. Cordioli, and L. Assuiti, "An Adaptive Occlusion Cancels for Hearing Aids," in IEEE Workshop on Applications of Signal Processing to Audio and Acoustics, 2013, and M. Sunohara, K. Watanuki, and M. Tateno, "Occlusion reduction system for hearing aids using active noise control technique," Acoustical Science and Technology, Vol. 35, No. 6, pp. 318-320, 2014. It is true that an adaptive controller does lead to an improvement in the suppression of the occlusion effect given the individual adaptation. With respect to the various applications in terms of orientation and insertion depth of the internal unit, the previous approaches do not lead to satisfactory results. In particular, the stability of the overall system with the feedback controller is not considered in the literature but represents one of the main problems of the electronic reduction of the occlusion effect.

[0009] It is therefore the object of the invention to provide a controller for a hearing aid that overcomes the drawbacks of the prior art and leads particularly both to an effective user-specific and to a robust user-independent compensation of the occlusion effect.

[0010] This object is achieved by a controller design method according to claim 1. Advantageous developments are indicated in the subclaims and elucidated below.

[0011] According to the invention, a method of designing a controller K for a hearing aid for the purpose of compensating for the occlusion effect in the emission of an

acoustic useful signal into the auditory canal of a human ear is proposed in which the hearing aid comprises an earbud that can be inserted into the ear with a speaker for emitting a compensation signal $\tilde{y}'(t), y(t)$ into the auditory canal, and a microphone for receiving an error signal $e'(t)$ from the auditory canal, as well as a control unit for processing the recorded signal to be emitted, the method comprising the following steps:

- measuring a nominal secondary path between the speaker and the microphone and determining a transmission function G that describes the behavior of the nominal secondary path,
- 10 - determining a first requirement in the form of a tolerance band W_{tol} about the transmission function G ,
- determining a second requirement in the form of a desired sensitivity function (S_{gew}) of the hearing aid,
- designing the controller (K) using an optimization method while simultaneously taking the first and second requirement into consideration, and
- 15 - implementing the controller (K) in the control unit.

[0012] In the interest of better understanding, the method will be explained in the following with reference to the accompanying figures. FIG. 3 shows a flowchart with the above-described steps. It should be expressly noted, however, that the method is by no means limited to what is shown in the figures. The figures show only examples of possible manifestations of the method and are not to be understood as limiting the invention in this respect.

25 [0013] FIG. 1 is a schematic view of an embodiment of a hearing aid 1 according to the invention, of which only an earbud 8 and a control unit 9 are shown in detail here. The earbud 8 is introduced into the auditory canal 5 that is also referred to as the ear canal in the context of the invention. Reference numeral 4 indicates the auricle of the human ear. The auditory canal 5 is thus closed off toward the auricle 4 by the earbud 8 and in the other direction by the eardrum 6.

30 [0014] The earbud 8 comprises a speaker 2 and a microphone 3 that are arranged next to one another. The region between the speaker 21 microphone 3 and the housing of the earbud 8 is referred to as a sound channel 11. As explained in the

introductory part of the description, one's own voice consists of an air-conducted component $x'_{AC}(t)$ and a bone-conducted component $x'_{BC}(t)$, both of which enter the auditory canal 5 and induce the internal acoustic interference signal $d'(t)$ there.

5 [0015] The control unit 9 of the hearing aid 1 comprises all of the signal processing components required for the inventive compensation of the occlusion effect. In principle, it can be purely analog, purely digital, or constructed from a combination of analog and digital components. In the design variant shown in FIG. 1, the control unit has a digital construction and comprises, in particular, a digital controller 15, an
10 analog-to-digital converter 13, a digital-to-analog converter 14, and a digital secondary path model 12.

[0016] The hearing aid 1 further comprises an external microphone 18 for recording voices and sounds from the environment that are described by the acoustic useful
15 signal $a'(t)$. Optionally, an analog-to-digital converter 13 associated with the external microphone as well as a signal processor 19 for the external signal can also be part of the control unit 9. This is not mandatory, however. The control unit 9 itself can be formed by a digital signal processor (DSP) or comprise such a DSP.

20 [0017] The speaker 2 emits an internal acoustic compensation signal $\tilde{y}'(t)$ that eliminates the interference signal $d'(t)$ to the greatest possible extent so that only an acoustic error signal $e'(t)$ remains that is picked up by the microphone 3, converted as an analog electrical error signal $e(t)$ by the analog-to-digital converter 13 into the digital error signal $e(k)$, and fed to the controller $K(z)$ 15 that generates a digital
25 controller signal $y_r(k)$ that is fed to the speaker 2 with a negative sign. The controller 15 is thus located on a feedback path 7 from the microphone 3 to the speaker 2.

[0018] The electrical signal $a(t)$ generated by the external microphone 18 is likewise digitized by an analog-to-digital converter 13 and subsequently processed, for
30 example amplified and/or filtered, in a signal processor 19. The signal processor 19 can also be upstream from the digitization 13, i.e. take place in the continuous time domain. In the normal case, the digital useful signal $a(k)$ is fed to the speaker 2 of the hearing aid 1, but after having been previously overlaid with the negative controller signal $y_r(k)$. The overlaid digital signal $a(k) - y_r(k)$ is then converted by the digital-to-

analog converter 14 into an analog electrical signal, fed to the speaker 2, and outputted accordingly.

[0019] Since the useful signal $a'(t)$ has no significance for the design of the controller 15 that serves to compensate for the occlusion effect, it is omitted here for the sake of simplicity or set to zero. Thus, the controller signal $y_r(k)$ corresponds to the digital compensation signal $\tilde{y}(k)$, except for the sign, meaning that the controller 15 directly specifies the compensation signal. The controller 15 then receives only the error signal $e(k)$ as an input signal, because the signal path below the feedback path 7 has no effect.

[0020] In reality, however, the useful signal $a'(t)$ is different from zero, so that the speaker 2 outputs not only the inverted controller signal $y_r(k)$ but also, and as intended, the useful signal, as an overlay of the two signals. This means the microphone 3 also receives the useful signal again, but altered by the transmission characteristic of the secondary path, so that not only the previously described error signal $e(k)$ but also a useful signal overlaid with same is fed to the controller 15. To eliminate this, the digital payload signal is fed to a model 12 whose transmission function corresponds to the estimated transmission function $\hat{G}(z)$ of the actual secondary path, so that the digital output signal of the model 12 corresponds exactly to the digitized signal that the microphone 2 picked up due to the useful signal present in the auditory canal 5. This model output signal is then subtracted from the digital microphone signal, so that only the pure error signal $e(k)$ resulting from the difference of the interference signal $d'(t)$ and the compensation signal $\tilde{y}'(t)$ is now actually fed to the controller 15. However, since the model 12 is based only on an estimate $\hat{G}$ of the secondary path, the model output and the portion in the microphone signal originating from the useful signal differ from one another, so that the subtraction of the model signal from the microphone signal does not yield precisely the error signal, but rather a digital modified error signal $\tilde{e}(k)$ that forms the input signal of the controller 15. This corresponds to an embodiment for making the useful signal free from the influence of the feedback controller. Another variant is characterized by the predistortion of the useful signal $a(k)$ by the signal processor 19.

[0021] As can be seen in FIG. 1, the secondary path also comprises, in addition to the direct acoustic path that signals coming from the speaker 3 can take to the microphone 3, the digital-to-analog conversion 14, the characteristics of the speaker 2 and of the microphone 3, and the subsequent analog-to-digital conversion 13. The behavior of the secondary path is described mathematically by its transmission function G, namely that of the multiplicative chaining of the transmission functions

- of the digital-to-analog converter (DAC) 14, G_{DAC} , upstream from speaker 2,
- of the speaker 2, G_{rec} ,
- of the distance between speaker and microphone, G_{ACOUST} ,
- of the microphone 3, G_{mic} , and
- of the analog-to-digital converter (ADC) 13 downstream from microphone 3. Thus we have

$$G = G_{DAC} \cdot G_{rec} \cdot G_{acoust} \cdot G_{mic} \cdot G_{ADC}.$$

[0022] The secondary path is essentially determined by the individual anatomical shape and length of the auditory canal 5 on the one hand and by the seating, i.e. the insertion position and orientation of the earbud 8 in the auditory canal 5 on the other hand. The "nominal" secondary path is therefore a reference path with a standard defined acoustic path between speaker and microphone. An anatomical model of an average human ear canal can be used with an average nominal length and width, or an average volume of the ear canal can be used for this purpose, for example.

Alternatively, the secondary path that is present individually in the wearer of the hearing aid can be defined as a nominal secondary path, appropriately measured, and used for further processing. Furthermore, a normal insertion position of the earbud is used for the nominal secondary path, i.e. one in which the earbud is neither too loose and would be apt to fall out of the auditory canal in the event of a movement nor too tight, i.e. inserted too deeply into the auditory canal, which would be unpleasant, or even painful, for the wearer of the hearing aid anyway.

[0023] The earbud can be a substantially rotationally symmetrical body with outwardly projecting elastic retaining ribs for example. Alternatively, the earbuds can

be formed by a so-called otoplastic that is a molded part fitted to the auditory canal and obtained by molding the inner ear.

[0024] The measurement of a secondary path between the speaker and the microphone according to step S1 of the method is inherently known. It can be accomplished by providing a measurement signal through the speaker that is picked up by the microphone, the signal exciting a wide range of frequencies within the auditory canal. For example, the spectrum can include frequencies between 20 Hz and 20 kHz. This spectrum can be traversed with a so-called SWEEP, for example. This means that the signal emits only one frequency at a time, but this is increased or reduced from a start frequency to an end frequency. For example, the measurement signal can be a sine function with a frequency that varies over time. The frequency can be varied linearly or logarithmically, with the high frequencies being passed through more quickly in the case of logarithmic variation. Furthermore, the measurement signal could be a sweep with perfect autocorrelation properties (so-called perfect sweep). Alternatively, the measurement signal can be formed by a noise signal, for example by so-called white or colored noise, by a periodic, random sequence, in particular by a maximum sequence (also known as maximum length sequence (MLS)) or by a sequence with perfect autocorrelation properties (perfect sequence). In this case, all frequencies are excited at the same time.

[0025] After the measurement, a transmission function G describing the behavior of the nominal secondary path is determined, step S2. This is described mathematically in the discrete complex z -domain by the ratio of the measured microtone signal $Y_{mic}(z)$ to the measuring signal $X_{mes}(z)$ of the speaker, since the microtone signal $y_{mic}(k)$, through a mathematical convolution of the transmission function $g(k)$ with the measurement signal $x_{mes}(k)$, yields the following in the discrete time domain:

$$y_{mic}(k) = g(k) * x_{mes}(k)$$

and

$$G(z) = Y_{mic}(z) / X_{mes}(z)$$

[0026] The determination of the transmission function $G(z)$ can thus be effected by a spectral division, for example by dividing the Fourier transform of the microtone signal and of the measurement signal by one another. The Fourier transforms can be determined, for example, by the so-called discrete Fourier transformation (DFT) or
 5 the so-called fast Fourier transformation (FFT) from the time-discrete values $y_{mic}(k)$ and $x_{mes}(k)$:

$$G(z) = \text{FFT}(y_{mic}(k)) / \text{FFT}(x_{mes}(k))$$

10

[0027] Alternatively, the transmission function G of the nominal secondary path can be estimated through so-called adaptive system identification, in which an iterative determination is made of G by starting from an arbitrary first estimated transmission function $\hat{G}$ and repeatedly estimating the estimate $\hat{G}$ while minimizing the error $G -$
 15 $\hat{G}$, until the error is below a predetermined threshold value and the transmission function G has thus been determined with sufficient accuracy, even though it is still an estimate. This method of "adaptive system identification" is also inherently known, so that reference is made to the relevant specialist literature for further information on this method.

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[0028] While the adaptive system identification is performed in the discrete time domain, the transmission function is determined by spectral division in the frequency domain on the basis of time-discrete variables. It should already be pointed out here that the method according to the invention can be fully carried out either with
 25 continuous-time signals $x(t)$, where t represents an arbitrary point in time, or with discrete quantities $x(k)$, where k represents a specific sampling time as a multiple of the sampling interval T . Both constitute a representation of the signal x . In that regard, individual process steps can be carried out in the frequency domain by the Laplace transform $X(s)$ of the time-continuous quantities or by the z -transform $X(z)$ of
 30 time-discrete quantities, with the complex variables being $s = \sigma + j\omega$ und $z = e^{\sigma + j\omega}$. The determined transmission function of the nominal secondary path can thus be present after the first method step as $G(s)$ or $G(z)$.

[0029] After the determination of the transmission function, a first requirement is determined according to the invention in the form of a symmetrical or asymmetrical tolerance band W_{tol} about the transmission function in order to take the uncertainty of the secondary path into account for the controller set-up, step S3). A maximum
 5 deviation from the nominal secondary path that the controller must take into account in its regulation is thus established. This can be achieved in various ways.

[0030] According to a first variant, a fixed relative limit $W_K = \text{const}$ can be used to define a tolerance band about the transmission function G . For example, the relative
 10 limit can be between $\pm 5\%$ and $\pm 15\%$ in particular $\pm 10\%$ of G , so that for $W_K = 0,9$, W_{tol} equals $0,9 \cdot G$, for example, in order to define the lower limit of the tolerance band.

[0031] As an alternative to a fixed relative limit, a frequency-dependent relative limit $W_K(f)$ can be defined, for example one in which the distance to G is greater at low
 15 and/or high frequencies than at medium frequencies. This takes measurement inaccuracies into account that can occur at low and high frequencies. The lower limit of the tolerance band then results from $W_{tol} = W_K(f) \cdot G$. For better readability and without restricting generality, here only $W_K(f)$ is representative of the time-continuous and time-discrete frequency-dependent limit $W_K(s)$, $W_K(z)$ (where $\omega = 2\pi f$, i.e. $s =$
 20 $j\omega = j2\pi f$ bzw. $z = e^{j\omega} = e^{j2\pi f}$).

[0032] According to a third variant, the tolerance band can be determined from a measurement of a number n , preferably a plurality of different secondary paths, for each of which a separate transmission function G_j is then determined as described
 25 above. Since the behavior of the secondary path changes from person to person when the insertion position of the earbud 8 is changed relative to the auditory canal 5 and in the case of changes in the auditory canal, a specific secondary path always results for the particular individual case from a multiplicity of possible secondary paths. In order to obtain a robust controller, i.e. one that is adapted for a multitude of
 30 different users and situations, it therefore makes sense to "simulate" different situations for the secondary paths and to measure them, so that it becomes clear from the number of different secondary paths what range of dispersion the controller must cover in order to provide the best results for the suppression of the occlusion effect in each case.

[0033] In view of the diverse auditory canals 5 that are anatomically possible, it makes sense to consider at least one of the following two extreme cases in the number n of secondary paths, namely an extreme case "free field" and an extreme case "sound channel closure."

[0034] In the extreme case "free field", the secondary path through the auditory canal 5 is determined without closure of the sound channel 11. This means that the earbud 8 is not introduced here into the auditory canal 5, resulting in an "acoustic open state." This extreme case virtually simulates an infinitely long auditory canal 5, or one with an especially large volume, although such a case is anatomically impossible. However, the removal of the hearing aid is thus modelled.

[0035] In the extreme case of "sound channel closure" the secondary path is measured with a directly closed sound channel 11. This means that the housing of the earbud 8 is closed, so that the sound emitted by the speaker 2 cannot escape from the earbud 8, thus creating a kind of "acoustic short circuit" between speaker and microphone. This extreme case virtually simulates an infinitely short auditory canal 5, or one with an especially small volume, although such a case is also anatomically impossible. This extreme case can occur during insertion of the hearing aid when the sound channel is closed off momentarily.

[0036] In view of the various possibilities for seating the earbud 8 in the auditory canal 5, it makes sense given the number n of secondary paths to consider, in addition or as an alternative to the above-described extreme cases, at least one case in which a loose fit of the earbud 8 in the auditory canal 5 is assumed and/or at least one case in which a tight fit of the earbud 8 in the auditory canal 5 is assumed. These cases can be carried out on the above-described anatomical model of a nominal/average human auditory canal, for example. Alternatively, different models with different auditory canals can also be used and the measurement of the secondary paths performed on each of them. As an alternative to the models, real people can also be used. According to another alternative, it is also possible to use an anatomical model of a variable-volume auditory canal 5 in which measurement of

the secondary path is performed accordingly with different volumes of the auditory canal 5, for example a changeable basic volume of 2 cm².

[0037] If the hearing aid is to be customized for a particular individual user in any case, it is sufficient if a measurement of the secondary path is carried out on this user with different seatings, particularly a loose, normal, and tight fit of the earbud.

[0038] The number of measured secondary paths forms a database of transmission functions G_i where $i = 1 \dots j \dots n$, with n being the number of measured paths. The more different secondary paths are measured, the better it can be recognized how much the secondary path varies or will vary with the hearing aid 1.

[0039] The maximum relative or absolute deviation of all measured secondary paths G_j from the nominal secondary path G can then be determined from the data base G_i . For this purpose, a deviation E_{Gj} from the nominal secondary path G is initially determined for each of the measured secondary paths G_j , as shown below using the example of the absolute deviation E_{Gj} :

$$E_{Gj}(j\omega) = G_j(j\omega) - G(j\omega)$$

[0040] If the relative deviation E_{Gj} is to be used, the following applies:

$$E_{Gj}(j\omega) = \frac{G_j(j\omega) - G(j\omega)}{G(j\omega)}$$

[0041] The frequency-dependent maximum is then determined from all deviations E_{Gi} , i.e. the maximum deviation is determined for each frequency from all deviations and defined as the limit WM of the tolerance band to be established:

$$|W_M(j\omega)| = \max_{G_i} |E_{Gi}(j\omega)|$$

[0042] An exemplary profile of the frequency-dependent maximum deviation or frequency-dependent limit $W_M(j\omega)$ for the nominal secondary path $G(s)$ is shown in FIG. 4. A continuous Laplace domain model for the tolerance band $W_{tol}(s)$ is

5 obtained by modeling the frequency-dependent limit $W_M(j\omega)$. This modeling can be performed, for example, using a minimal-phase filter with the aid of the so-called log-Chebyshev magnitude design as described, for example, in Boyd, S. and Vandenberghe, L., "Convex Optimization," Cambridge University Press, 2004. This yields the first requirement, the tolerance band $W_{tol}(s)$. As an alternative to the
10 variable s , the requirement can be expressed time-discretely with the argument z .

[0043] Preferably, the lower limit W_M determined according to the third variant can be modified such that the maximum deviation at low and/or high frequencies is increased compared to the middle frequencies, for example between 2 percent and
15 10%, preferably around 5%. This takes into account the fact that measurements are always flawed and the signal-to-noise ratio (SNR) is worse at low and high frequencies during the measurement. This can be taken into account in the robustness of the controller by increasing the maximum deviation.

20 [0044] According to a fourth variant, the tolerance band can be determined by an estimation.

[0045] After the first requirement is determined in the form of a tolerance band about the transmission function of the secondary path, a second requirement is determined
25 according to the invention in the form of a desired sensitivity function S_{gew} that the hearing aid 1 is to have, step S4. This, too, can be achieved in various ways.

[0046] The sensitivity function S describes the behavior of the overall feedback system consisting of controller 15 secondary path G from its input $d(t)$ to its output
30 $e(t)$, the input being formed by the electrical interference signal $d(t)$ and the output being formed by the electrical error signal $e(t)$. This becomes clear from FIG. 2 that shows a time-continuous model view of the overall feedback system in the absence of a useful signal, with the time-continuous interference signal $d(t)$ forming the input of the model and the time-continuous error signal $e(t)$ forming the model output. A

time-continuous model 17 of the controller K and a time-continuous model 16 of the secondary path G form the feedback branch here. The model of the overall system according to FIG. 2 is extended by weight functions $W_1(s)$, $W_2(s)$ $W_3(s)$, the meaning and significance of which will be explained below.

5

[0047] The sensitivity function S is obtained mathematically according to the equation

$$S = \frac{1}{1 + G \cdot K}$$

10

[0048] This describes the influence of the interference signal $d(t)$ on the error signal $e(t)$ or the reaction sensitivity of the error signal $e(t)$ to a change in the interference signal $d(t)$, so that it also represents the attenuation of the feedback system. In other words, it is the transmission function from the interference signal $d(t)$ to the error signal $e(t)$.

15

[0049] For the sensitivity function S, a complementary sensitivity function T exists for all frequencies,

$$T = \frac{G \cdot K}{1 + G \cdot K}$$

20

so that the product of complementary sensitivity function T and sensitivity function S is equal to 1. The complementary sensitivity function T describes the influence of the interference $d(t)$ on the compensation signal $y(t)$, i.e. the output of the secondary path and hence also the influence of measurement noise on the compensation signal. It thus reflects the robustness of the system, particularly including against interference due to measurement noise.

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[0050] Ideally, the sensitivity function S should be small, minimizing interference. At the same time, the complementary sensitivity function T should be small, so that measurement noise has minimal effect. In view of the fact that the sum of sensitivity function S and complementary sensitivity function T is equal to one, however, these

two requirements are mutually opposed and cannot be fulfilled simultaneously. This is also referred to as the "fundamental dilemma" of feedback regulation.

5 [0051] The above-described representations of the sensitivity function S and the complementary sensitivity function T can be written as a function of the time-continuous complex variable s or of the time-discrete variable z .

10 [0052] The aim is to form the sensitivity function S so that it corresponds to the inverse of the transmission function G_{OE} of the occlusion effect, since this is to be suppressed according to the invention. Since the occlusion effect is different in the person, the compensation must be ideally adapted to the person.

15 [0053] According to a first design variant, the sensitivity function S_{gew} can be specified manually in the form of a desired sensitivity. For example, the sensitivity function can be configured such that an attenuation of at least 10 dB is present in certain frequency ranges. This can be done in the modeling of S_{gew} , for example through combined high and low passes.

20 [0054] According to a second design variant, the sensitivity function S_{gew} can be specified manually from empirical data on the occlusion effect. The empirical data can be obtained through actual measurements on subjects or from data in the literature; for example, see Part II, page 6.2, FIG. 6.1 of M. Ostergaard Hansen, "Occlusion Effects Part I and II," PhD thesis, Technical University of Denmark, Denmark, 1998. If the frequency-response characteristic of the occlusion effect is
25 known from these data, the sensitivity function can be calculated accordingly.

[0055] According to a third design variant, the determination of the sensitivity function S_{gew} from the measurement of the objective occlusion effect can be carried out specifically for the person who will later wear the hearing aid. A customized design of
30 the controller is thus achieved.

[0056] It should be noted here that, in terms of control engineering, two levels of customization exist for the individual adaptation of the hearing aid to a person. To wit, customization of the hearing aid can be achieved through adaptation of the

secondary path to the individual auditory canal 5 and/or through adaptation of the sensitivity function S.

[0057] The objective occlusion effect is characterized by the objectively measurable
 5 difference between the acoustic signal on the eardrum when the ear canal is open
 and when the ear canal is closed. Thus, it only partially affects the individual
 subjective perception of one's own voice, since the perception of the voice also
 includes influences of the middle and inner ear. The objective occlusion effect cannot
 be measured with a measurement signal that is emitted via an internal or external
 10 speaker, because the occlusion effect also includes structure-borne sound
 components $x'_{BC}(t)$ that cannot be generated via a speaker. In particular, the
 concrete relationship between airborne sound component $x'_{AC}(t)$ and structure-borne
 sound component $x'_{BC}(t)$ during dynamic vocal excitation is not easily determined. It
 must therefore be determined with the person's own voice, meaning that the person's
 15 own voice is the measurement signal. Using two microphones calibrated to one
 another at different measurement positions, with an internal microphone being
 located inside the ear and an external microphone being located outside the ear, the
 person pronounces [i:], for example, resulting in a particularly strong occlusion effect,
 or reads a phonetically balanced text aloud that reflects natural usage, which
 20 corresponds to a medium occlusion effect. The resulting microtone signals are
 recorded. The external microphone thus provides a microtone signal corresponding
 to the airborne sound component $x'_{AC}(t)$, and the internal microphone provides a
 microtone signal corresponding to the sound $d'_{occl}(t)$ occurring in the auditory canal 5
 when the auditory canal is closed. The frequency-dependent occlusion effect can be
 25 determined through spectral division of the Fourier transforms $D'_{occl}(f)$ and $X'_{AC}(f)$ of
 the respective time signals $d'_{occl}(t)$ and $x'_{AC}(t)$. A transmission function that
 approximately reflects the occlusion effect can be obtained according to the following
 equation.

30
$$G_{OE}(f) = \frac{|D'_{occl}(f)|}{|X'_{AC}(f)|}$$

[0058] The fact that this transmission function of the occlusion effect $G_{OE}(f)$ is only
 an approximate determination of the occlusion effect is evident because the so-called

open ear canal characteristic (Real Ear Unoccluded Gain (REUG)) is missing from the calculation but would actually have to be in the denominator of the above equation in order to accurately determine the frequency-dependent occlusion effect. Additional information on the determination of the objective occlusion effect can be found in EP 2 640 095 A1.

[0059] Ideally, the desired sensitivity function S_{gew} of the hearing aid is then determined from the transmission function of the occlusion effect G_{OE} as the inverse of the transmission function of the occlusion effect G_{OE} :

$$S_{gew} = \frac{1}{G_{OE}}$$

[0060] In view of the necessity of the technical implementability of the controller 15 in a DSP, it is advantageous to reduce the order that the transmission function G_{OE} determined from the measured occlusion effect has, since a DSP has only limited computing power. The implementable order depends here decisively on the sampling rate $1/T_S$ used in the digital system. In real systems, and at a sampling rate of $1/T_S = 48000 \text{ Hz}$, the transmission function can have an order of between 10 and 20 in FIR (Finite Impulse Response) and IIR (Infinite Impulse Response).

Since the overall order of the controller results from the sum of the orders of the transmission function of the secondary path, the tolerance band, and the sensitivity function, an order of between 30 and 40 can quickly arise here. In order to make implementation possible, it may be necessary to perform a downstream order reduction.

[0061] According to a preferred development, the transmission function G_{OE} of the occlusion effect can therefore be approximated by a compensation curve W_A (polynomial) of an order of between 5 and 10, preferably of the order 6, as shown in FIG. 5. While a higher order would improve the compensation, this would also place greater demands on the DSP. The inverse of the compensation curve W_A can then be established as the second requirement or desired sensitivity function S_{gew} of the hearing aid.

[0062] According to another development, in order to reduce the order even further, the compensation curve can have at least one recursive component, as is known in so-called IIR filters or IIR systems (IIR Infinite Impulse Response). This is characterized in a transmission function in the z-range by coefficients in the denominator, which cause feedback of the filter output.

$$H(z) = \frac{b_0 + b_1 z^{-1} + b_2 z^{-2} + \dots + b_Q z^{-Q}}{a_0 + a_1 z^{-1} + a_2 z^{-2} + \dots + a_R z^{-R}}$$

[0063] In general, the order in FIR component (numerator) and in the IIR component (denominator) can have different orders Q and R.

[0064] The order reduction can be applied not only during the determination of the sensitivity function, but also during or after the determination of the transmission function for the nominal secondary path and during the determination of the tolerance band, since the overall order of the overall feedback system results from the sum of the orders of these three system components. An approximation can thus be made for the nominal measured secondary path as well by a curve with an order that is lesser than the order of the measured nominal secondary path. The same applies to the determined tolerance band.

[0065] Once the first requirement and the second requirement have been determined, the digital controller is designed according to the invention by an optimization method with simultaneous consideration of the first and second requirements, step S5.

[0066] A model of the system consisting of secondary path and controller can first be set up for this purpose using the example of continuous-time quantities as shown in FIG. 2. In this example, the interference signal d(t) is the input quantity and the error signal e(t) resulting from the difference between the interference signal d(t) and the compensation signal y(t) is the model output quantity. The controller 17 and a downstream model 16 of the secondary path are in the feedback branch, so that the controller 17 receives the error signal e(t) as an input signal and the compensation

signal $y(t)$ forms the output signal of the secondary path model 16, which is negatively fed back onto the interference signal.

[0067] For the controller design, the two determined requirements must now be incorporated into the model, for example by expanding the system model. According to one design variant, the so-called $\mathcal{H}_\infty$ -controller design method can be used for this purpose, preferably the special "Mixed Sensitivity $\mathcal{H}_\infty$," controller design method as described in S. Skogestad and I. Postlethwaite, "Multivariable feedback control: analysis and design," John Wiley and Sons, 2005. This method uses the extended system model already shown in FIG. 2, particularly at least two of the three weighting functions W_1 , W_2 and W_3 shown there. The $\mathcal{H}_\infty$ controller design method is the general design method that also enables system models other than shown in FIG. 2 to be employed. The "mixed sensitivity $\mathcal{H}_\infty$ " controller design method is characterized particularly by the system model shown in FIG. 2. Furthermore, the design can be performed using other methods, such as the $\mathcal{H}_2$ controller design method, for example.

[0068] The weighting functions W_1 , W_2 and W_3 represent transfer functions that, in the example model here, have a single input and a single output. The error signal $e(t)$ is fed to the first weighting function W_1 so that it receives the same signal input as the controller 17. The second weighting function W_2 receives the output signal $y_r(t)$ of the controller 17 as input, and the third weighting function W_3 receives the output signal of the secondary path model 16 with the transmission function G as input. The mathematical relationships are indicated here in the Laplace domain, i.e. in the continuous-time spectral range, so that the quantities are written as a function of the variable s . However, it is also possible to use the time-discrete spectral range here, i.e. the Z domain, i.e. to write the quantities as a function of the variable z . These representations can be converted into one another by the Tustin method, in which the following applies:

$$z = e^{sT_s} = \frac{1 + \frac{T_s}{2} \cdot s}{1 - \frac{T_s}{2} \cdot s}$$

[0069] The first weighting function $W_1(s)$ reflects the desired overall transmission function of the system and thus represents the performance of the system. The second weighting function $W_2(s)$ reflects the uncertainty in the secondary path in absolute terms, i.e. how much it varies due to different users and/or different location of the earbud in the auditory canal, and thus represents the robustness of the system. The same applies to the third weighting function $W_3(s)$, but in relative form to the nominal secondary path G .

[0070] It follows that the weighting functions $W_1(s)$, $W_2(s)$ and $W_3(s)$ can be used to describe the first and second requirements, so that the requirements can be introduced into the model by these weighting functions $W_1(s)$, $W_2(s)$ and $W_3(s)$.

[0071] The first weighting function $W_1(s)$ can be determined from the second requirement, and the second or third weighting function $W_2(s)$, $W_3(s)$ from the first requirement. Preferably, the first weighting function $W_1(s) = 1/S_{gew}(s) = G_{OE}(s)$ and is particularly equated with the compensation curve $W_1(s)=W_A(s)$. If the deviation E_{Gj} of the measured secondary paths G_j from the nominal secondary path G has been determined in absolute form, then $W_2(s) = W_{tol}(s)$ and $W_3(s) = 0$ can be set. If the deviation E_{Gj} of the measured secondary paths G_j from the nominal secondary path G has been determined in relative form, then $W_2(s) = 0$ and $W_3(s) = W_{tol}(s)$ can be set.

[0072] Each of the weighting functions $W_1(s)$, $W_2(s)$, $W_3(s)$ provides its own output $z_1(t)$, $z_2(t)$, $z_3(t)$ of the model, which are combined into a vector $\mathbf{z}(t)$ in FIG. 2:

$$\mathbf{z}(t) = \begin{pmatrix} z_1(t) \\ z_2(t) \\ z_3(t) \end{pmatrix}$$

[0073] This vector thus forms a combined output of the model. The aim of the $\mathcal{H}_\infty$ controller design method is to design the controller K such that the ∞ norm of the transmission function $\mathbf{T}_{zd}(S)$ of the model is minimized from its input $d(t)$ to the combined output $\mathbf{z}(t)$. This transmission function $\mathbf{T}_{zd}(S)$ is also a vector in the defined model and can be represented as follows in the Laplace domain:

$$T_{zd}(s) = \begin{pmatrix} W_1(s) \cdot S(s) \\ W_2(s) \cdot K(s) \cdot S(s) \\ W_3(s) \cdot K(s) \cdot G(s) \cdot S(s) \end{pmatrix} = \begin{pmatrix} W_1(s) \cdot S(s) \\ W_2(s) \cdot K(s) \cdot S(s) \\ W_3(s) \cdot T(s) \end{pmatrix}$$

- [0074] It is on this basis that the ∞ -norm is now formed and an analysis is performed
5 to determine for which $K(s)$ it becomes minimal:

$$\min_K \|T_{zd}(s)\|_\infty$$

$$\|T_{zd}(s)\|_\infty = \left\| \begin{pmatrix} W_1(s) \cdot S(s) \\ W_2(s) \cdot K(s) \cdot S(s) \\ W_3(s) \cdot T(s) \end{pmatrix} \right\|_\infty = \gamma$$

- 10 [0075] This can be done by solving two Riccati equations, as is proposed in "J. C. Doyle, K. Glover, P. P. Khargonekar, and B. A. Francis, "State-space solutions to standard H_2 and H_∞ control problems, "IEEE Transactions on Automatic Control," vol. 34, no. 8, pp. 831-847, 1989".
- 15 [0076] The $\mathcal{H}_\infty$ norm is defined as follows as the absolute peak value (supremum) of the maximum singular value $\bar{\sigma}(T_{zd})$:

$$\|T_{zd}(s)\|_\infty = \sup_{\omega} \bar{\sigma}(T_{zd}(j\omega))$$

- 20 [0077] The supremum, which describes an upper limit of an infinitely extended function, is simplified here to the simple maximum value for finite functions. In the most general case, the maximum singular value $\bar{\sigma}(T_{zd})$ is the root of the largest eigenvalue λ_i of the matrix product from the complex conjugate transmission function T_{zd}^H and the unchanged transmission function T_{zd} of the extended system model:

25

$$\lambda_i = \text{eig}(T_{zd}^H T_{zd})$$

$$\bar{\sigma}(T_{zd}) = \sqrt{\max_i(\lambda_i)}$$

[0078] For a system with an input and an output, this expression can be reduced to the Euclidean vector norm by the transmission function $T_{zd}(S)$; see “S. Skogestad and I. Postlethwaite, Multivariable feedback control: analysis and design, John Wiley and Sons, 2005”. The $\mathcal{H}_\infty$ norm of the vector-valued transmission function T_{zd} can thus be expressed as

$$\|T_{zd}(s)\|_\infty = \max_{\omega} \sqrt{|W_1 S|^2 + |W_2 R|^2 + |W_3 T|^2}$$

[0079] The maximum absolute value of the weighted sensitivities is thus sought over all frequencies ω . If the optimization has worked, it is ensured that $\|W_1(s) \cdot S(s)\|_\infty$ is always less than or equal to the threshold value γ . If the requirements were too stringent, they can be softened within the optimization until a controller can be found. If the optimization produces a controller that contains $\gamma = 1$, all requirements are met. If $\gamma < 1$, a controller was found that is better than the requirements. For $\gamma > 1$, the requirements had to be reduced.

[0080] With the $\mathcal{H}_\infty$ controller design method, a controller K can be found that satisfies both set conflicting requirements, i.e. the performance defined with the desired sensitivity function on the one hand and the robustness defined with the tolerance band, and is ideally even better. To wit, the identified controller K can result in a sensitivity function $S=1/(1+G \cdot K)$ in the overall system, which is better than the desired sensitivity function S_{gew} , meaning that their damping amplitude $|S(j\omega)|$ for all frequencies lies below or at most at the damping amplitude $|S_{gew}(j\omega)|$ of the desired sensitivity function S_{gew} :

$$|S(s)| \leq |S_{gew}(s)| = \frac{1}{|W_1(s)|}$$

[0081] This is shown in the Bode diagram in FIG. 6. It is immediately clear from the above inequality that $|W_1(s) \cdot S(s)| \leq 1 = \gamma$, i.e. that with proper optimization, the sensitivity function $S(s)$ of the system with the identified controller K coincides

maximally with the desired sensitivity function S_{gew} at individual frequencies. If the threshold $\gamma > 1$, then at least one of the two requirements must be moderated in order to find a controller that satisfies the requirements. The search for a corresponding controller K using the optimization method is then repeated
 5 accordingly.

[0082] As the last step S6 of the method according to the invention, the identified controller K is implemented in the control unit 9 as is generally known in the prior art. This implementation can preferably take place as a digital controller, for example in
 10 the form of a FIR/IIR filter, or in state space representation on a DSP of the control unit. For this purpose, after the designing of the time-continuous controller $K(s)$, a further discretization is performed, whereby $K(z)$ is obtained. Moreover, in addition or as an alternative to the above-described order reduction for secondary path, tolerance band, or sensitivity function, an order reduction of the designed controller
 15 can be carried out with the specified methods.

List of Reference Symbols

[0083]
 20
 1 hearing aid
 2 speaker
 3 error microphone
 4 auricle
 25 5 auditory canal, ear canal
 6 eardrum
 7 feedback branch
 8 earbud
 9 control unit
 30 10 time-continuous system model
 11 sound channel
 12 digital model of the secondary path
 13 analog-to-digital converter
 14 digital-to-analog converter

- 15 digital controller
- 16 time-continuous model of the secondary path
- 17 time-continuous controller
- 18 external microphone
- 5 19 signal processing

General:

[0084]

10

- ' Quantities provided with a prime denote acoustic analog signals
- $\sim$ Quantities provided with a tilde denote modified quantities
- $\wedge$ Quantities provided with a circumflex denote estimated quantities

f frequency in Hz

15

T_s sampling interval

ω angular frequency

t variable for the time of time-continuous quantities

k index variable for the time of time-discrete quantities

s complex parameter of a time-continuous function transformed into the

20

frequency domain by the Laplace transformation

z complex parameter of a discretized/digital function transformed into the frequency domain by Z-transformation

G overall transmission function of the nominal secondary path

G_i totality of transmission functions n of different secondary paths

25

G_j j -th transmission function of the totality G_i

W_{tol} tolerance band about the transmission function of the secondary path for describing the uncertainty of the secondary path

W_K fixed relative limit

$W_K(f)$ frequency-dependent relative limit W_M lower limit of the tolerance band

30

E_{Gj} deviation of the different secondary paths from the nominal secondary path

G_{OE} transmission function of the occlusion effect

- W_1 function for the optimization; reflects the desired overall transmission function
- W_3 weighting function for the optimization that reflects the uncertainty in relative form
- H_∞ H infinite
- 5 G_{rec} transmission function of the speaker
- G_{mic} transmission function of the internal microphone
- G_{acoust} acoustic transmission function between internal speaker and internal microphone
- $x'_{AC}(t)$ airborne sound signal (consisting of a combination of one's own voice and ambient noises)
- 10 $x'_{BC}(t)$ bone-/structure-borne sound signal (contains predominantly one's own voice)
- $d'(t)$ acoustic internal interference signal
- $d(t)$ electrical internal interference signal
- $e'(t)$ acoustic internal error signal
- 15 $e(t)$ electrical internal error signal
- $\tilde{y}'(t)$ acoustic internal compensation signal
- $y(t)$ electrical internal compensation signal
- $\tilde{y}(k)$ digital modified compensation signal (emitted via speaker)
- $y_r(k)$ digital controller output signal/compensation signal
- 20 $y_r(t)$ continuous controller output signal/compensation signal
- $a(k)$ digital useful signal/audio signal
- $e(k)$ digital error signal
- $\tilde{e}(k)$ modified digital error signal
- $\hat{G}(z)$ estimated transmission function of the nominal secondary path
- 25 $G(s)$ time-continuous model of the secondary path
- $K(z)$ transmission function of the controller
- $K(s)$ continuous model of the controller
- $W_1(s)$ continuous weighting function for optimization, for obtaining a desired overall transmission function of the hearing aid

	$W_2(s)$	continuous weighting function for the optimization that reflects the uncertainty in absolute form
	$W_3(s)$	continuous weighting function for the optimization that reflects the uncertainty in relative form
5	$z(t)$	weighted output vector of the extended model
	$T_{zd}(s)$	vectorial transmission function between the interference signal $d(t)$ and the weighted output vector of the regulation system $z(t)$
	$T_{zd}^H(s)$	complex conjugate vectorial transmission function between the interference signal $d(t)$ and the weighted output vector of the regulation system $z(t)$
10	$S(s)$	continuous sensitivity function/transmission function of the overall system
	$S_{gew}(s)$	desired sensitivity function/transmission function of the overall system
	$d'_{occl}(t)$	sound occurring in the auditory canal 5 when the auditory canal is closed
	$T(s)$	continuous complementary sensitivity function
15	$D'_{OCCL}(f)$	Fourier transform of the time signal $d'_{occl}(t)$
	$X'_{AC}(f)$	Fourier Transform of the Time Signal $x'_{AC}(t)$
	γ	upper limit for the sensitivity function in the controller design method
	λ_i	i-th eigenvalue
	W_A	compensation function through the occlusion function
20	R	product of controller K and sensitivity function S

P a t e n t k r a v

1. Fremgangsmåde til udformning af en regulator (15, 17) til et hørehjælpemiddel (1) til at kompensere for okklusionseffekten ved udsendelse af et akustisk anvendeligt signal i øregangen (5) i et menneskeøre, hvor hørehjælpemidlet (1) omfatter en øreprop (8), der kan indføres i øregangen (5), med en højttaler (2) til udsendelse af et compensationssignal ($y(t)$, $\tilde{y}'(t)$) i øregangen (5) og en mikrofon (3) til optagelse af et fejlsignal ($e(t)$) fra øregangen (5) og en styreenhed (9) til bearbejdning af signalet, der skal udsendes og optages, og hvor fremgangsmåden omfatter følgende trin
- at måle en nominal sekundær sti mellem højttaleren (2) og mikrofonen (3) og fastlægge en overføringsfunktion (G), der beskriver den nominale sekundære stis adfærd,
 - at fastlægge en anmodning i form af en ønsket sensitivitetsfunktion (S_{gew}) af hørehjælpemidlet,
 - at udforme regulatoren (15, 17) ved hjælp af en optimeringsfremgangsmåde under hensyntagen til anmodningen og
 - at implementere regulatoren (15, 17) i styreenheden (9),
- kendetegnet ved, at** anmodningen er en anden anmodning, og fremgangsmåden omfatter fastlæggelse af en første anmodning i form af et tolerancebånd (W_{tol}) om overføringsfunktionen (G), og at udformningen af regulatoren (15, 17) sker ved hjælp af optimeringsfremgangsmåden under samtidig hensyntagen til den første og anden anmodning.
2. Fremgangsmåde ifølge krav 1, **kendetegnet ved, at** fastlæggelsen af tolerancebåndet sker ud fra en måling af et antal (n) af forskellige sekundære stier, hvortil der i hvert tilfælde bestemmes en egen overføringsfunktion (G_j), og den maksimale afvigelse af disse overføringsfunktioner derefter bestemmes til overføringsfunktionen (G) af den nominale sekundære sti, og den første anmodning fastlægges deraf.
3. Fremgangsmåde ifølge krav 2, **kendetegnet ved, at** antallet (n) af forskellige sekundære stier omfatter en sekundær sti, hvor øreproppen (8) ikke er indført i øregangen (5), og/eller en sekundær sti, hvor øreproppens (8) hus er

lukket på en sådan måde, at lyden, der afgives af højtaleren (2), ikke kan komme ud af øreproppen (8).

5 4. Fremgangsmåde ifølge krav 2 eller 3, **kendetegnet ved, at** antallet (n) af forskellige sekundære stier omfatter en sekundær sti, hvor øreproppen (8) er indført let i øregangens (5) begyndelsesområde, og/eller en sekundær sti, hvor øreproppen (8) er indført fast i øregangen (5).

10 5. Fremgangsmåde ifølge krav 4, **kendetegnet ved, at** målingen af de forskellige sekundære stier udføres ved forskellige øregange (5).

15 6. Fremgangsmåde ifølge et af kravene 2 til 5, **kendetegnet ved, at** den fastlagte maksimale afvigelse udgør den første anmodning eller først modificeres på en sådan måde, at der forefindes en forhøjning af afvigelsen til lave frekvenser og/eller høje frekvenser, og denne modificerede afvigelse anvendes som første anmodning.

20 7. Fremgangsmåde ifølge et af de foregående krav, **kendetegnet ved, at** der til fastlæggelse af den anden anmodning fastlægges en overføringsfunktion G_{OE} af den objektive okklusionseffekt, og dennes reciprokke værdi eller en funktion, der er afledt af overføringsfunktionen (G_{OE}), fastlægges som sensitivitetsfunktion (S_{gew}).

25 8. Fremgangsmåde ifølge krav 7, **kendetegnet ved, at** den afledte funktion er en udligningskurve af en lavere orden, fortrinsvis orden 6, der tilnærmer overføringsfunktionen G_{OE} af den objektive okklusionseffekt.

30 9. Fremgangsmåde ifølge et af de foregående krav, **kendetegnet ved, at** en model af hørehjælpemidlet (1), der dannes ud fra den sekundære sti (G) og regulatoren (15, 17), lægges til grund for udformningen af regulatoren (15, 17) og omfatter et forstyrrelsessignal ($d(t)$), der skal kompenseres, som indgangsstørrelse og fejlsignalet ($e(t)$), der resulterer af forskellen mellem forstyrrelsessignalet ($d(t)$) og compensationssignalet ($y(t)$), som udgang, hvor regulatoren (15, 17) og en model (16) af den sekundære sti, der er efterkoblet regulatoren

ligger i en tilbagekoblingsgren, således at regulatoren (15, 17) modtager fejl-signalet $e(t)$ som indgangssignal, og compensationssignalet ($y(t)$) udgør den sekundære stimodels (16) udgangssignal, der er tilbagekoblet negativt til forstyrrelsessignalet ($d(t)$).

5

10. Fremgangsmåde ifølge et af de foregående krav, **kendetegnet ved, at** $\mathcal{H}_\infty$ - eller $\mathcal{H}_2$ -regulatorudformningsfremgangsmåden eller en kombination af disse regulatorudformningsfremgangsmåder, fortrinsvis Mixed-Sensitivity $\mathcal{H}_\infty$ -regulatorudformningsfremgangsmåden anvendes som optimeringsfremgangsmåde.

10

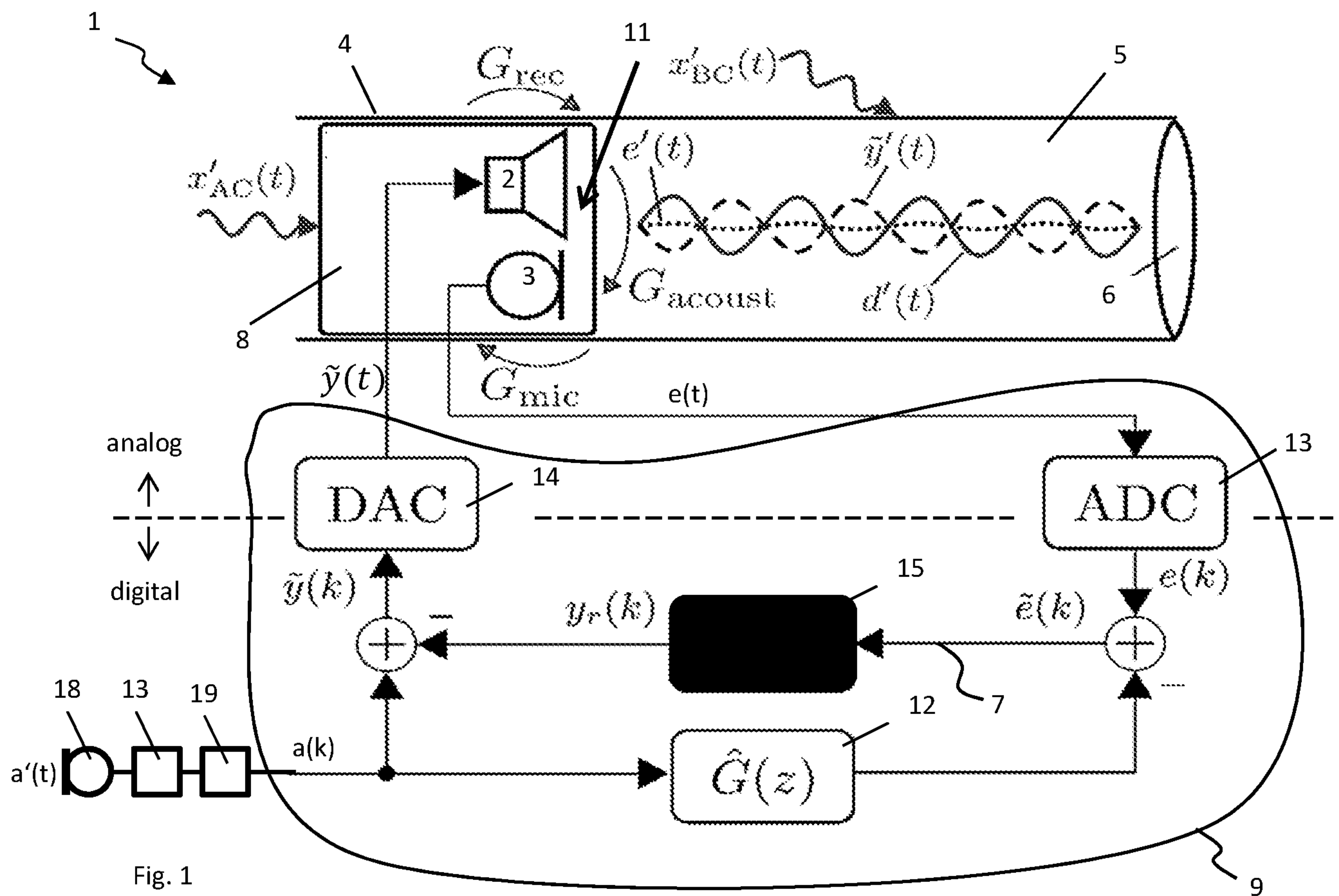


Fig. 1

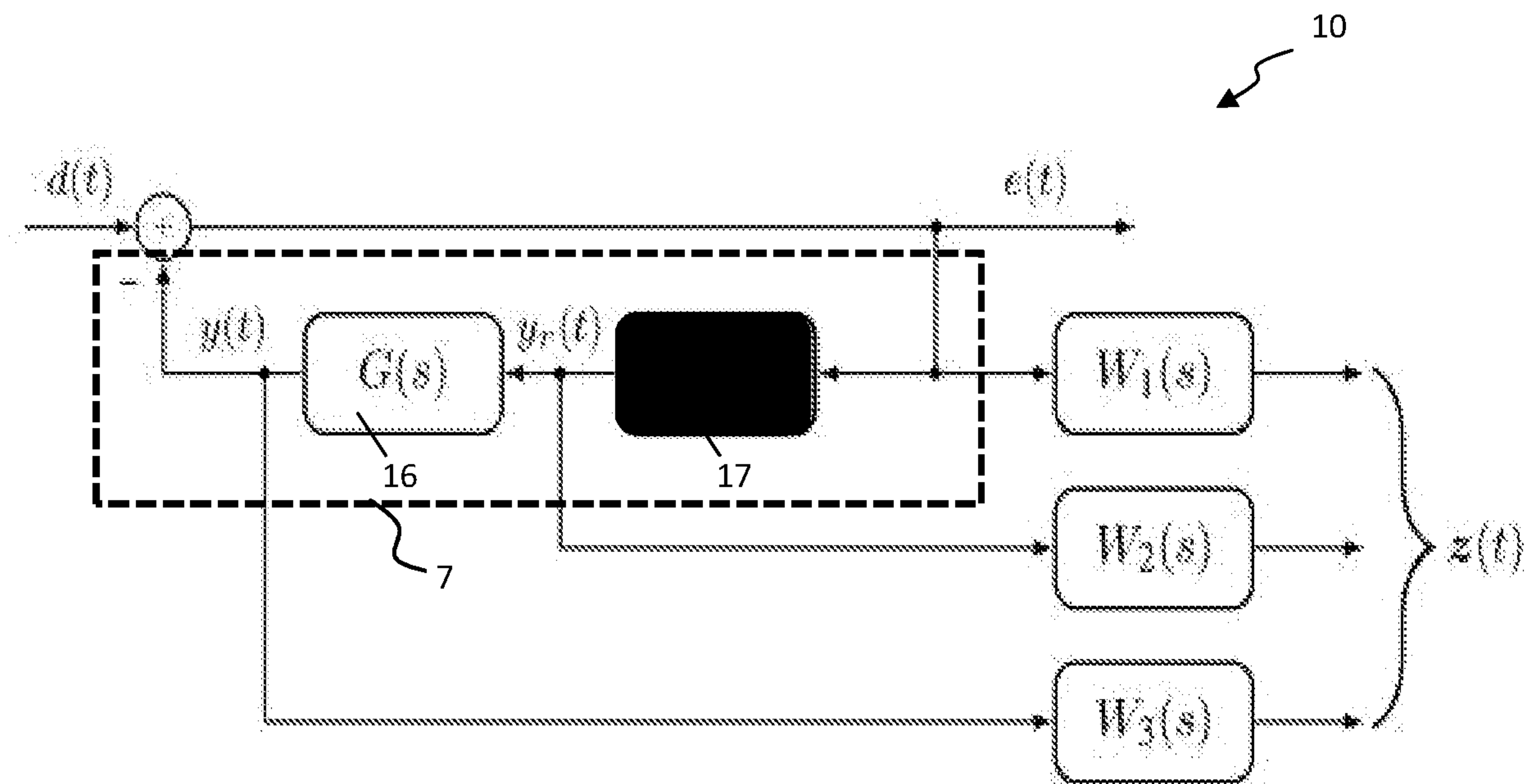


Fig. 2

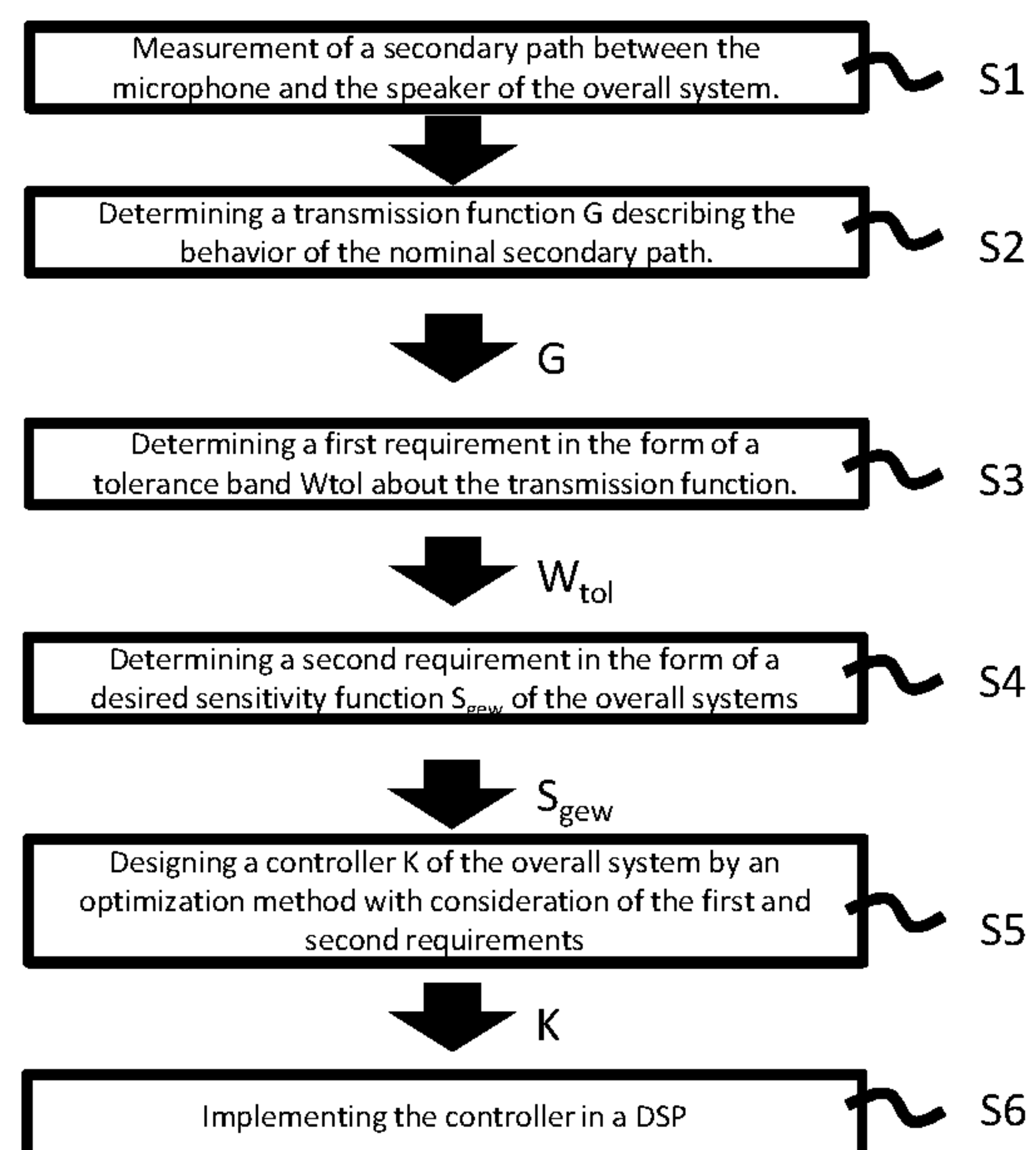


Fig. 3

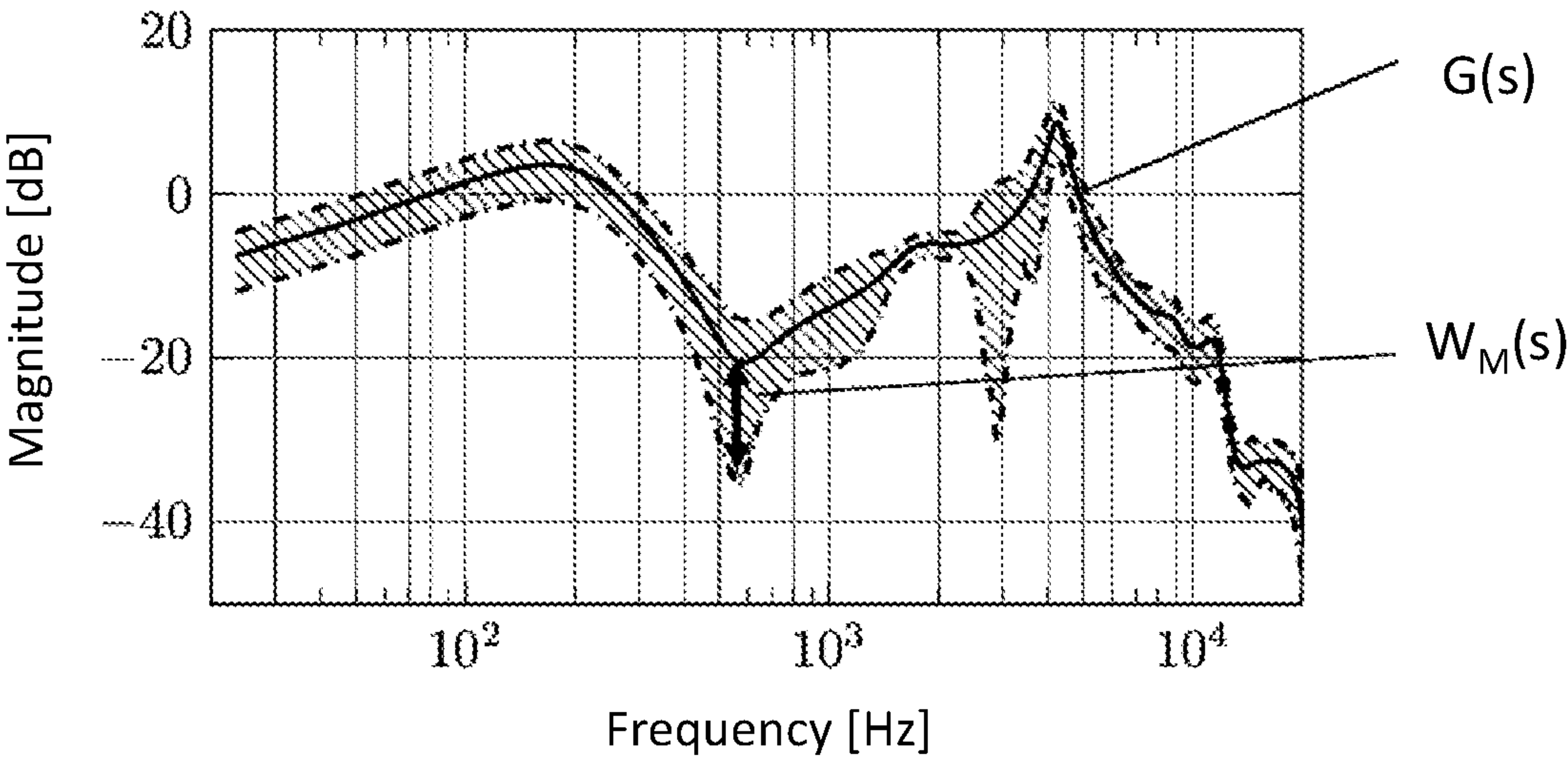


Fig. 4

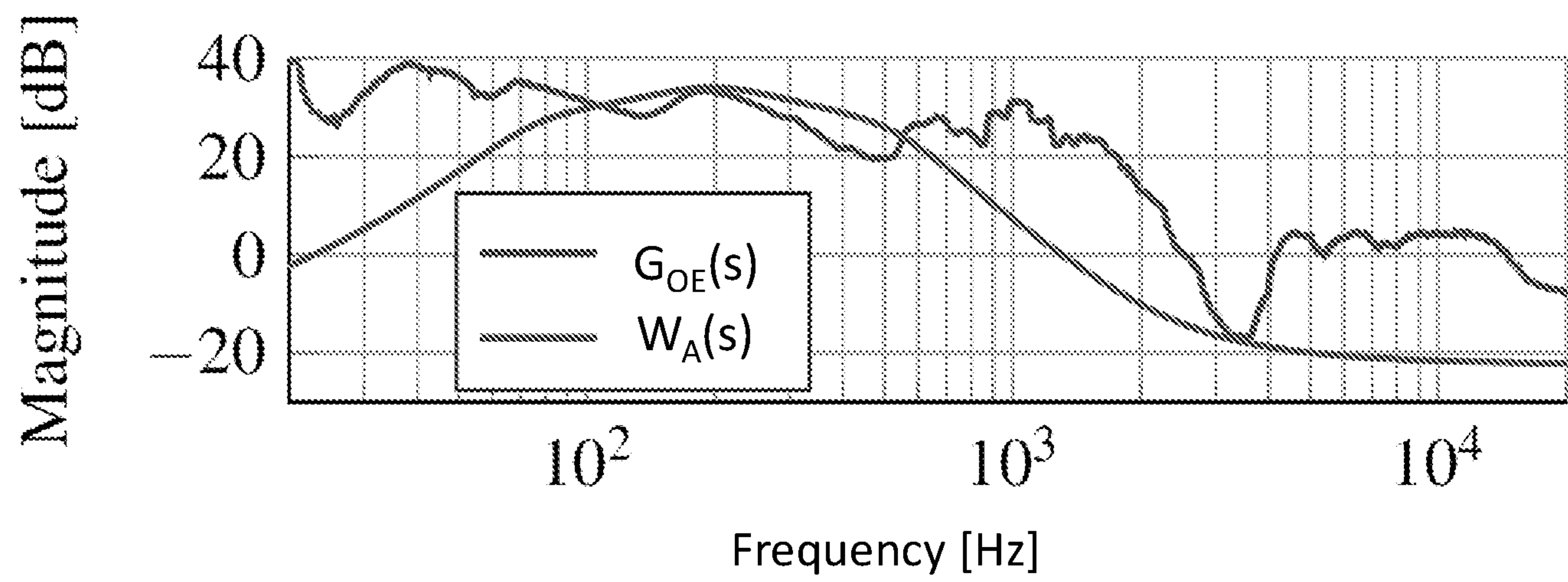


Fig. 5

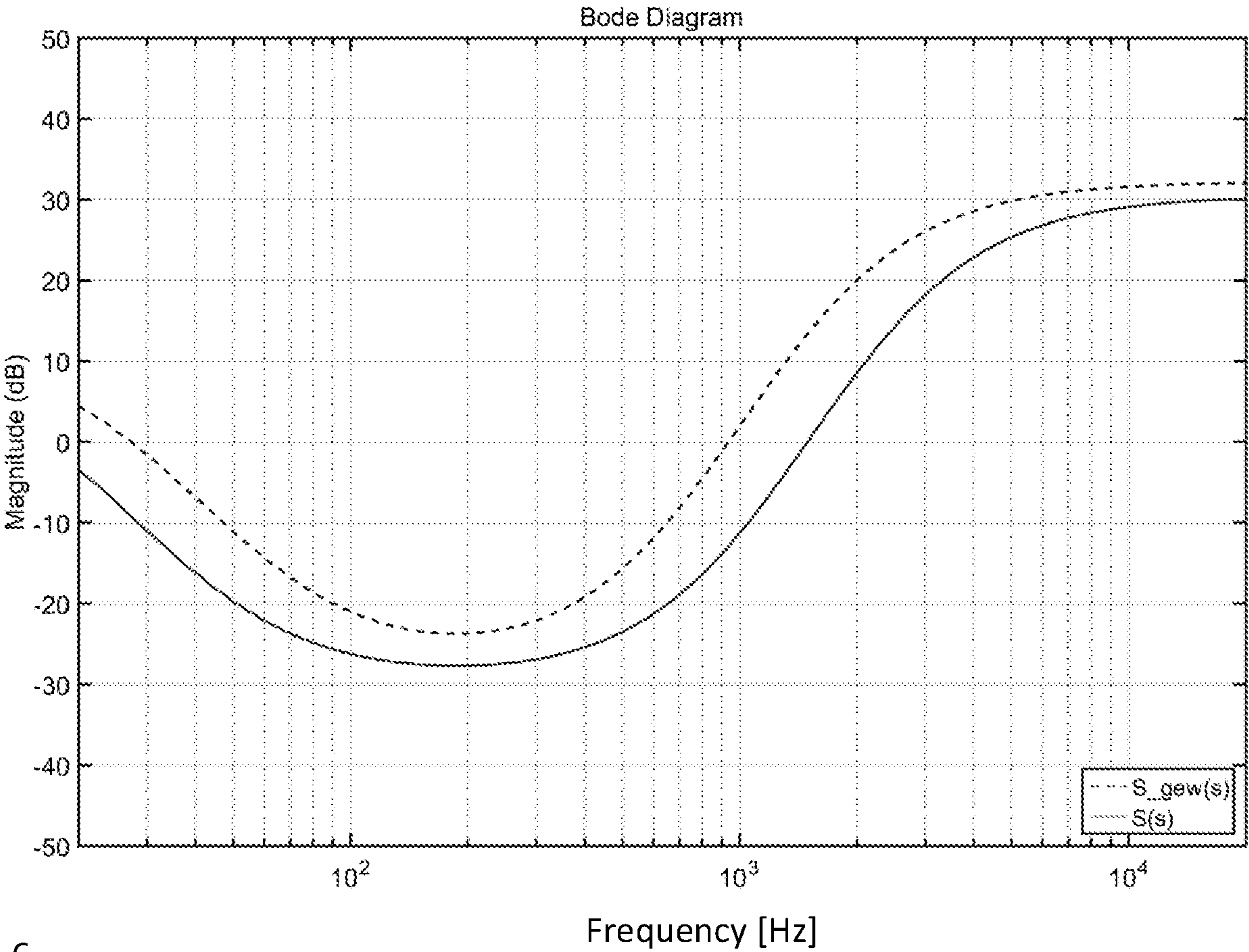


Fig. 6