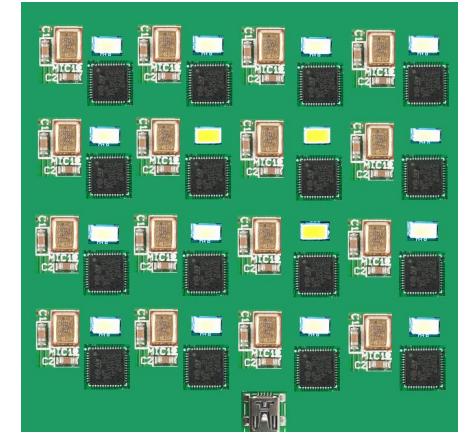
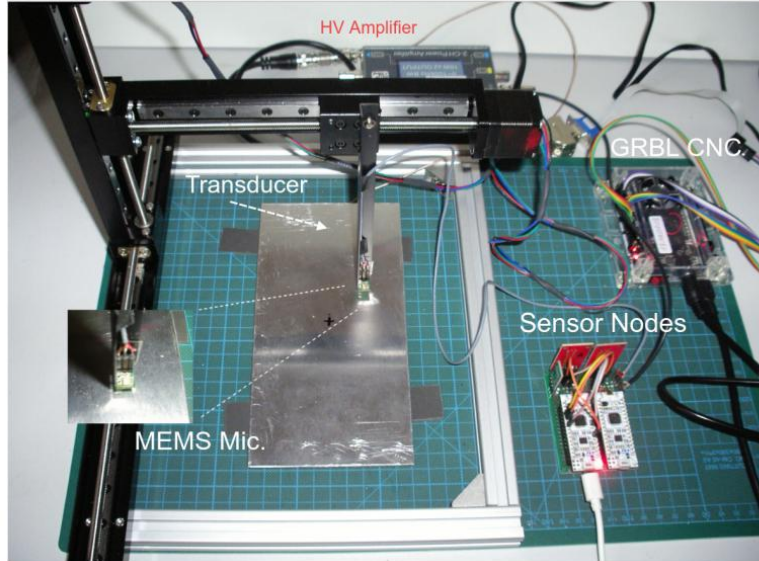
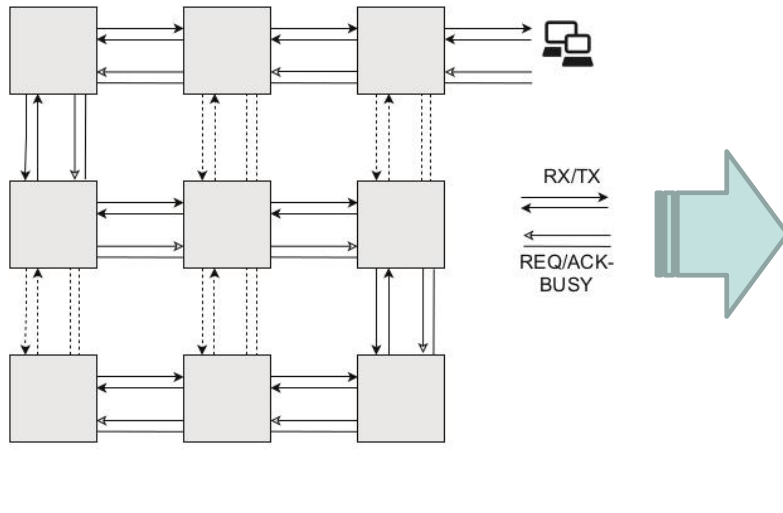


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TOWARDS AN AIR-COUPLED ULTRASONIC SENSOR NETWORK AND CAMERA FOR NON-DESTRUCTIVE TESTING WITH INTEGRATED MACHINE LEARNING

Stefan Bosse

Schall 2025 Conference



Praktische
Informatik

UK university
of koblenz
Computer Science

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INTRODCUTION

- For non-destructive testing (NDT) of structures, various methods are usually used.
- Among other methods, acoustic emission (AE) and guided ultrasonic wave (GUW) tests are often used to assess structures and to detect damages and defects.
- Both methods are characterized by high-dimensional time-dependent data.

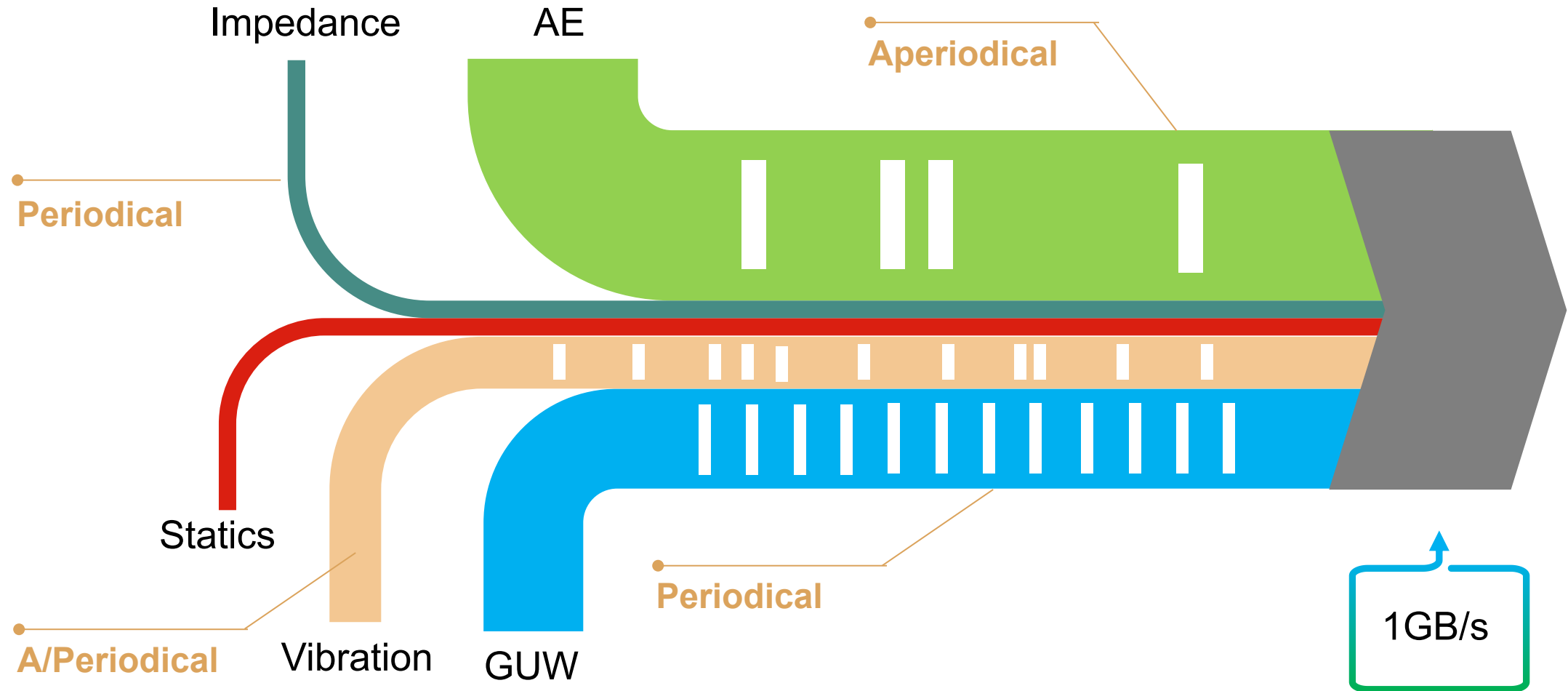


The use of a guided wave-based approach is due to the fact that these waves can propagate over relatively long distances and interact sensitively and specifically with various types of defects.

PROBLEM: DATA STREAMS IN NDT



Central Processing
not suitable

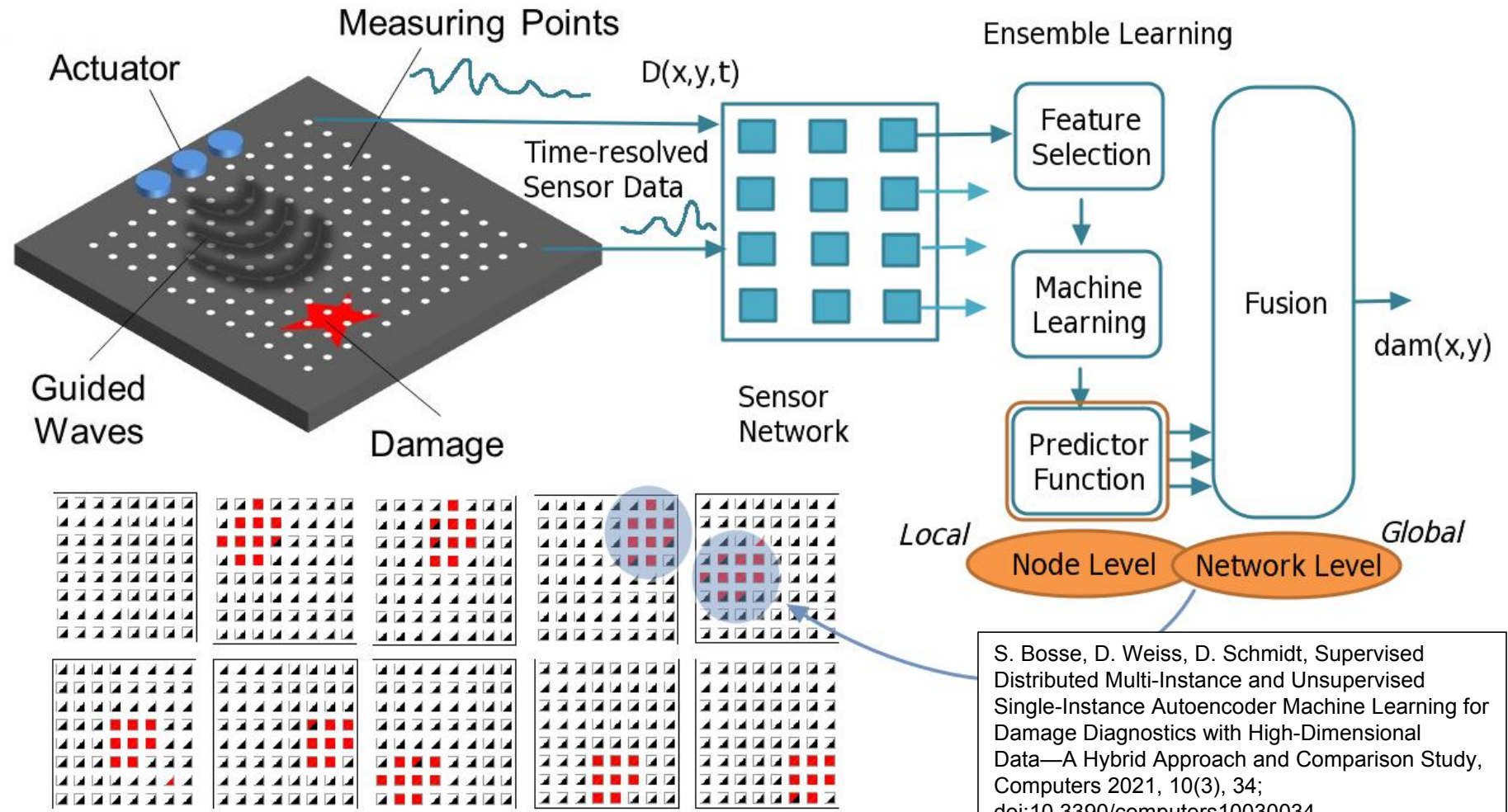


SENSORFUSION VERSA MODEL FUSION IN DISTRIBUTED SENSOR NETWORKS

Distributed Spatial Sensorfusion:

*Local State Estimation
(Damage and Anomaly Detection)*

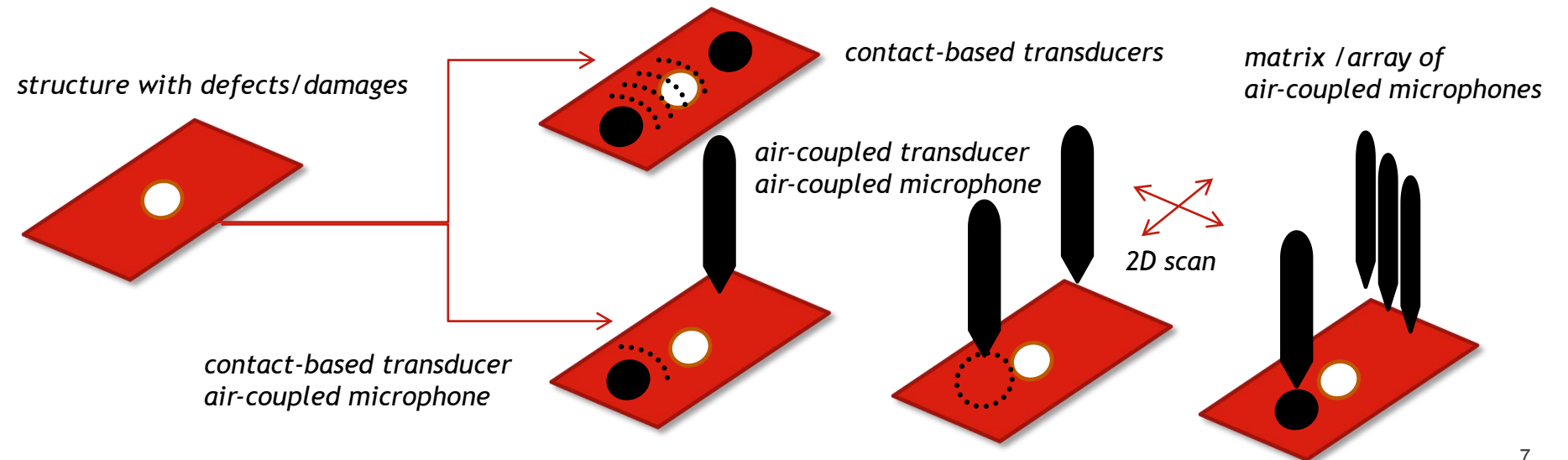
*Global Fusion
(Localization and Aggregation)*



S. Bosse, D. Weiss, D. Schmidt, Supervised Distributed Multi-Instance and Unsupervised Single-Instance Autoencoder Machine Learning for Damage Diagnostics with High-Dimensional Data—A Hybrid Approach and Comparison Study, Computers 2021, 10(3), 34; doi:10.3390/computers10030034

NDT MEASURING TECHNIQUES

- Suppose you have a composite material consisting of multiple layers, e.g., a sandwich structure of alternating metal and fibre layers.
- Now suppose there is a hidden defect or a damage that we cannot see or feel from the outside.
- How can we detect and localize these hidden defects and damages with in-field measuring techniques quickly and robustly?



AIR-COUPLED GUW CAMERA



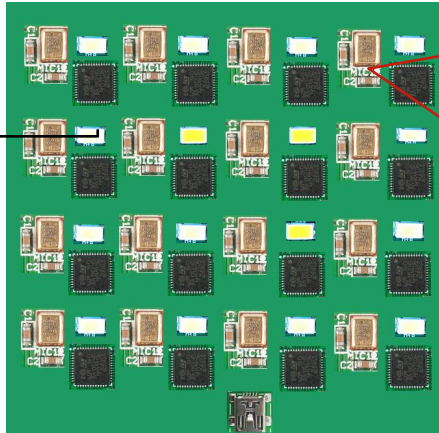
Goal: Single Board Distributed Sensor Network with multiple sensors, message- and signal-based communicating sensor nodes, and integrated spatially resolved damage and defect prediction with TinyML models and a Virtual Machine.

- This study introduces a low-cost air-coupled measuring technique using a 1\$ MEMS microphone as a signal receiver and a surface-coupled transducer as a sender. Each sensor is integrated with data processing and communication (ICT), providing a "Smart Sensor Node" for signal processing, feature extraction, and Machine Learning for feature prediction. The approach provides higher freedom of design and scalability, especially for spatially large extended sensor networks.



Distributed multi-sensor acquisition of time-dependent signals require message- and signal-based synchronization; clock synchronization depends on low latency and jitter!

FULLY INTEGRATED SENSOR NODE: ARCHITECTURE



Visualization

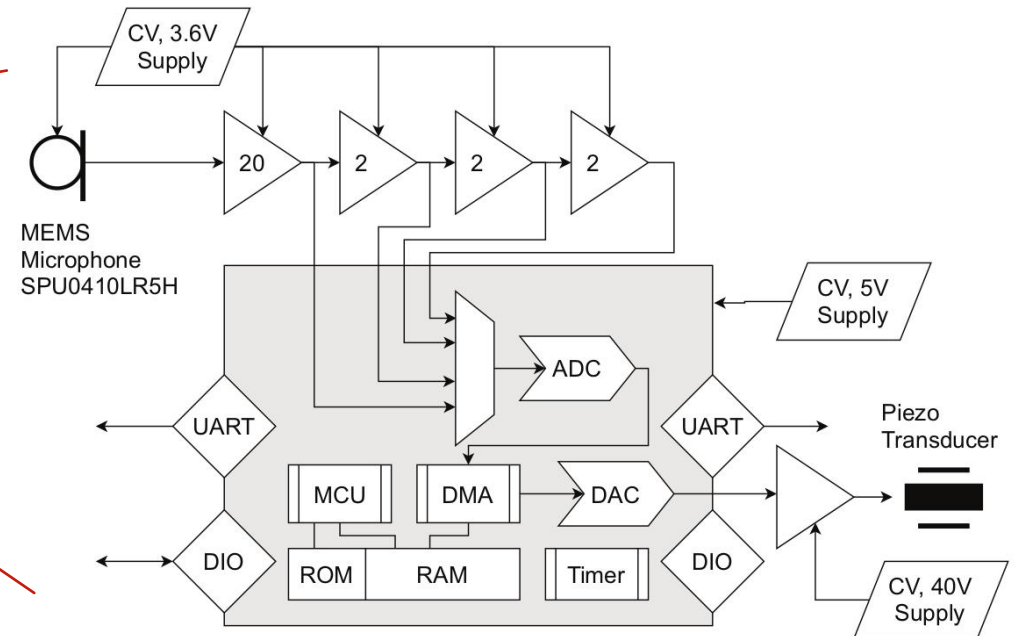
- LEDs indicate localized state prediction

Sensor Network

- Chain or Mesh-grid
- Communication
- Network
- MEMS Microphone

Sensor Node

- Fully Integrated w. ICT
- Analog-Digital Interface
- Sensors
- Tiny ML



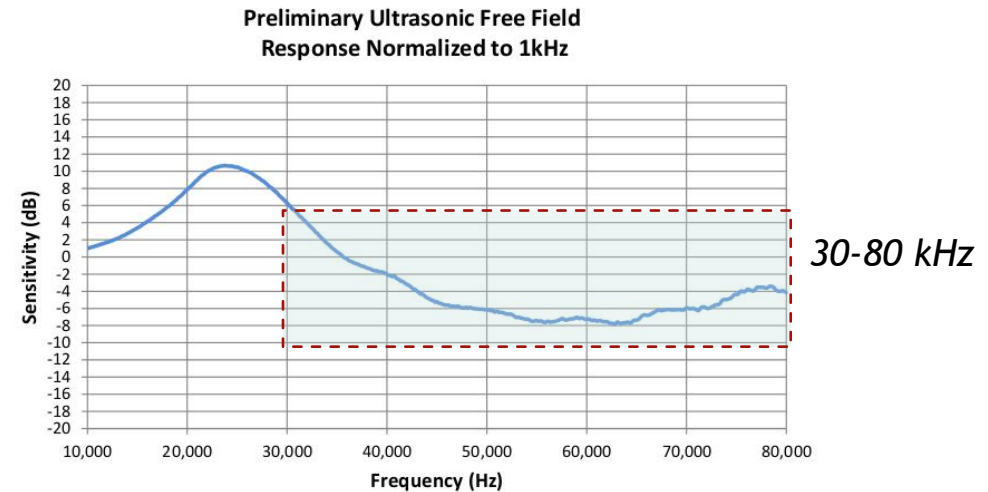
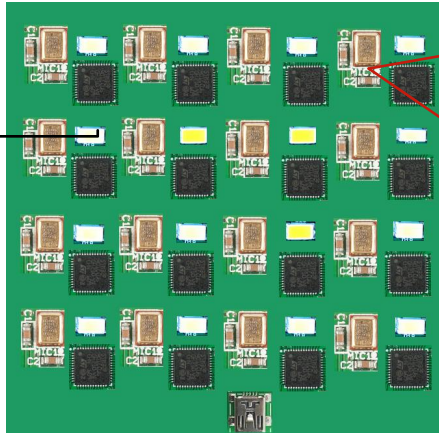
Analog

- Pre-Amplifier Cascade
- Bandwidth ~ 200 kHz
- ADC (12 Bits, 2 MS/s)
- DAC (12 Bits, 10 MS/s)

Digital

- STM32F303 32Bit ARM Cortex M4 + FPU
- Communication
- Embedded Basic
- Virtual Machine

FULLY INTEGRATED SENSOR NODE: SENSOR



Visualization

- LEDs indicate localized state prediction

Sensor Network

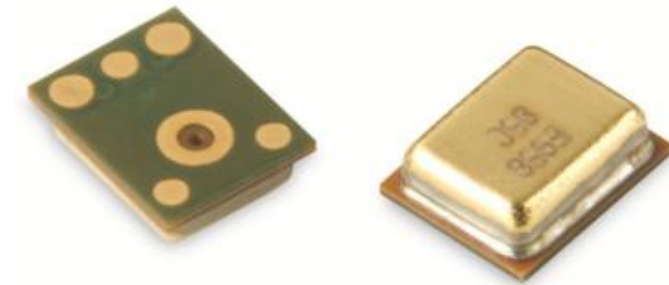
- Chain or Mesh-grid
- Communication
- Network
- MEMS Microphone

Sensor Node

- Fully Integrated w. ICT
- Analog-Digital Interface
- Sensors
- Tiny ML

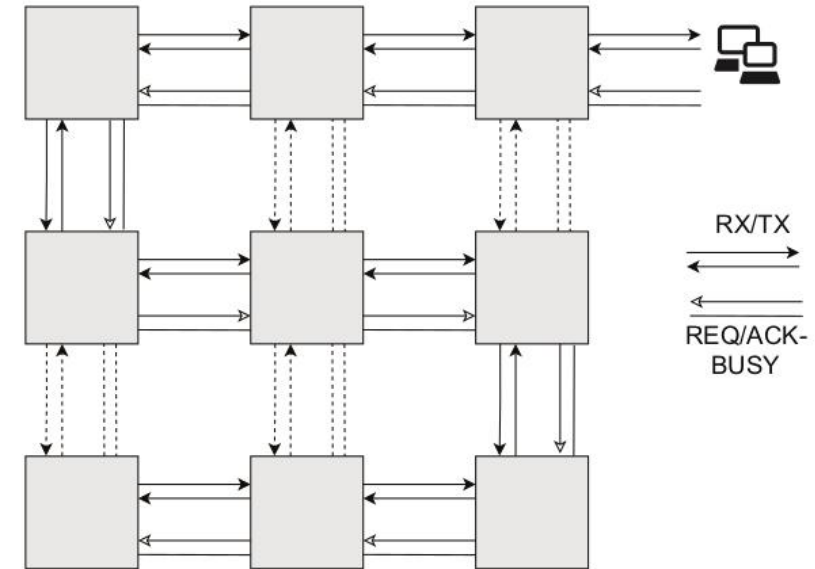
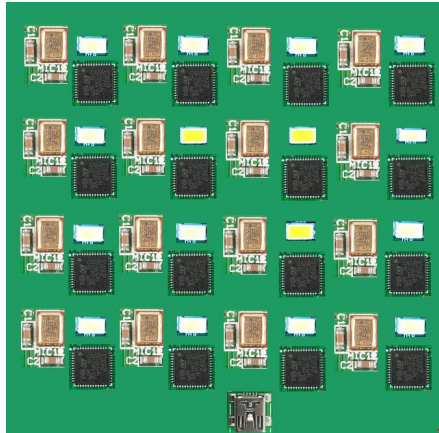
Sensor

- MEMS Zero-Height SiSonic Microphone SPU0410LR5H
- Size: 3x3.8x1mm
- Flat Frequency Response
- Omnidirectional
- Sensitivity: -38 dBV/Pa



(Foto Seltech)

FULLY INTEGRATED SENSOR NODE: NETWORK



Sensor Network

- Chain or Mesh-grid
- Communication
- Network
- One node connected to external Computer

Sensor Node

- Fully Integrated
- Analog-Digital Interface
- Message-based Communication
- Signals

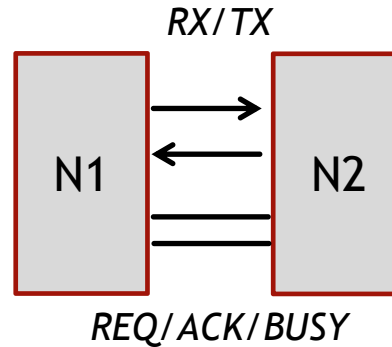
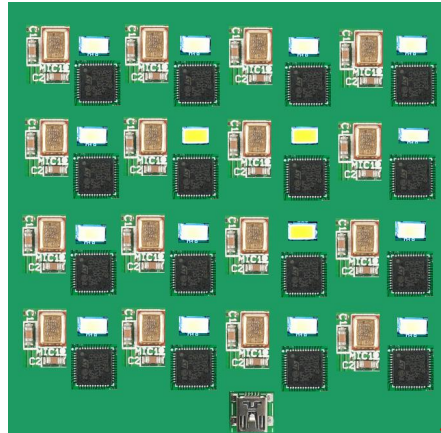
Links

- 2/3/4 bi-directional
- serial (UART/i2C) links
- up to 1 Mb/s

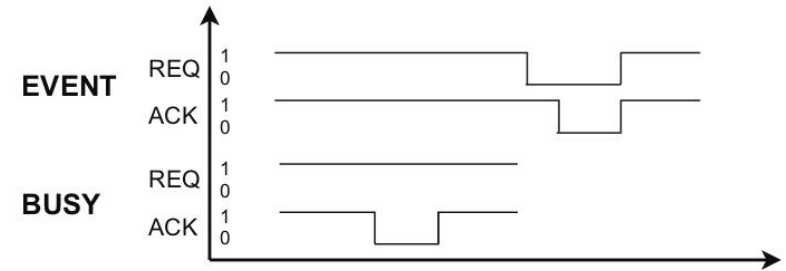
Signals

- Bus (OC)
- REQ: Fast hardware signal propagation
- ACK/BUSY: Message transfer control

FULLY INTEGRATED SENSOR NODE: COMMUNICATION



Program code	[code:code:code]⌊
Code Incremental	[[code:code:code]]⌊
Single statement	]code:code[⌊
Route-through data	!data,data,data!⌊
P2P message	\$data,data,data\$⌊
Routing message	\$id,hops,time@⌊
Console message	text⌊



Sensor Network

- Chain or Mesh-grid
- Communication
- Network
- One node connected to external Computer

Sensor Node

- Fully Integrated
- Analog-Digital Interface
- Message-based Communication
- Signals

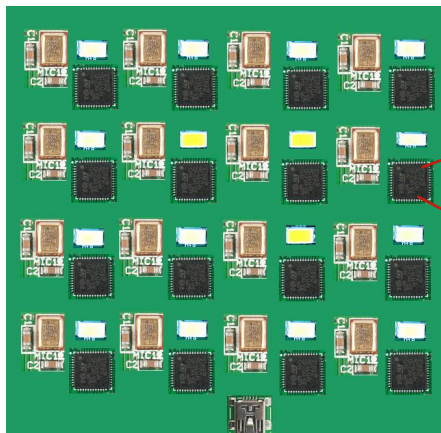
Software Protocol

- Code propagation (network is a SIMD computer)
- Message propagation
 - Peer-to-Peer
 - Data

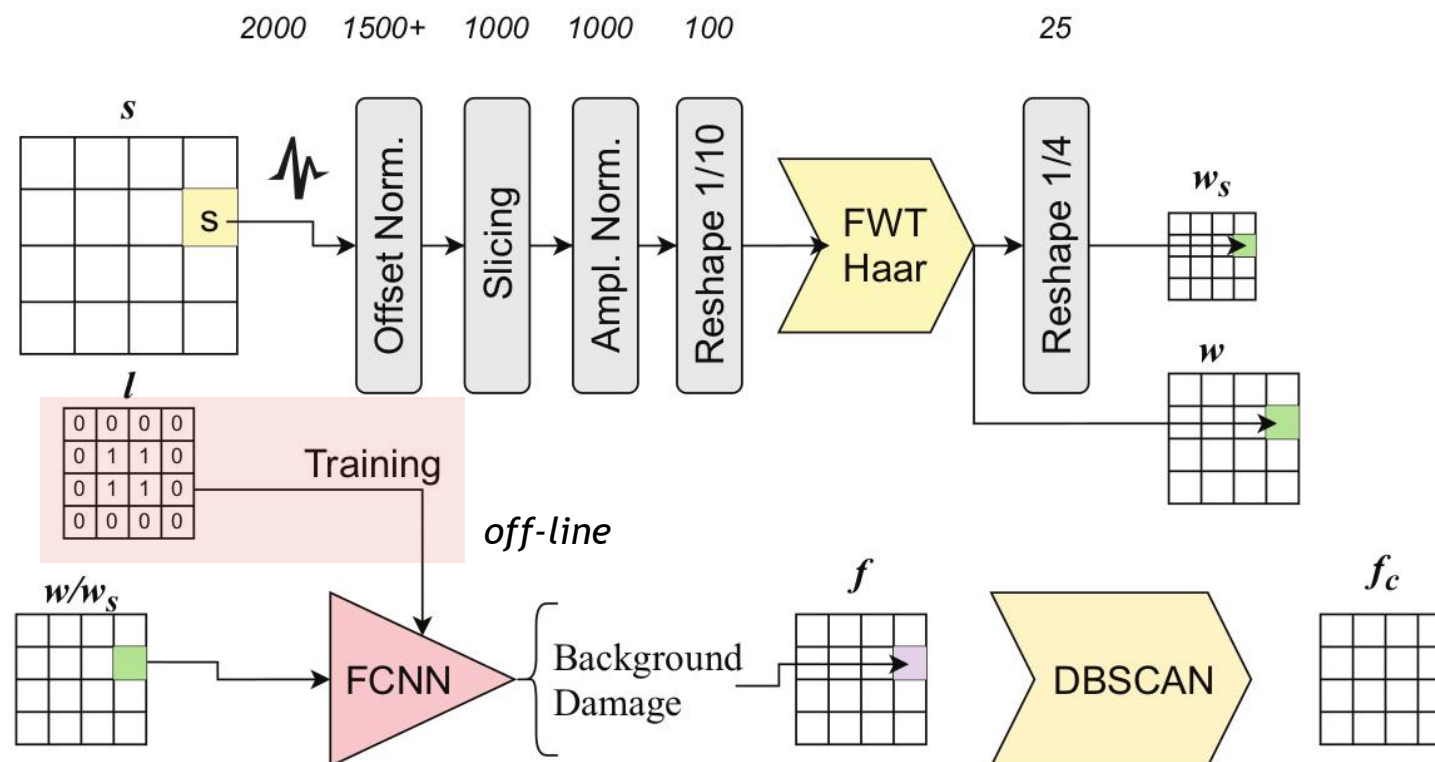
Hardware Protocol

- Fast hardware event signals propagated through network
- Start of signal acquisition
- Routing control
- Clock synchronization

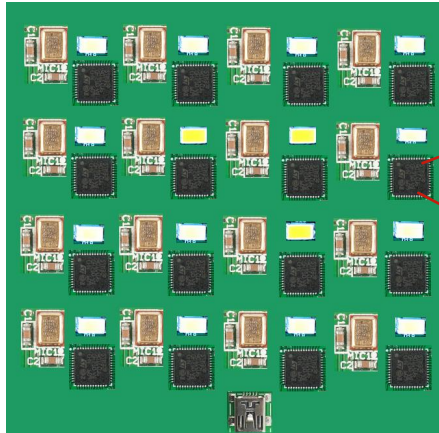
FULLY INTEGRATED SENSOR NODE: TINY ML



- Data-flow architecture implemented in each sensor node (except model training)
- Input: Time sensor signal
- Feature extraction: Fast Wavelet Transform with Haar wavelet
- Damage classifier: Fully Connected Neural Network Classifier
- Output: Damage near by? 0/1



FULLY INTEGRATED SENSOR NODE: TINY ML



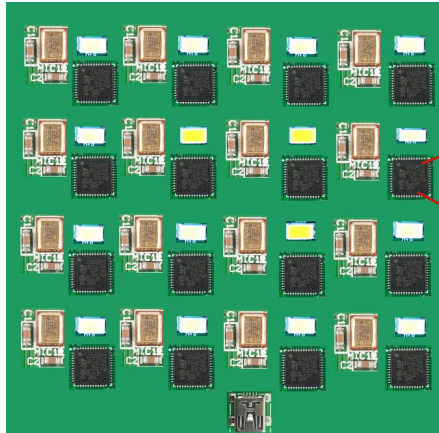
- Fully Connected Artificial Neural Network
- Input: FWT vector (Length N, Level 5)
- Output: Damage yes/no decision
- Three hidden layers + one softmax layer
- Trained with Float 32 Bits data type
- After training converted into Integer 16 Bits data type
- Int16 FCNN computed with Basic Vector Operation (STM32 microcontroller)

Fully Connected Neural Network

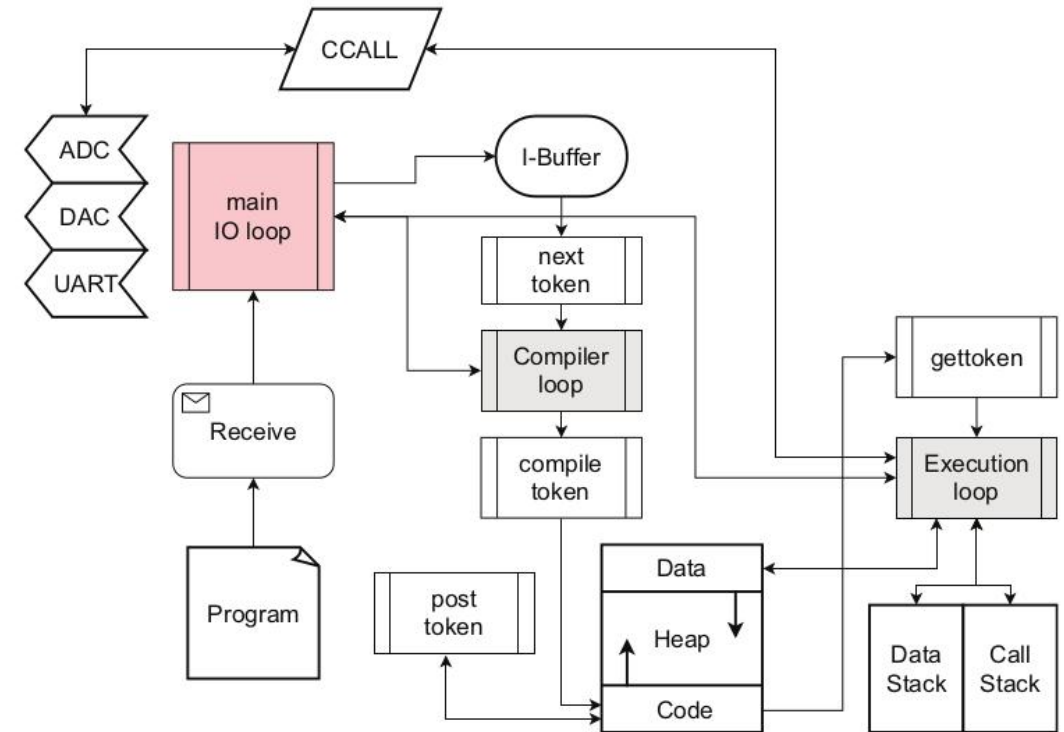
```

=====
Classes:    2 {B,D}
Input:      [N,1,1]
Output:     [2]
Layers:     [L5 P9]
[1] input :           out=[N,1,1]  params=0
[2] fc :             in=[25]  out=[10]  params=N*10+10
[3] tanh :           out=[10]  params=0
[4] fc :             in=[10]  out=[10]  params=110
[5] tanh :           out=[10]  params=0
[6] fc :             in=[10]  out=[10]  params=110
[7] tanh :           out=[10]  params=0
[8] fc :             in=[10]  out=[2]   params=22
[9] softmax : in=[2]   out=[2]   params=0
-----
Predictors: N                                     Parameters=N*10+252
    
```

FULLY INTEGRATED SENSOR NODE: VIRTUAL MACHINE



- Programming Language: High-level Basic!
- Input: Text (single statements and program code)
- Fast tokenstream compiler with optimization and code compaction (two-pass compiler)
- Single-step compiler and execution loop (live in harmony with main IO loop and host application)
- Event-driven preemptive processing
- Very low resource requirements: < 14 kB RAM

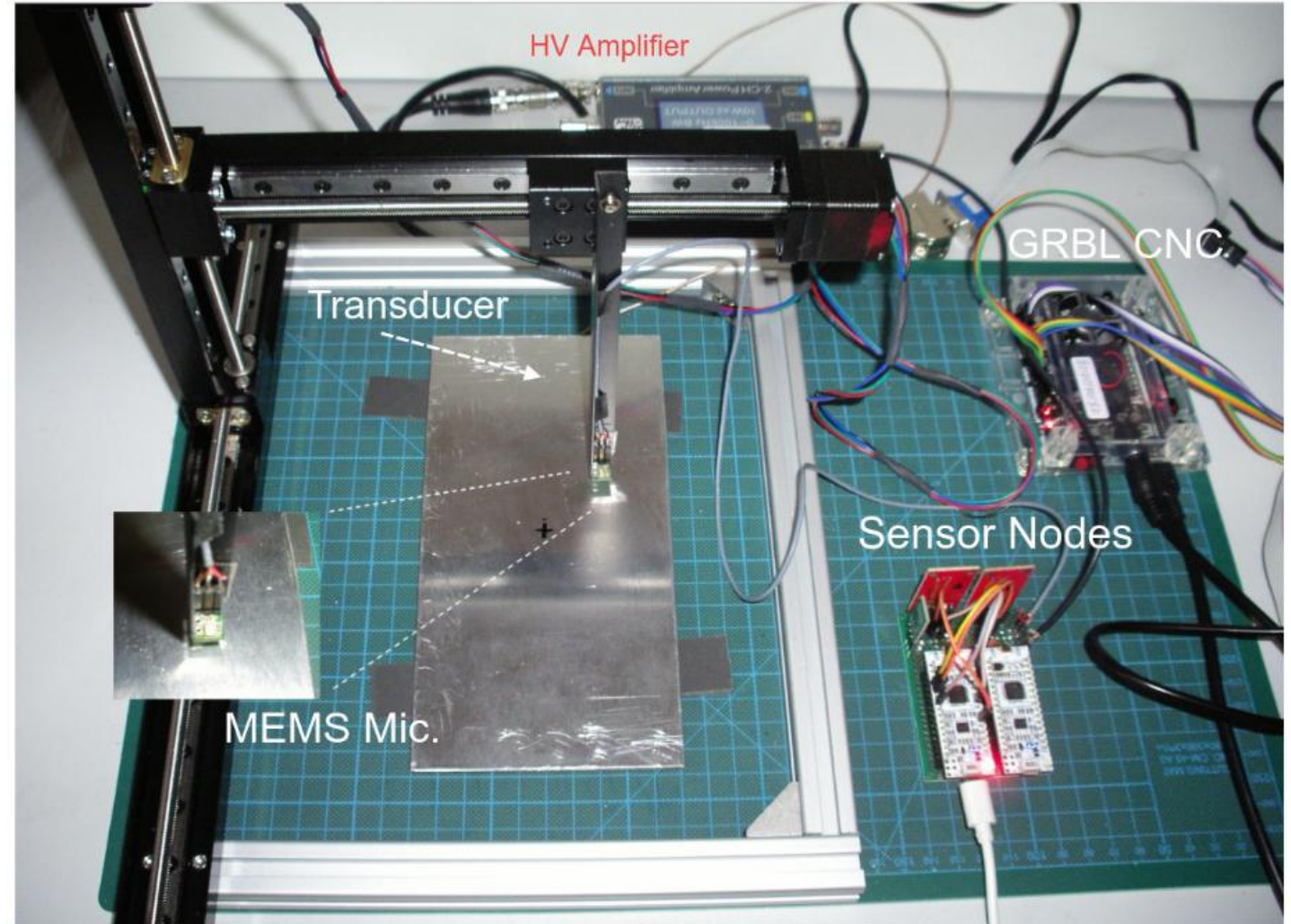


Programming Features

- Event handler
- Error handler
- Extended I/O
- Math
- Vector operations for Tiny ML
- 16 Bits data width (Int 16)
- can be easily extended
- C Call API

AIR-COUPLED SCAN TECHNIQUE

- Proof-of-concept: Experimental data acquisition to evaluate the damage prediction model (ML)
- The experimental prototype: The 3-dim. portal arm device with a mounted MEMS microphone and the test plate.
- On the lower right side there is an experimental demonstrator consisting of two sensor nodes and the amplifier cascade circuit.
- On the upper right side there is the GRBL CNC controller driving the portal arm machine
- The transducer is mounted on the down side of the plate and driven by a high-voltage amplifier ($V_{\max} = 40 \text{ V}_{\text{pp}}$, $f_{-3\text{dB}} = 100 \text{ kHz}$, $G = 20 \text{ dB}$)



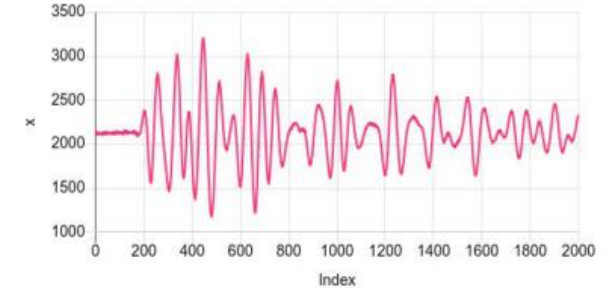
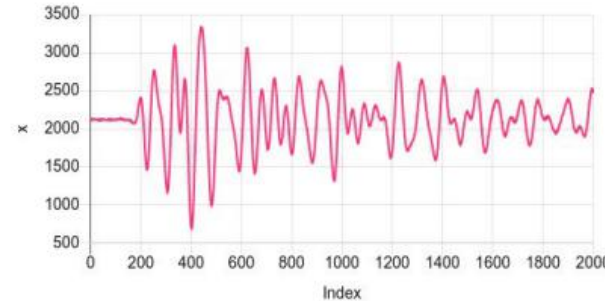
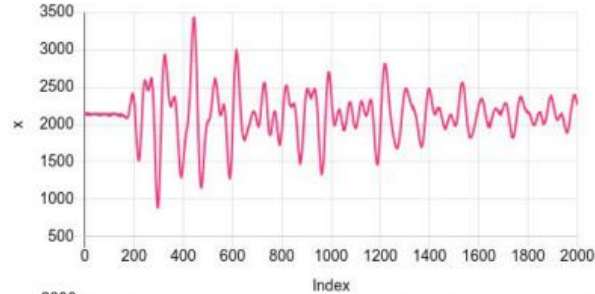
AIR-COUPLED SCAN TECHNIQUE

$z=4$ mm

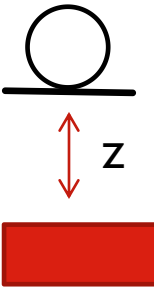
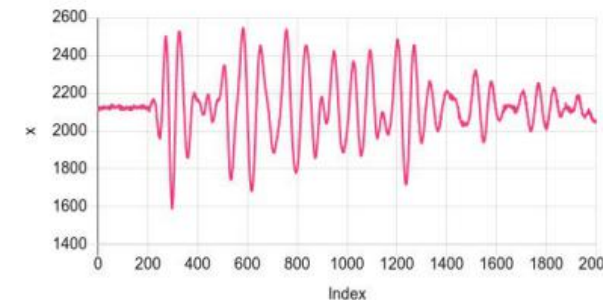
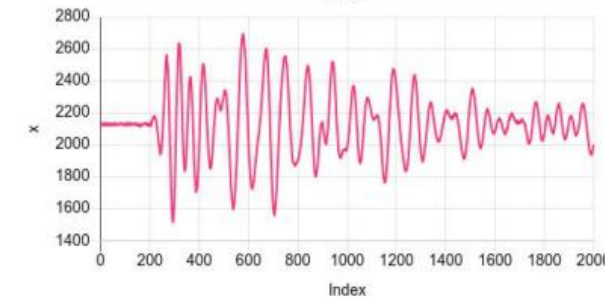
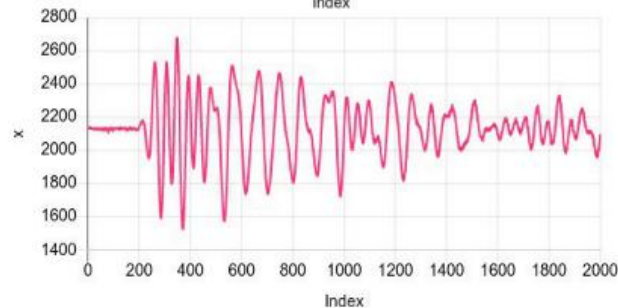
$z=5$ mm

$z=6$ mm

X=30 mm
Y=30 mm
Damage



X=2 mm
Y=2 mm
No Damage

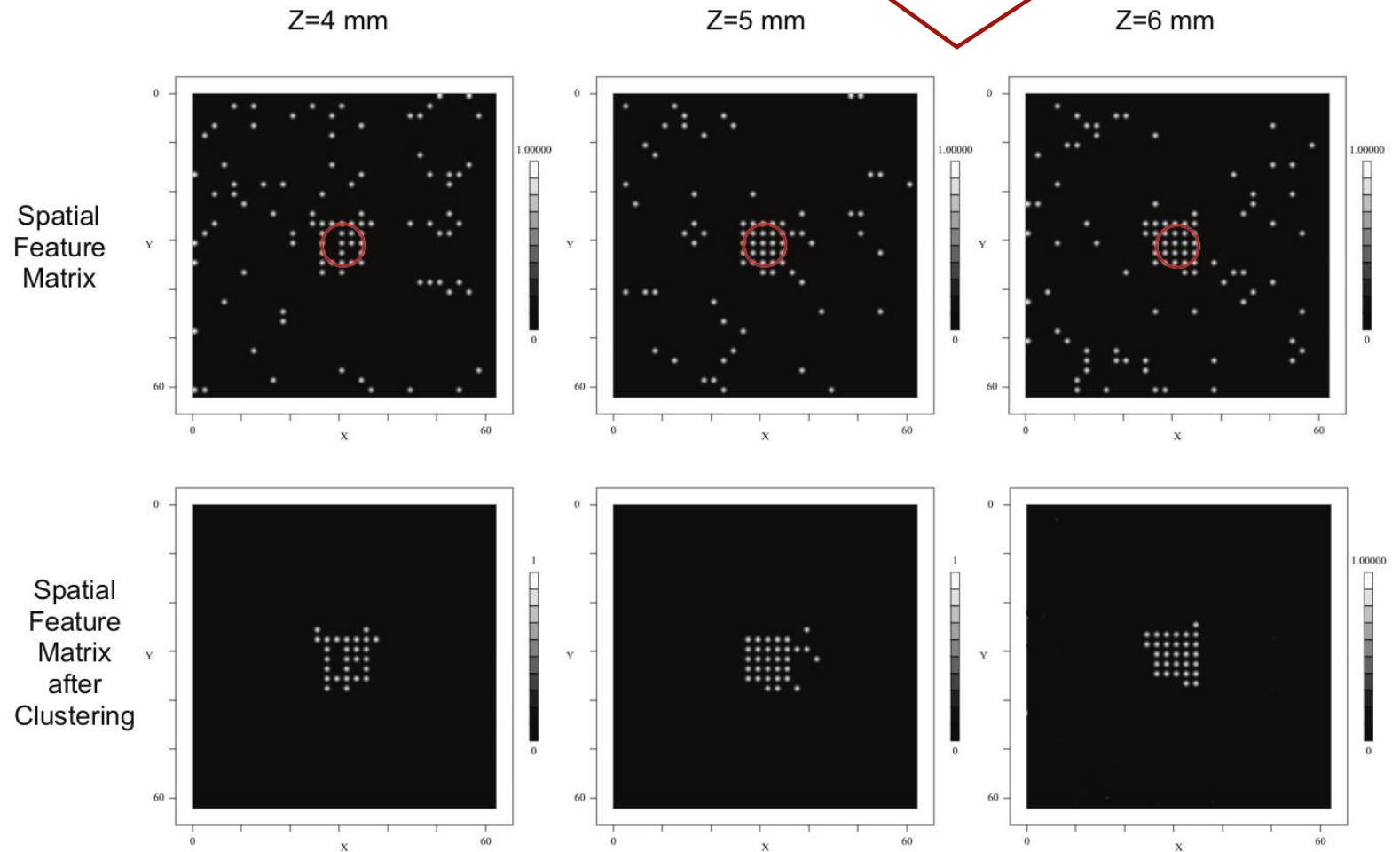


Sensor signals are significantly dependent on the distance from the material surface to the microphone (microphone height z)!

EXPERIMENTAL RESULTS

- Input data: GUW sensor signal matrix from **air-scan** with 31 x 31 (x,y) positions (2 mm distance) and different microphone heights (z)
- Input feature vector: FWT (25/100)
- Predictor model FCNN (Float32) was **trained** with labeled sensor data (all heights z)
- Predictor model FCNN and feature extraction were applied to 31 x 31 signals for different microphone heights (z), resulting in **feature images** (top)
- **Density-based clustering** was applied to the feature image (bottom) removing noise (false-positive predictions): **Model Fusion**

• But wait, there is a lot of noise!



FWT: L5-N100 FCNNF32 L3[10-10-10]:tanh

EXPERIMENTAL RESULTS

	Error	F1 Score	False Positive	False Negative	Localization
FWT=100 DT=Float32	8.3%	0.89	10%	0%	±5 mm
FWT=25 DT=Float32	6.8%	0.90	10%	4%	±6 mm
FWT=100 DT=Int16	8.3%	0.90	12%	2%	±6 mm
FWT=25 DT=Int16	6.6%	0.89	10%	2.6%	±6 mm
	Average			Variance	
Hardware Signal Propagation (Node-to-Node)	3μs			<100 ns	
VM Execution Time (1 Token==VMachine Instr.)	2μs			<1μs	
FCNN Computation (STM32)	<100 ms			-	
Signal Recording	12 Bits, 2MS/s, 2000 points (1ms)			-	

Ressources:
 STM32 F303
 64 MHz Clock
 50/64 kB ROM
 14/14 kB RAM

Only proof-of-concept study!

CONCLUSIONS

Air-coupled MEMS Microphone and GUW

- Contactless GUW monitoring
 - Small size
 - Easy integration, high miniaturization
- **Ultrasonic frequency response 30-80 kHz**
- **High sensor density**
- 1-Sensor 2D-scan or Distributed N sensor network
- **Signal is z-dependent** and damage/defect information is time- and location dependent

Distributed Sensornetwork

- Fully Integrated Sensor Node with low-resource microcontroller (STM32): Less than 64kB ROM and 20 kB RAM
- Chain- or mesh-grid network
- **Synchronization** is performed via hardware signals and messages
- A **Virtual Machine** provides a Basic scripting engine, event-driven preemptive processing, signal processing (e.g. FWT) and TinyML (vector operations)
- VM supports single-step (single-token) compilation and execution

Distributed ML

- Each sensor node records a GUW signal, performs a Wavelet transformation, and predicts the local state using a simple FCNN model trained off-line
- False-positive rate is increased - therefore no robust local damage or defect prediction is possible
- But clustering and global model fusion (or within a given range) improves damage prediction and localization significantly
- Instead global density-based clustering a local neighboring approach can be used

THANK YOU

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