Design and Development of an FPGA Based Intelligent Stereo Vision System

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Agenda

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Motivation

Basics

System Design

Stereo Vision System

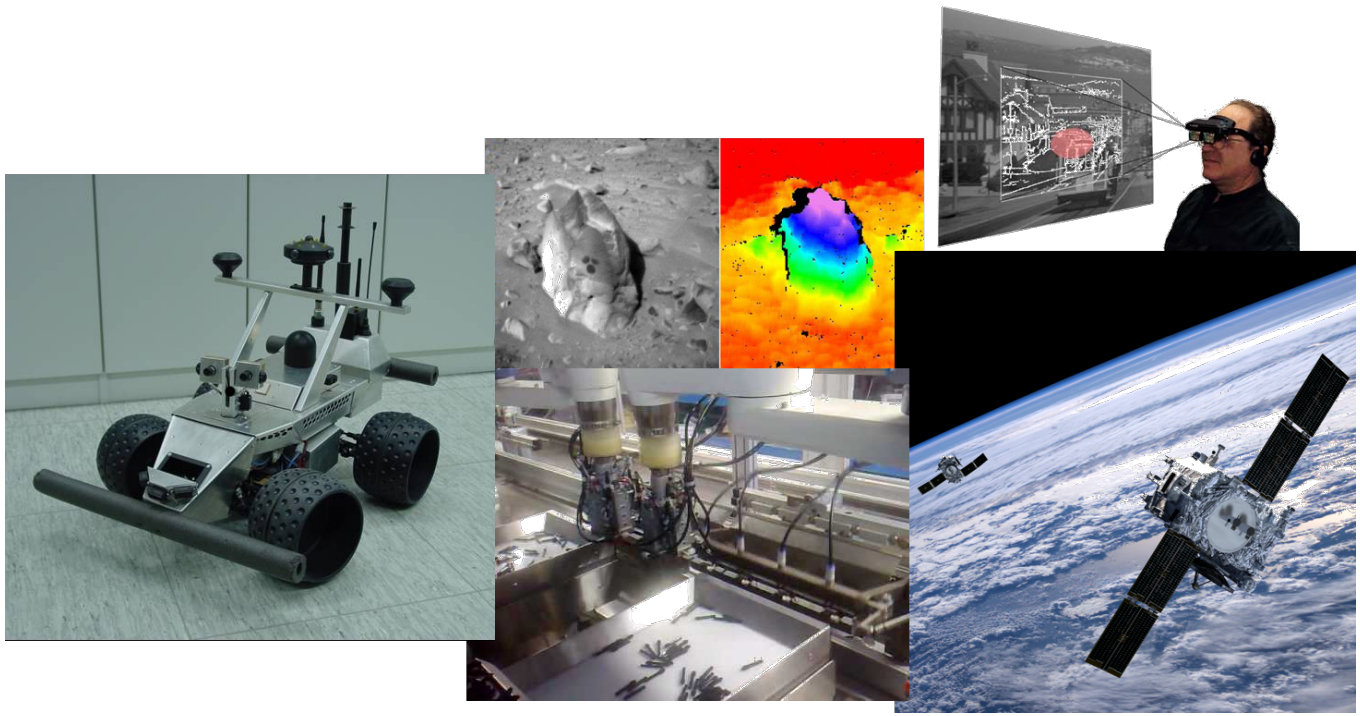
Results

Summary and Outlook

Motivation: Stereo Vision

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- **Definition:** Stereo vision is the extraction of 3D information from images obtained by two cameras.
- Stereo vision is important in different fields:
  - e. g. aid for visually impaired, automated systems, robotics, space exploration



Motivation: FPGA

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How does a stereo vision algorithm can be computed?

	Processor	FPGA
Single computation performance	●●	○●
Parallel computation performance	○●	●●
Costs	●●	●●
Usage simplicity	●●	○●

Decision

- Stereo vision algorithms are mostly parallalizable
- $\Rightarrow$ FPGAs are well suitable

Motivation:Tasks

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Tasks

- Development of an prototyping stereo vision system
  - Generic and modular design
  - Cost-efficient system
  - Hardware choosing and construction

Agenda

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Motivation

Basics
- FPGA
- Impulse C

System Design

Stereo Vision System

Results

Summary and Outlook

Basics: FPGA

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What is an FPGA?

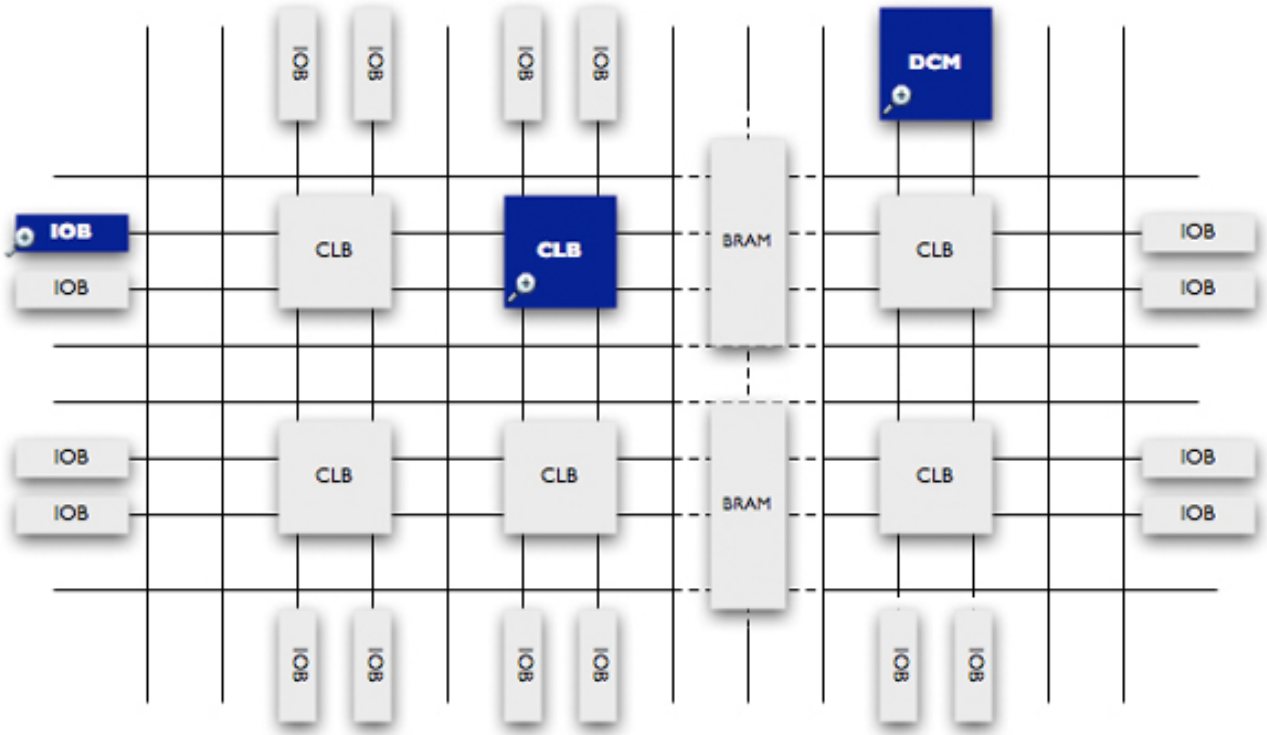
- **F**ield-**P**rogrammable **G**ate **A**rray
- Integrated Circuit
- Configurable behaviour
  - typically defined by Hardware Description Languages (HDL)



Basics: FPGA

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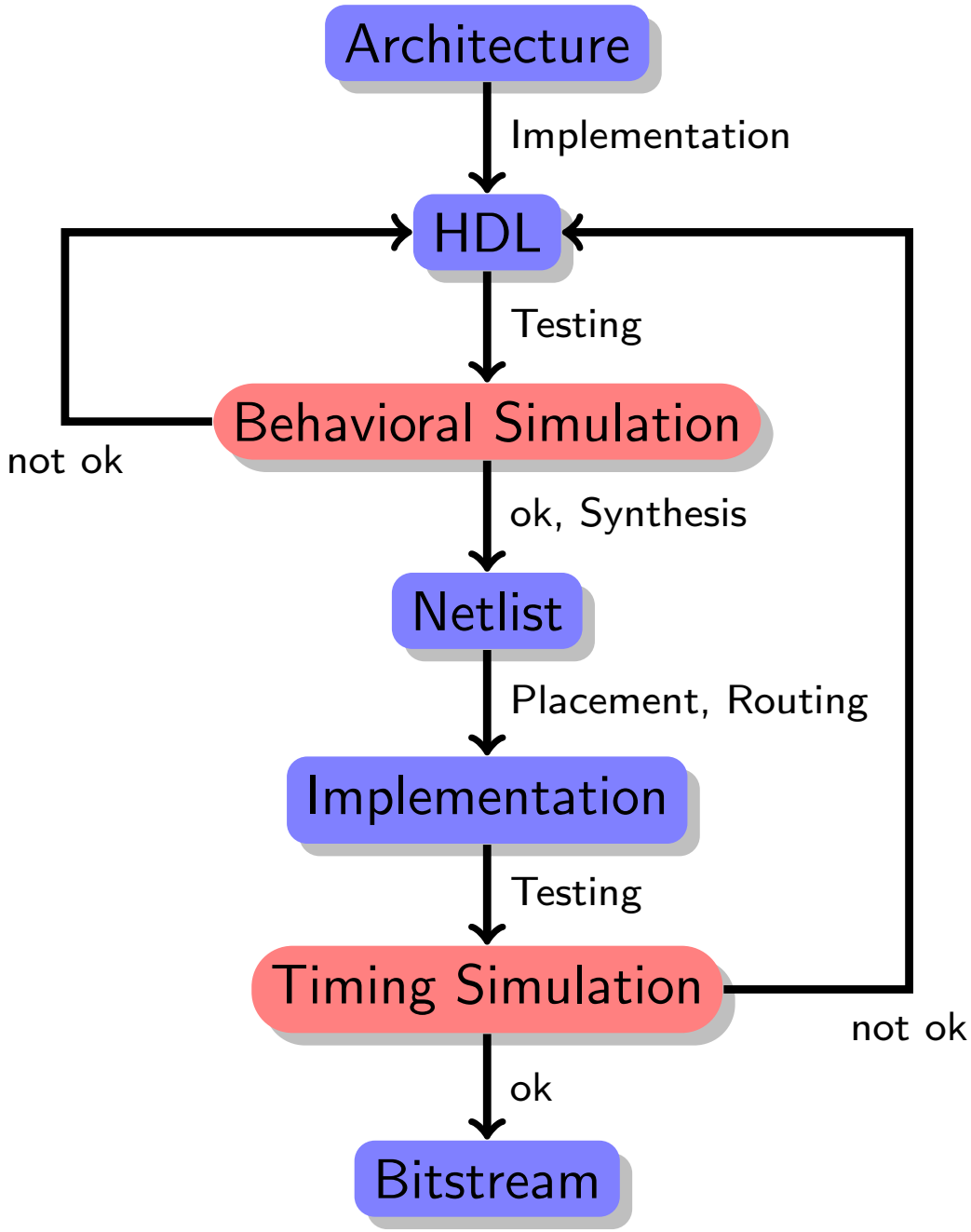
- FPGA - Internal Structure



IOB Input/Output Block, **CLB** Configurable Logic Block, **BRAM** Block RAM, **DCM** Digital Clock Manager

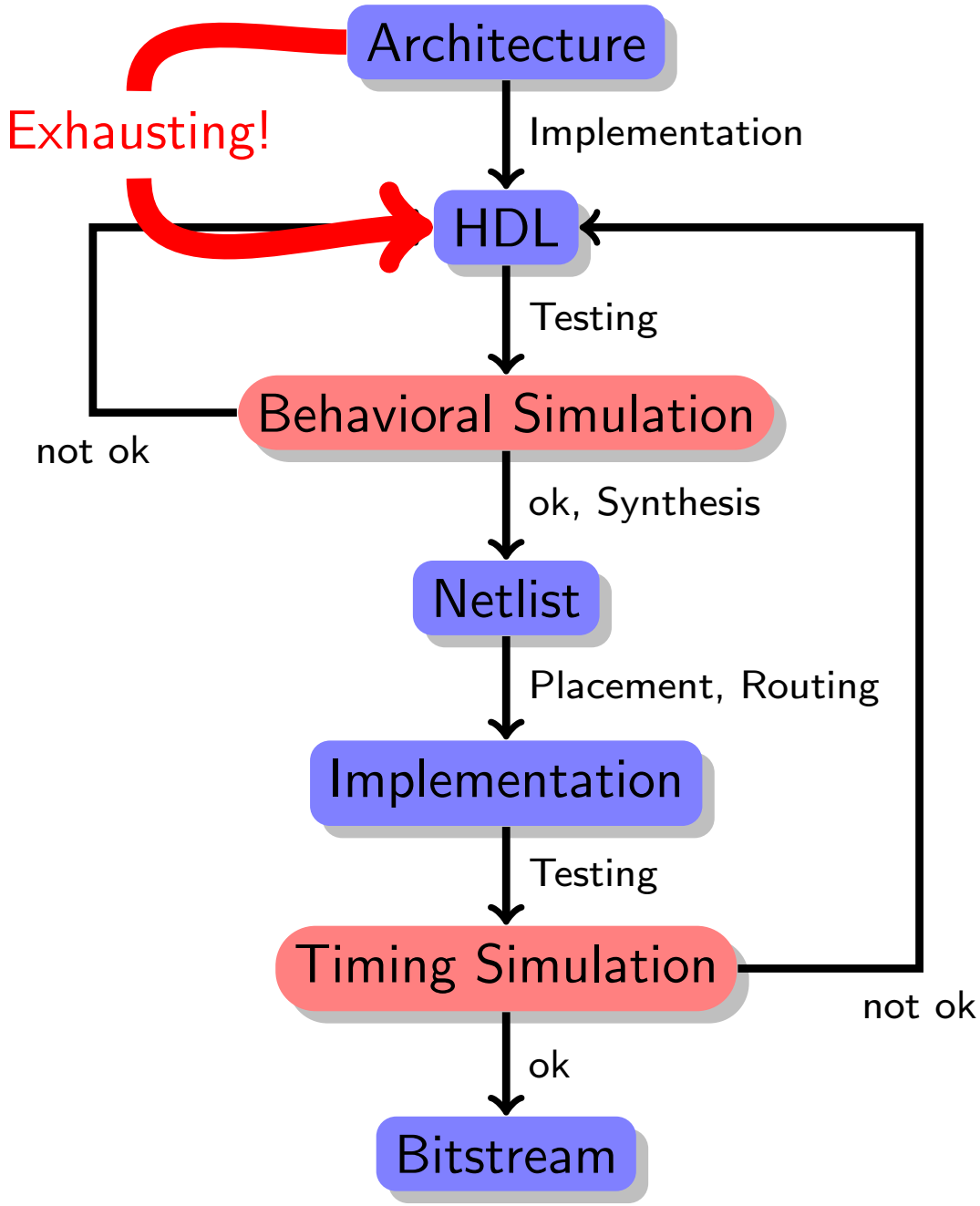
- **FPGA:** *Circuit with a configurable structure and behaviour*

Basics: FPGA Workflow



Basics: FPGA Workflow

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Basics: Impulse C C-to-VHDL Compiler

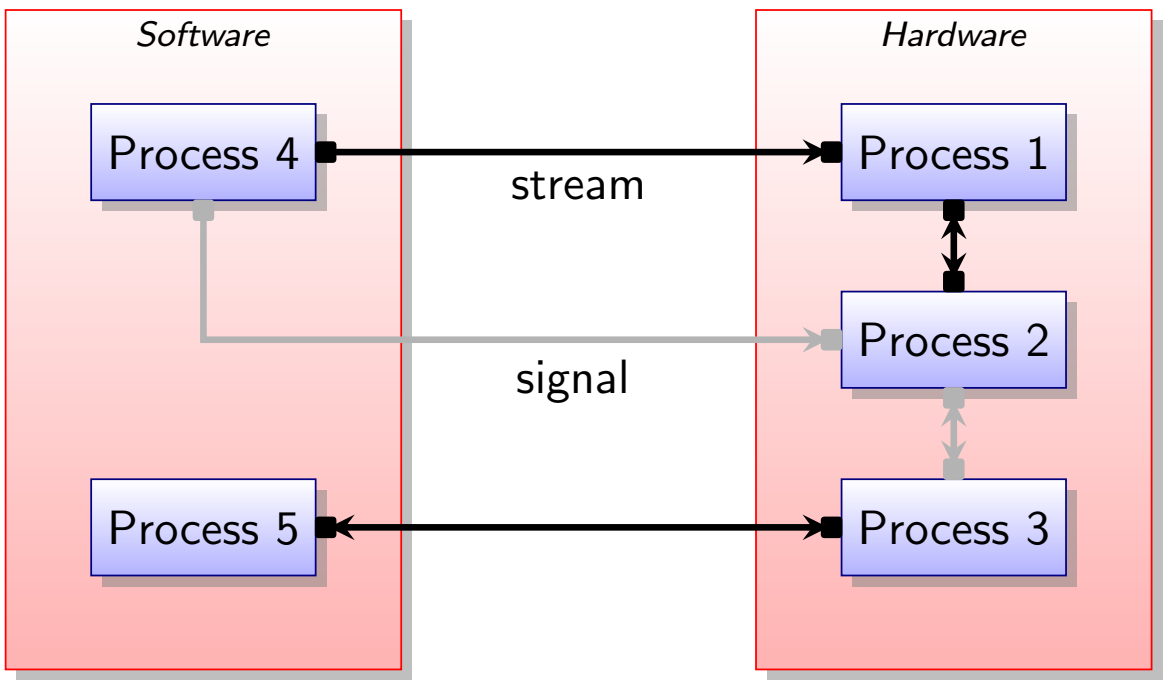
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- Impulse C is subset of C programming language
- Allows to write C programs for usage on FPGA
- C is translated into VHDL
- **Advantages:**
  - No need to learn HDL
  - Rapid prototyping possible
  - Simulation on host PC possible
  - Allows hardware/software codesign
- **Disadvantages:**
  - Generated VHDL not as efficient as hand-optimized VHDL
  - Debugging hard in complex applications

Basics: Impulse C programming model

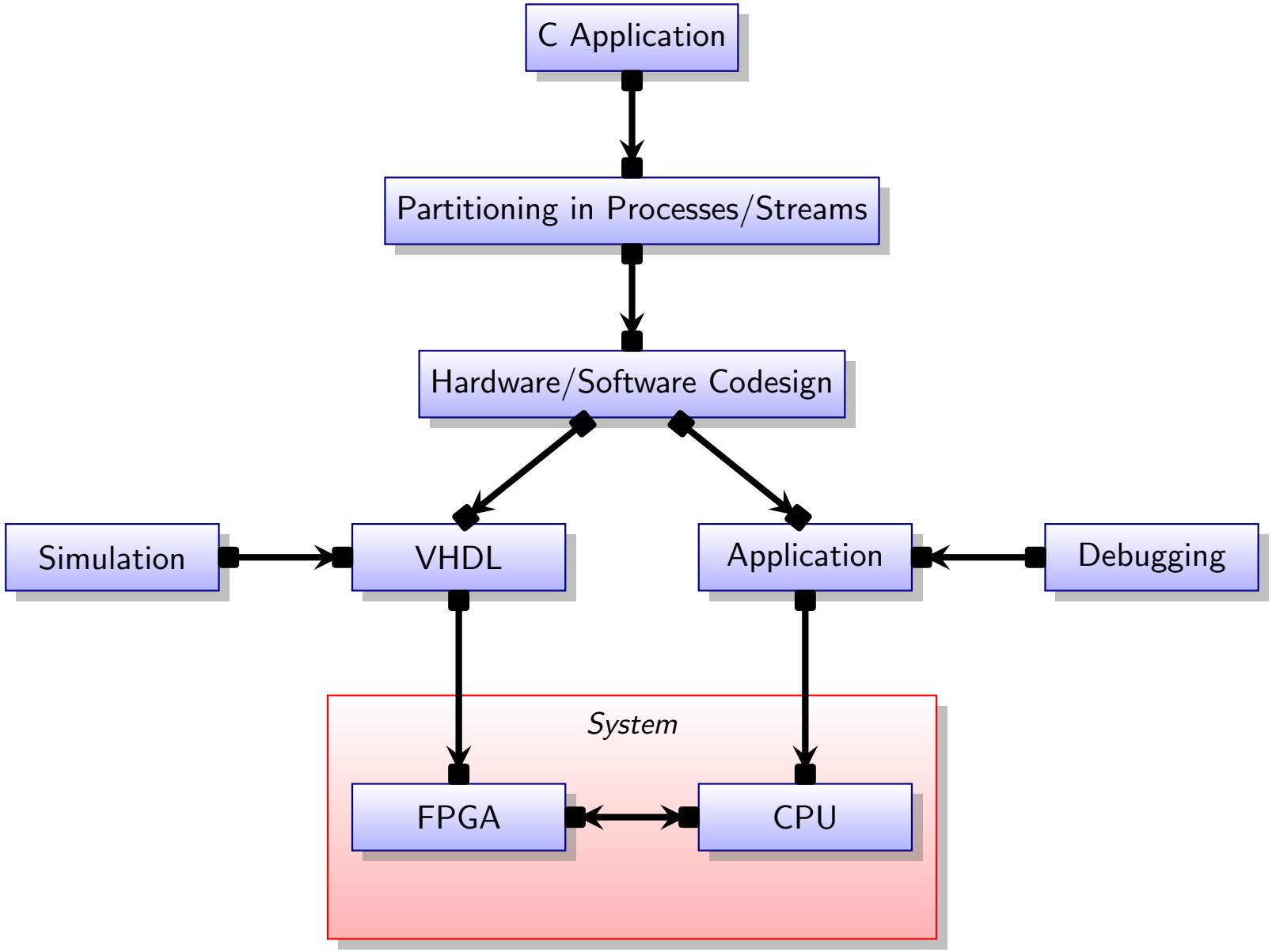
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- C program is divided in different *processes*
  - All processes run concurrently
- Processes are interconnected with *communication objects*
  - e. g. streams, signals, semaphores
- Processes can run on processor as well as FPGA
- Different optimizations possible
  - e. g. pipelining, loop unrolling



Basics: Impulse C Workflow

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Basics: Scan-Line based Segmentation

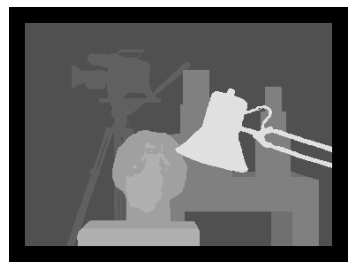
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Idea

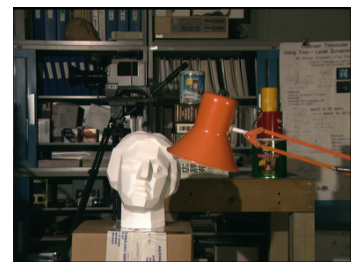
- Stereo vision algorithm, computes disparity map



left image



disparity map

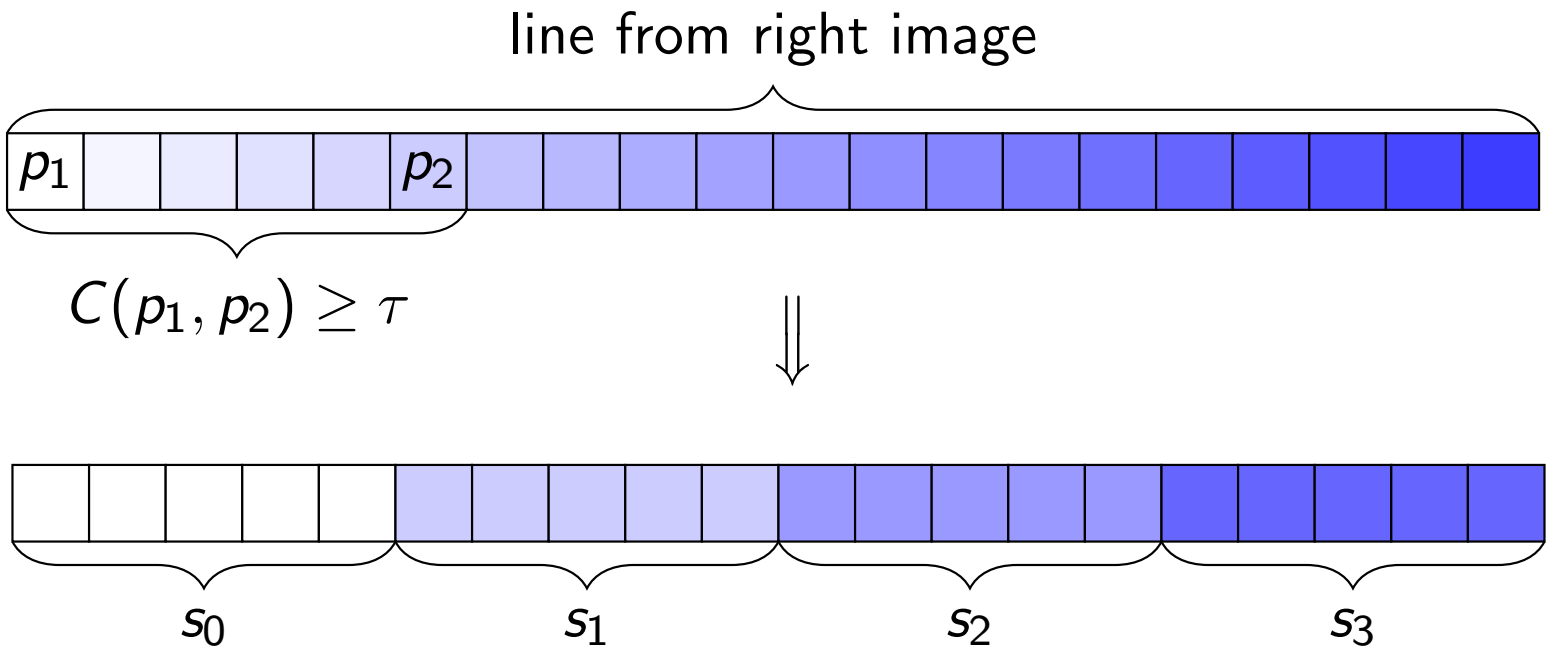


right image

- Local, line by line approach (no $n \times n$ filter window)
- Two phases:
  - Segmentation phase
  - Correspondence phase

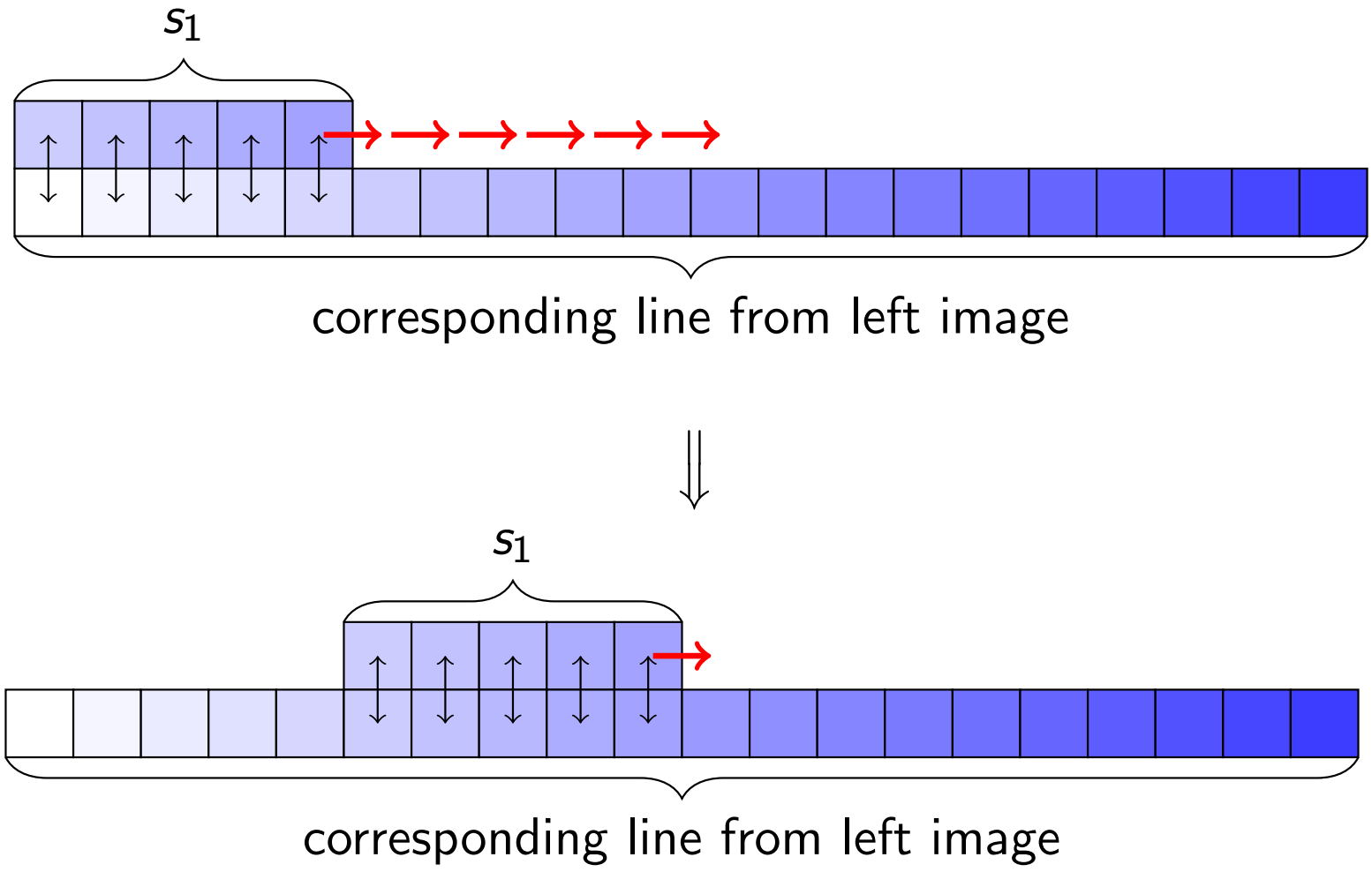
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Phase I: Line segmentation



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Phase II: Correspondence

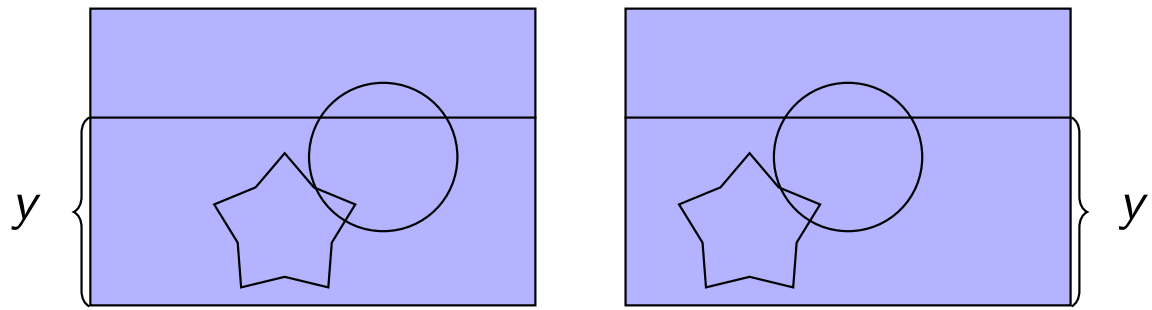


Basics: Scan-Line based Segmentation

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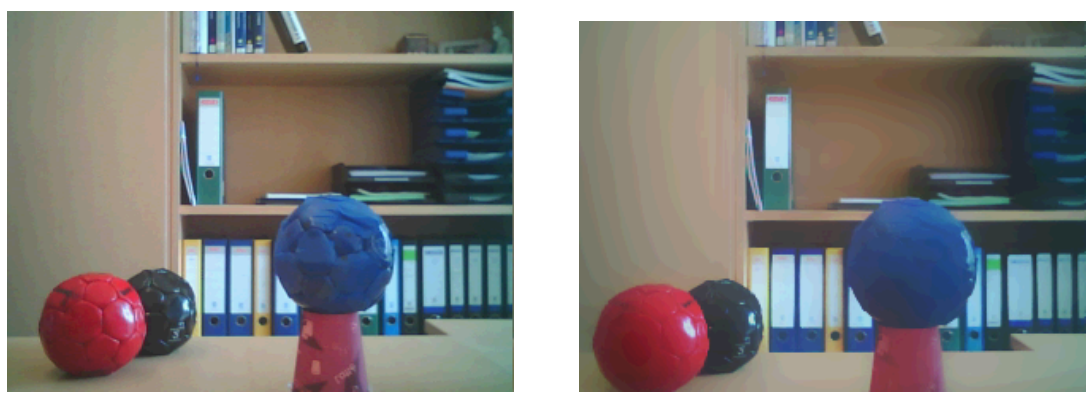
Requirements

- Rectified input images



left image right image

- Scene smooth except at borders of objects



detailed image smooth image

Agenda

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Motivation

Basics

System Design
- Requirements
- Designs
- Design Decision
- HDL/Impulse C Partitioning

Stereo Vision System

Results

Summary and Outlook

System Design: Requirements

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Requirements

- Image input, processing and output
  - Image Input: Simultaneously captured images
  - Algorithms: Full image pixel access in arbitrarily order
  - High Speed output interface
- Easy usage for C developers
- As much as possible implemented in Impulse C
  - Vision Algorithms
- Cost efficient system
- Long time availability of components
- Low power (robotic)

Tasks

- Choose hardware platform
- System partition in HDL and Impulse C

System Design: Design I

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FPGA system with PowerPC processor and USB cameras

- **Processor:** Hard core PowerPC
- **OS:** Typically a Linux system
- **Advantages:**
  - Easy implementation of framegrabbing, data transmission
- **Disadvantages:**
  - FPGA + PowerPC is deprecated
  - Sparse number of development boards
  - Generally quite expensive
- **Partition:**
  - Image Capturing: Linux System
  - In/Output: Linux System
  - Vision Algorithm: Impulse C

FPGA system with MicroBlaze processor and USB cameras

- **Processor:** Soft core MicroBlaze
- **OS:** Typically a Linux system
- **Advantages:**
  - Easy implementation of framegrabbing, data transmission
- **Disadvantages:**
  - Requires logic elements for processor
  - Applicable boards not yet available
- **Partition:**
  - Image Capturing: Linux System
  - In/Output: Linux System
  - Vision Algorithm: Impulse C

System Design: Design III

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FPGA system without processor and direct camera interface

- **Processor:** No processor
- **OS:** No operating system
- **Advantages:**
  - Everything on FPGA
  - High logic element efficiency compared to Design I+II
    - $\Rightarrow$ Smaller FPGA sufficient, cheaper
- **Disadvantages:**
  - Camera interfacing without driver support
  - Hard problem, potentially not done yet
  - In/Output in HDL
- **Partition:**
  - Image Capturing: HDL System
  - In/Output: HDL System
  - Vision Algorithm: Impulse C

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Summary

	I: FPGA + PPC	II: FPGA + MB	III: FPGA
Availability	○○	○●	●●
Price	○○	○●	●●
Implementation	●●	●●	○○

Decision

- $\Rightarrow$ **Design III**

System Design: HDL/Impulse C Partitioning

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Facts

- Memory necessary to allow arbitrarily image pixel access
- Fast output interface necessary
  - Gigabit Ethernet preferred
- **Impulse C**: No direct interfacing possible for
  - Cameras
  - Ethernet
  - Memory

Partition

- Image algorithms in Impulse C
- VHDL: Cameras, memory and Ethernet interface
- **Data Path:** Input(VHDL) $\rightarrow$ Impulse C $\rightarrow$ Output(VHDL)

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Motivation

Basics

System Design

Stereo Vision System
- System Hardware
- System Architecture
- Vision Framework
- Vision Core

Results

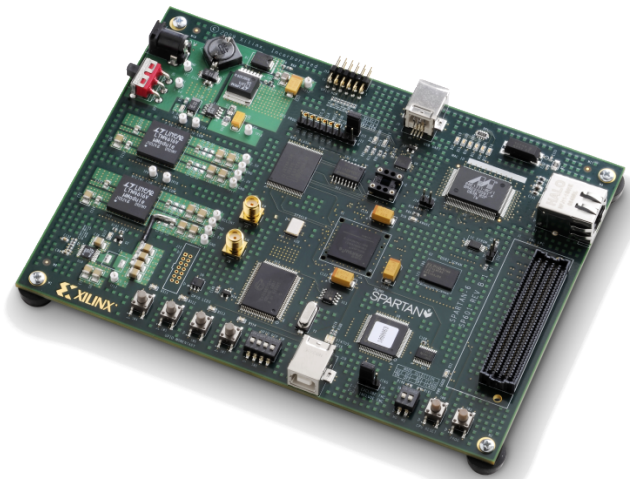
Summary and Outlook

Stereo Vision System: Hardware

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SP601 Development Board

- Xilinx Spartan-6 FPGA
  - Integrated Memory Controller Blocks
- 128 MB DDR2 memory
- Gigabit Ethernet transceiver
- Available, complies with requirements
- Costs $\approx$ 300 Euro



How can the development board be used?

- Cameras can't be directly connected
- $\Rightarrow$ Own hardware components are necessary

Stereo Vision System: Hardware

Considerations

- **Cameras:**
  - With direct interface
  - Replaceable camera lenses
- **Mounting:**
  - Maintain camera orientation
  - Adaptable camera distances
- **Additional Hardware:**
  - Used for data transmission between cameras and SP601
  - Preserve data integrity
  - Perform voltage translation

Stereo Vision System: Hardware

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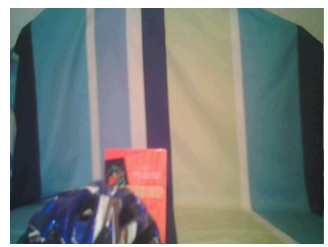
Cameras

- Direct interface to image sensor
- Configured by approx. 200 registers

OV7 Camera

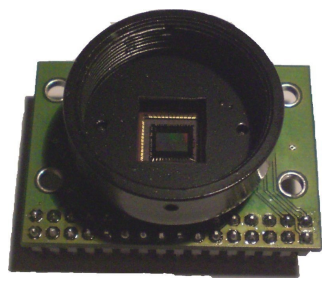
- Evaluation board of Omnivision
- OmniVision OV7720 sensor
- 640 $\times$ 480 pixel resolution, max. 60 fps





MT9V Camera

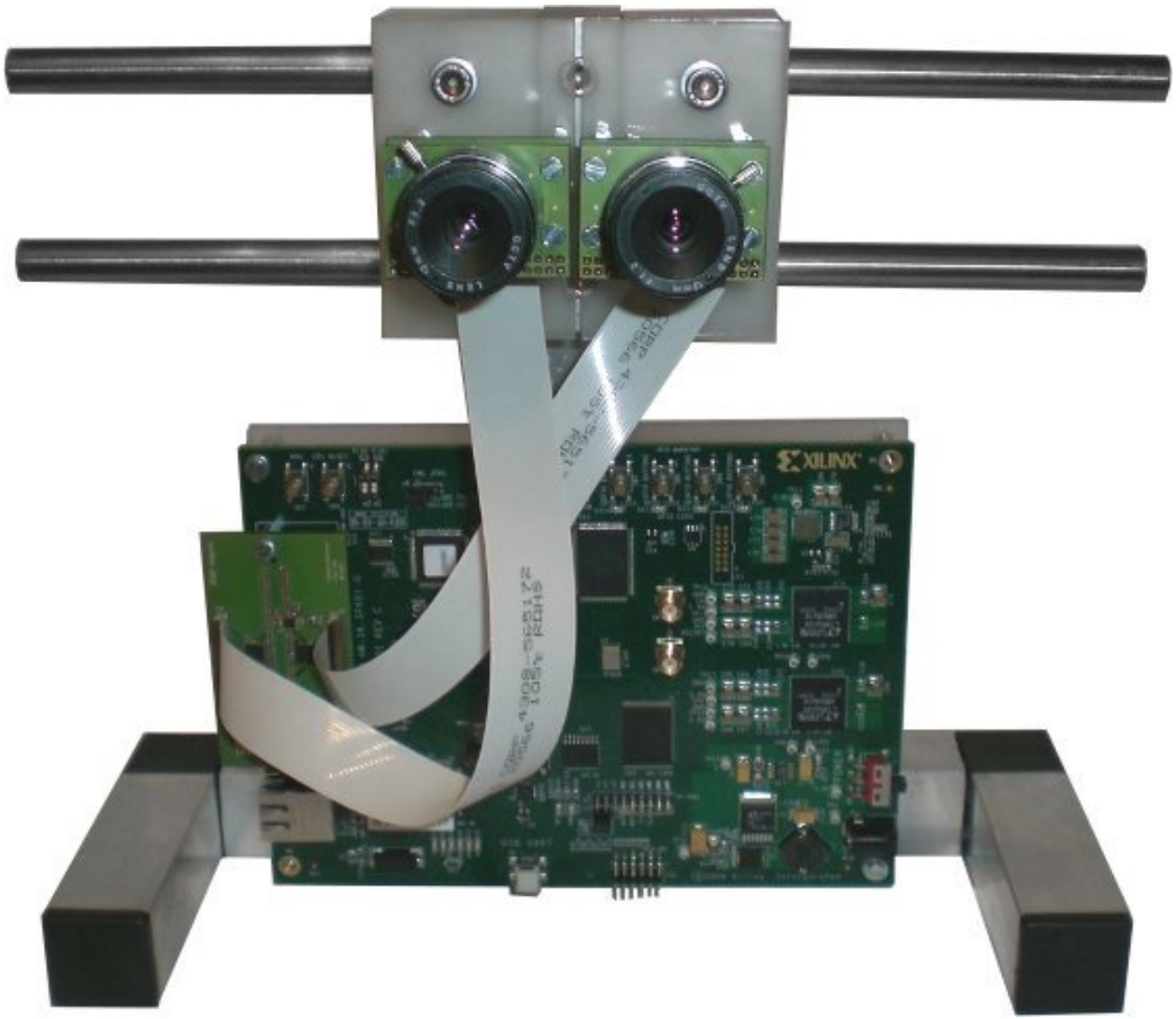
- Self designed and manufactured
- Aptina MT9V032 sensor
- 752 $\times$ 480 pixel resolution, max. 60 fps

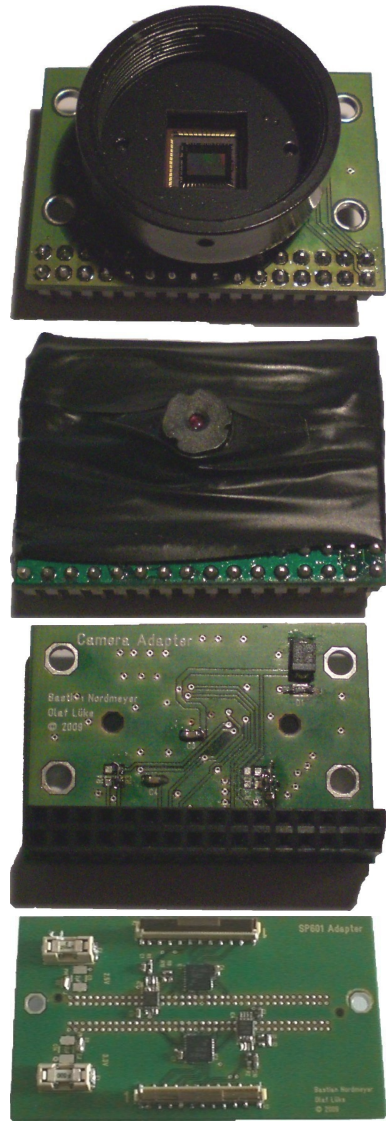




Stereo Vision System: Hardware

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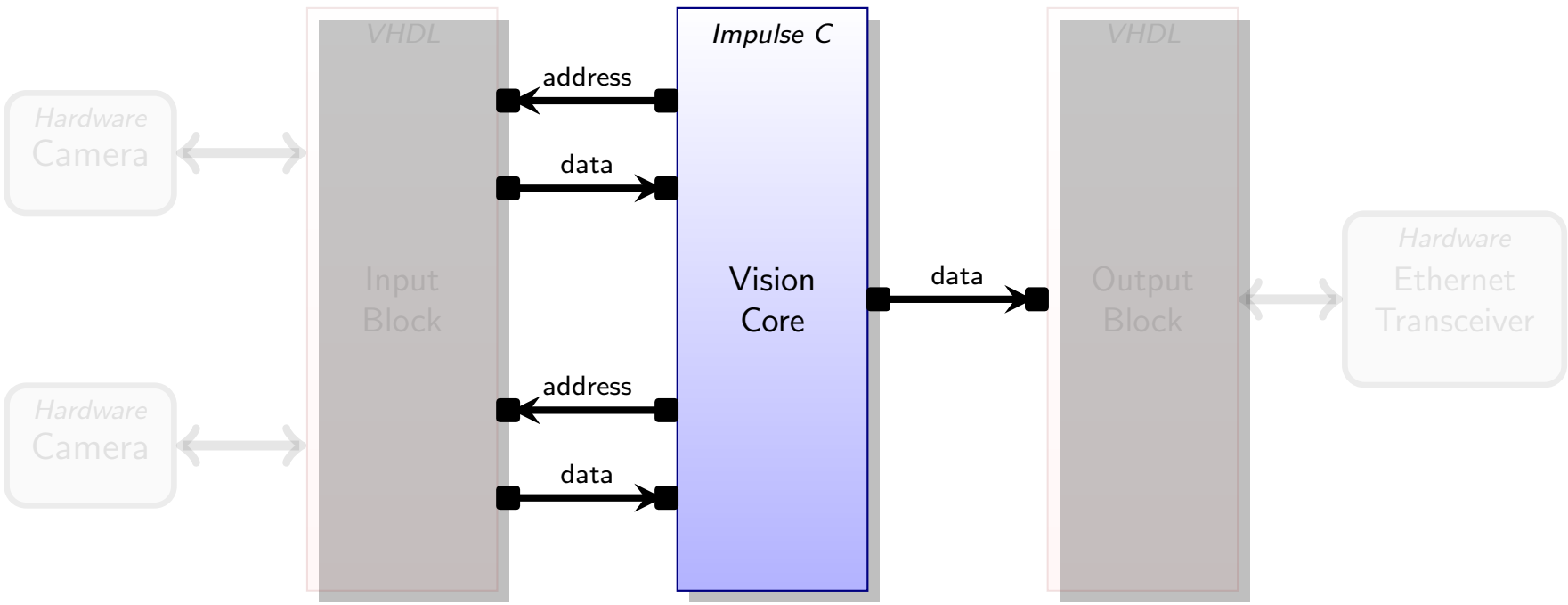




Stereo Vision System: System Architecture

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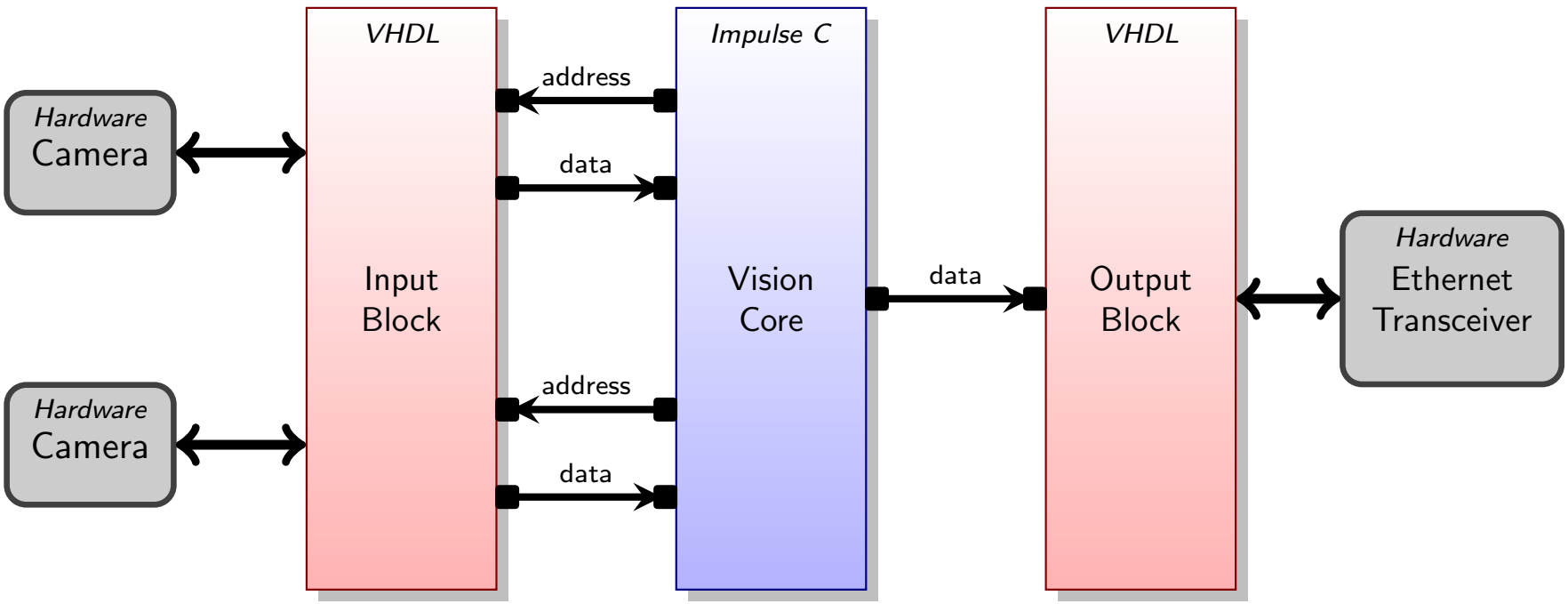
General Architecture



Stereo Vision System: System Architecture

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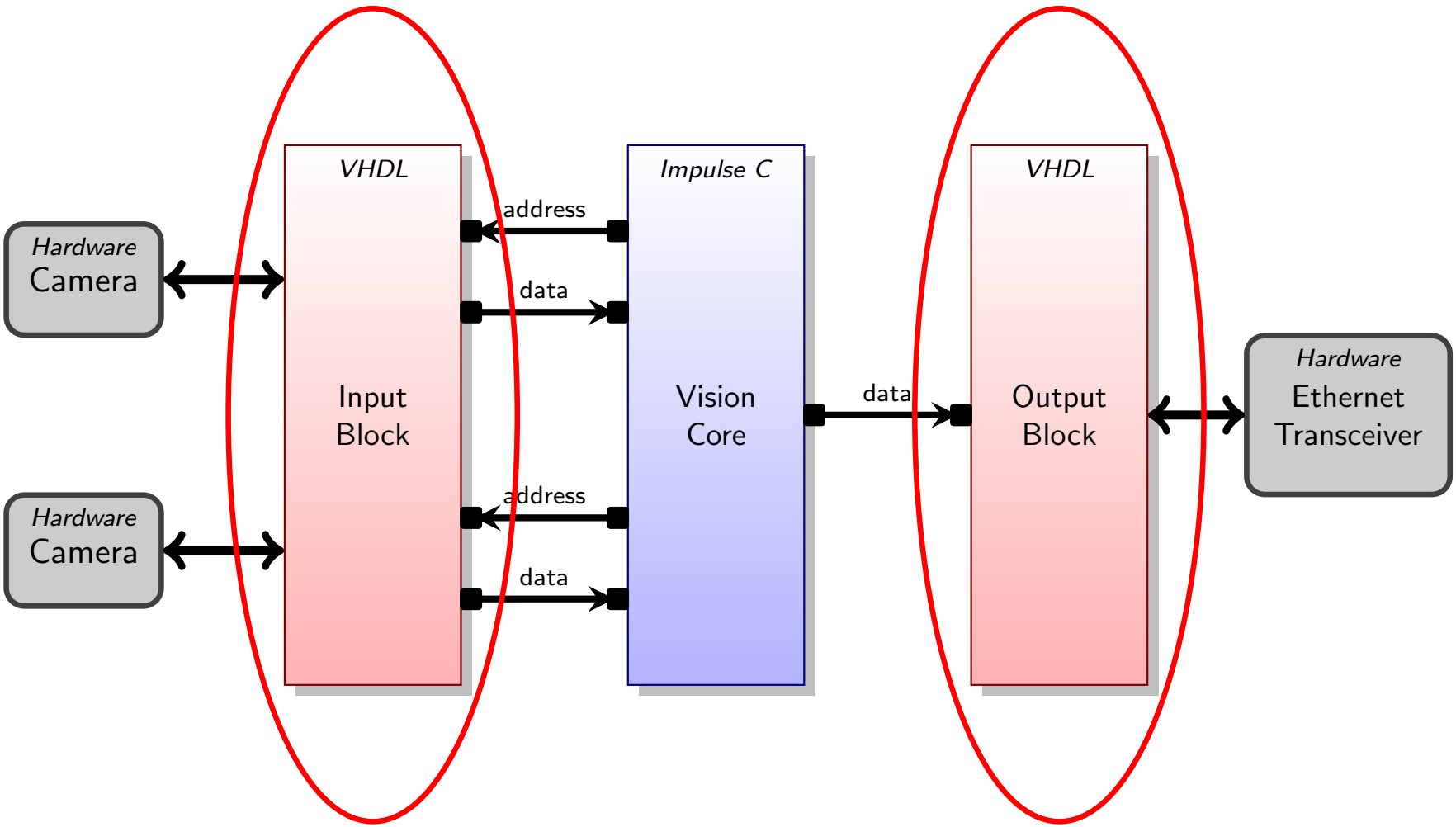
General Architecture



Stereo Vision System: System Architecture

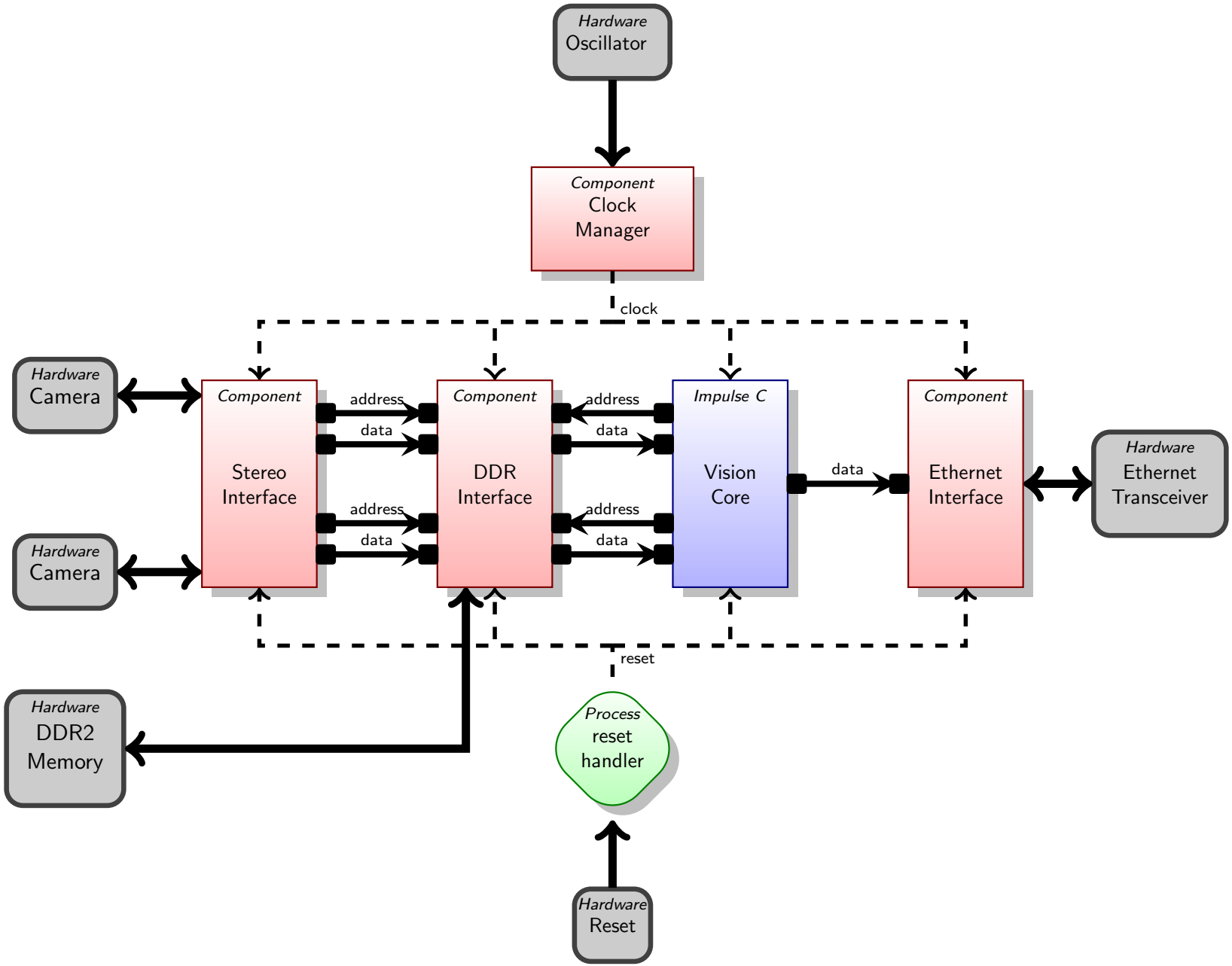
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General Architecture

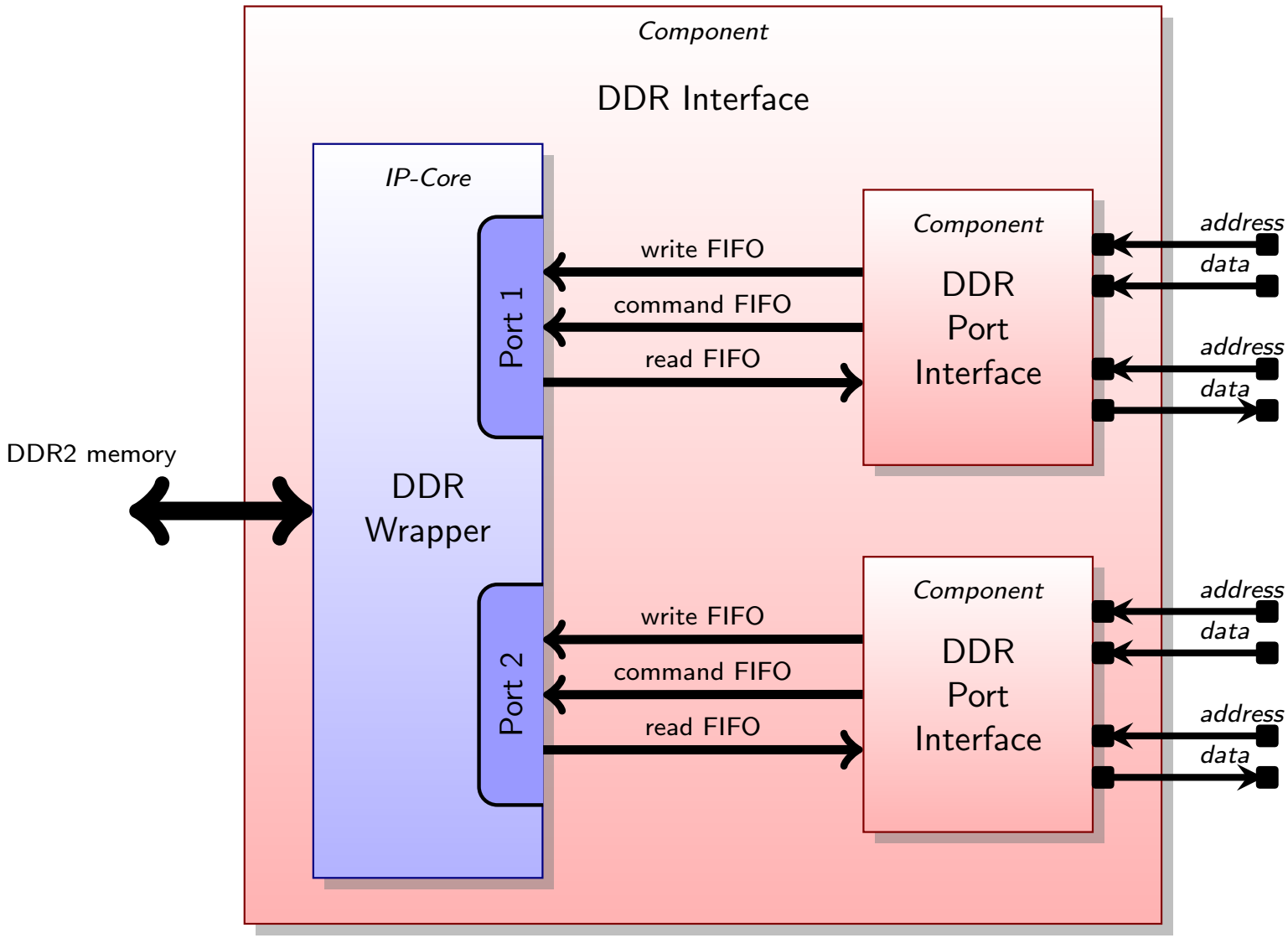


Stereo Vision System: Framework Overview

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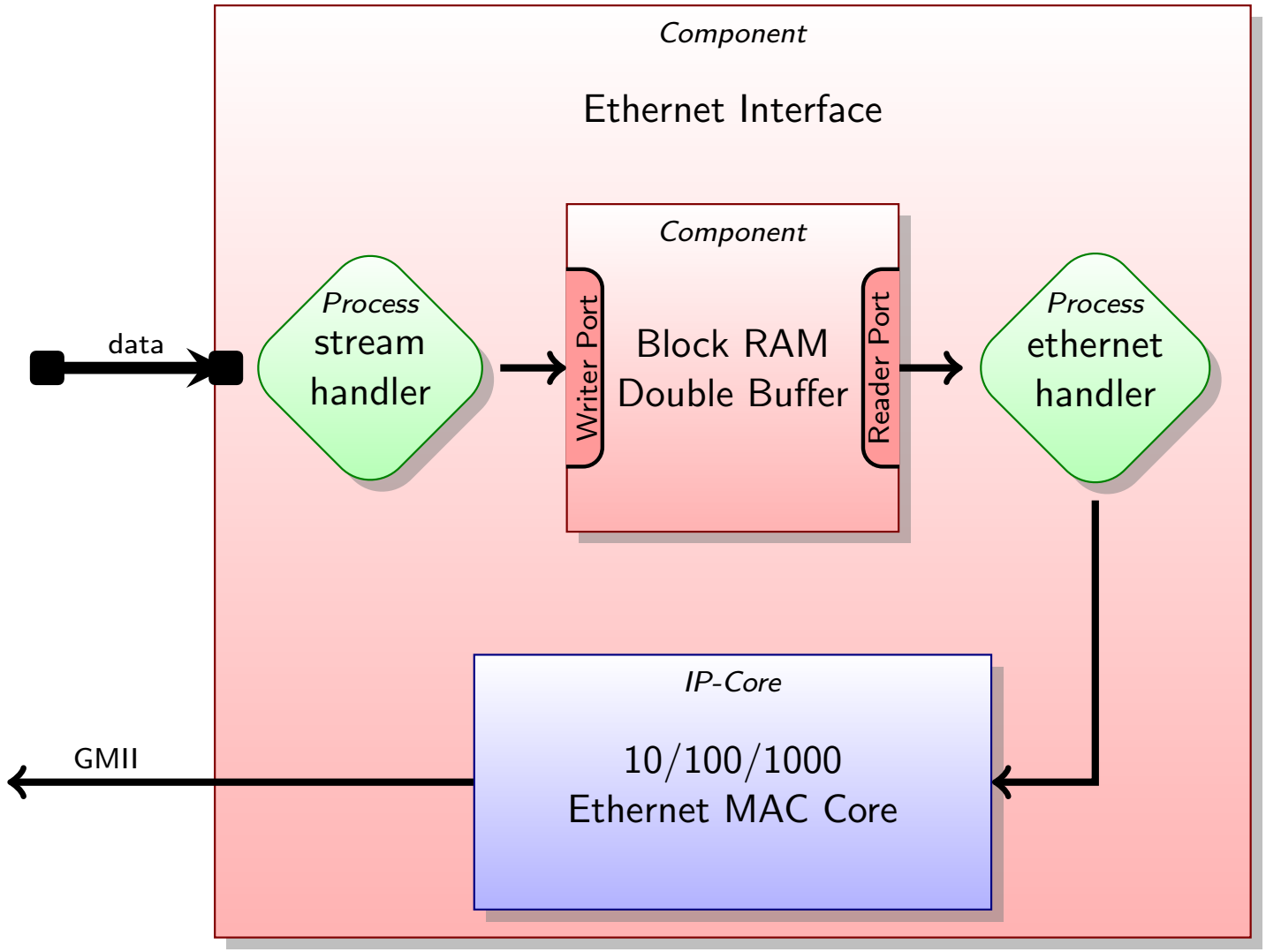


Stereo Vision System: DDR Interface



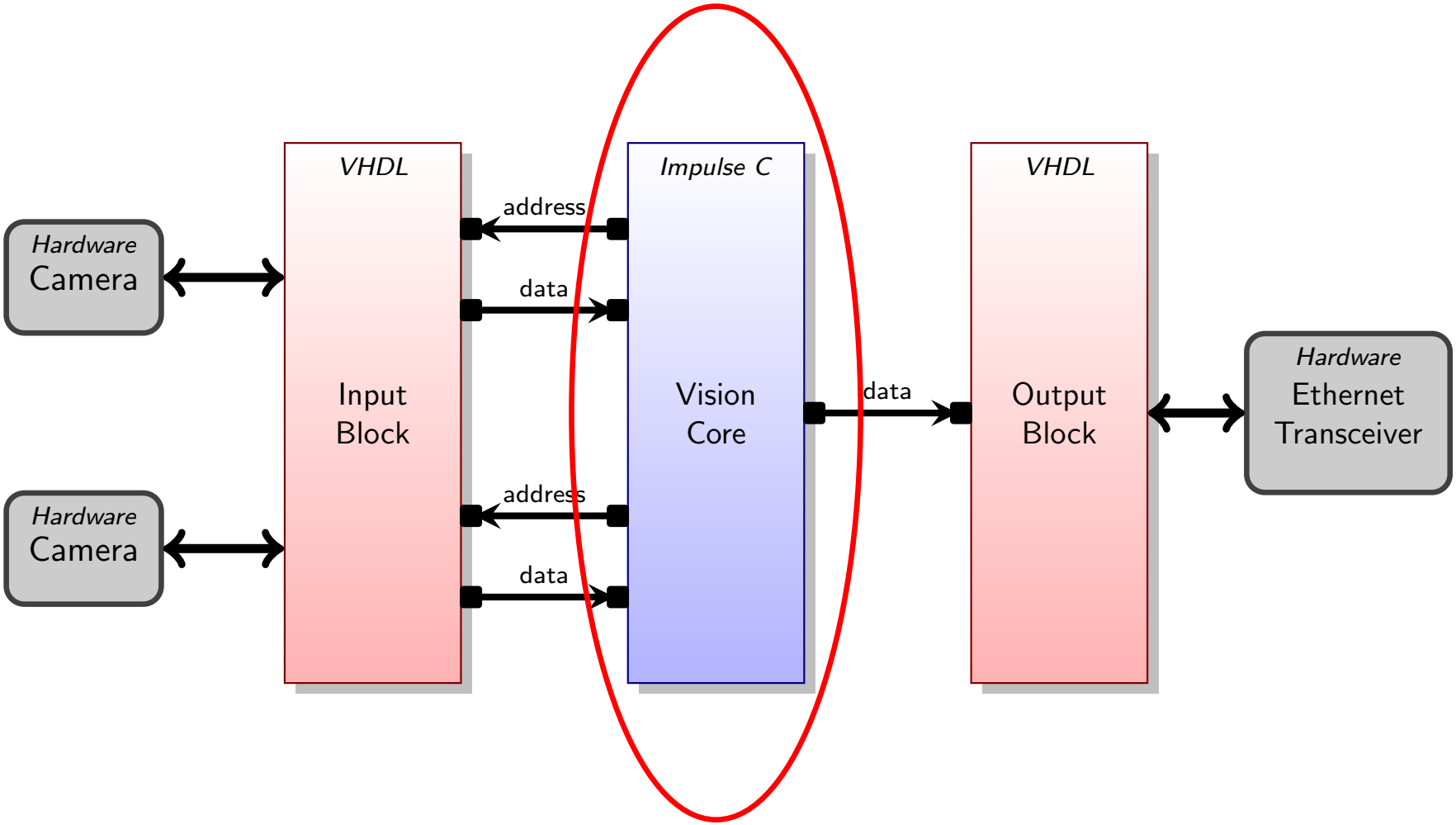
Stereo Vision System: Ethernet Interface

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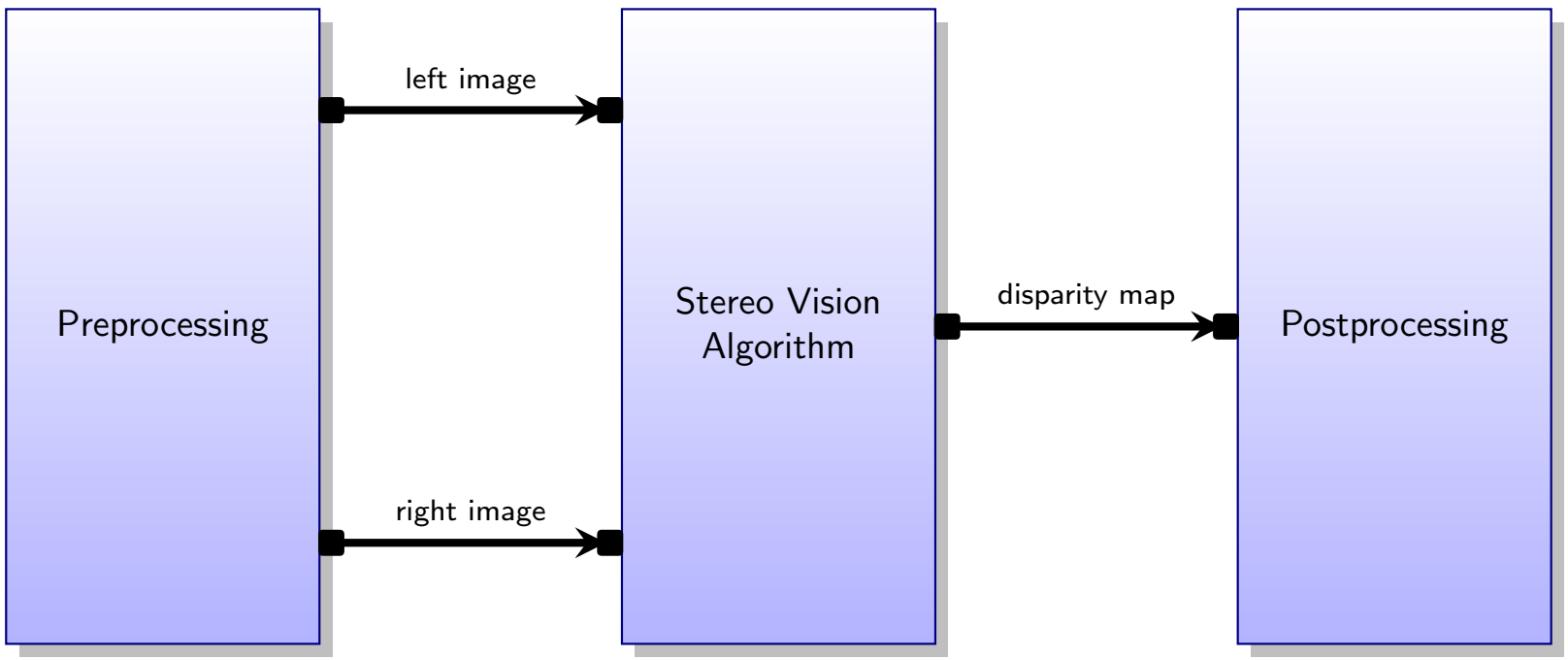
Vision Core: Design

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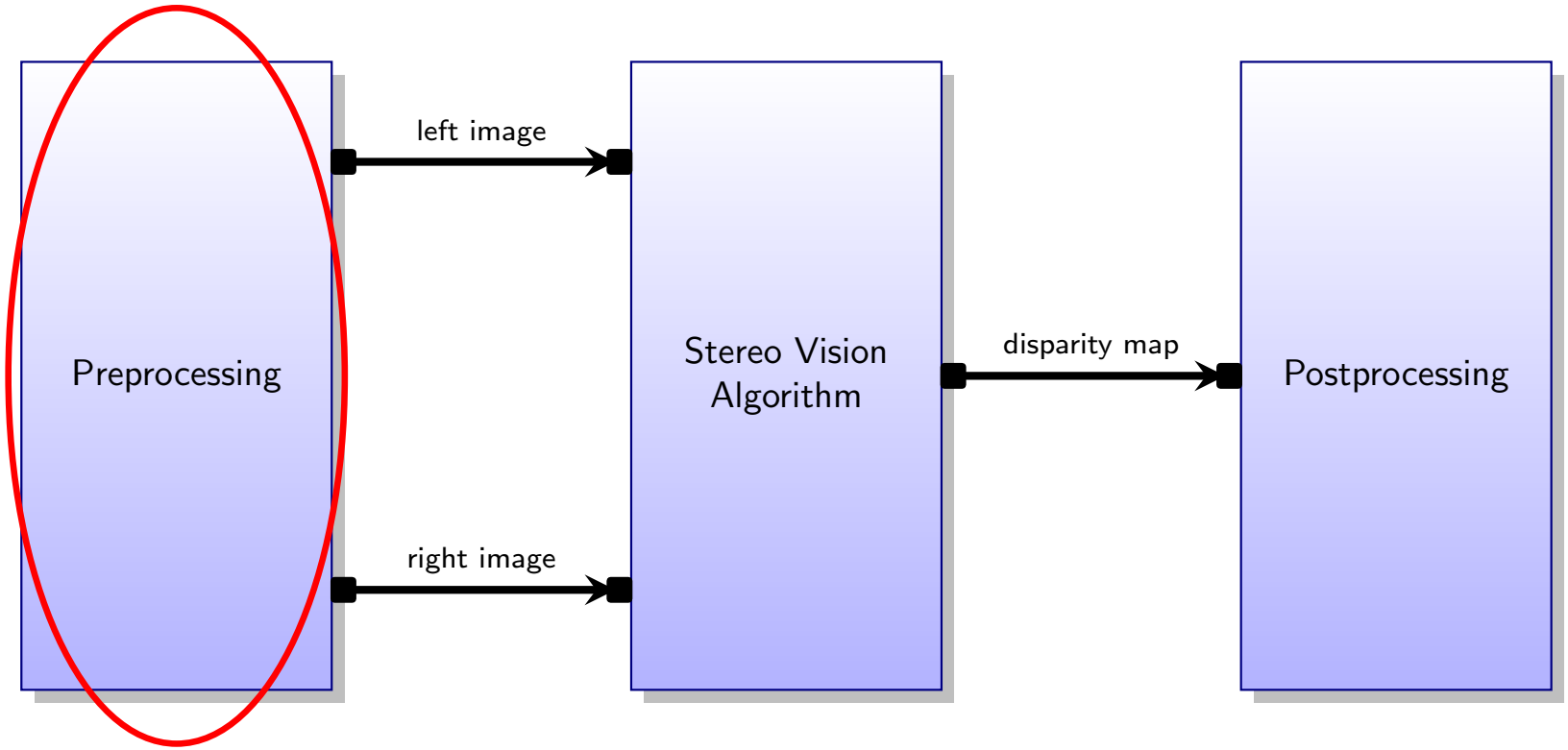
Vision Core: Design

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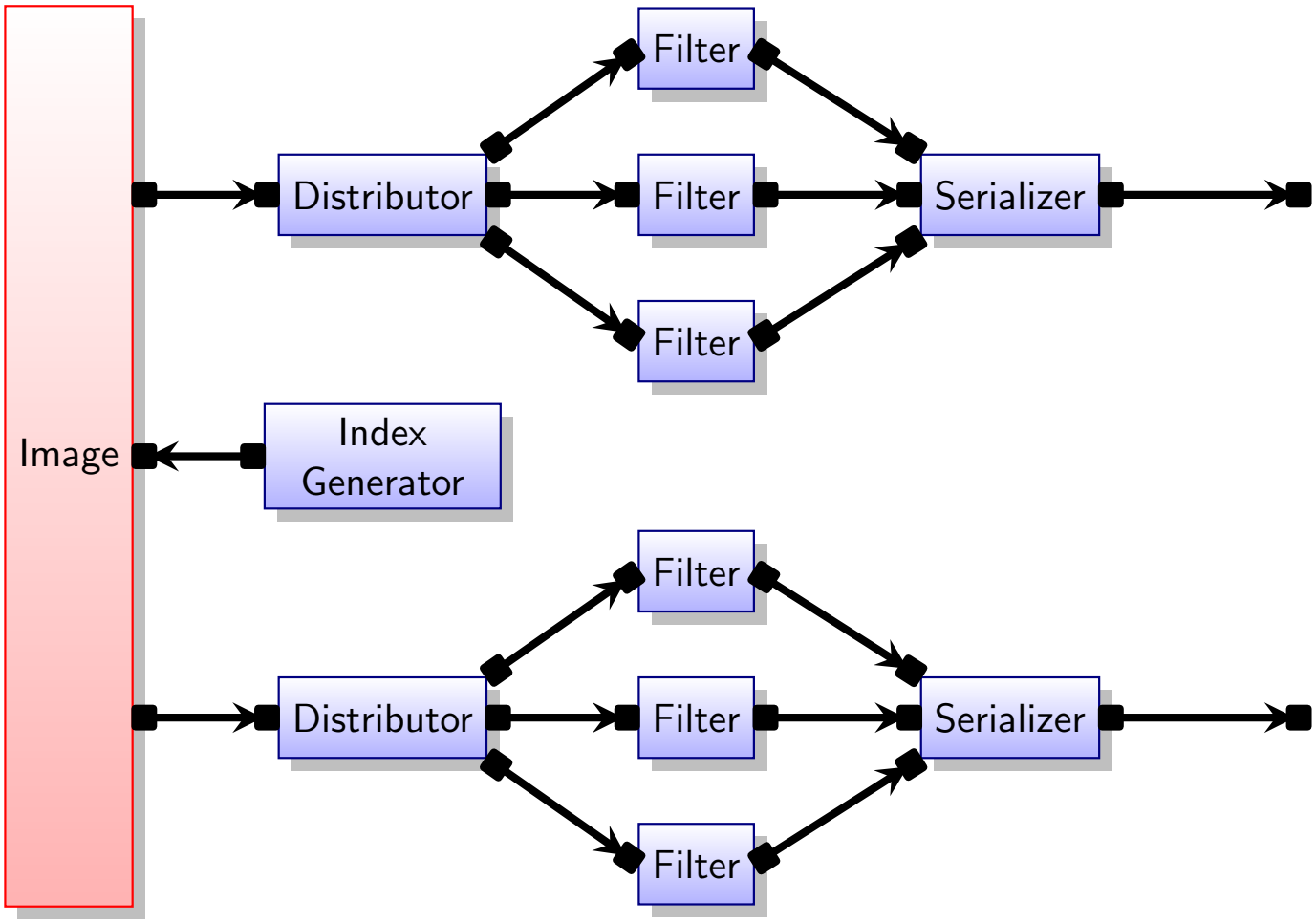
Vision Core: Design

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Architecture



Vision Core: Preprocessing

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- Four different image filter implemented in **C** and tested:
  - Gaussian filter
  - Median filter
  - Hybrid median filter
  - Bilateral filter
- Bilateral filter implemented in **Impulse C**:
  - Has most parameterization possibilities
  - Can act as Gaussian and median filter
  - Implementable in $\mathcal{O}(1)$ for arbitrary kernel window sizes[1]

[1] Ben Weiss. „Fast median and bilateral filtering“. In: ACM Trans. Graph. 25.3 (2006), pp. 519–526

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Illustration

- Three example filter windows with corresponding convolution
- Edge enhancing and smoothing in one run recognizable



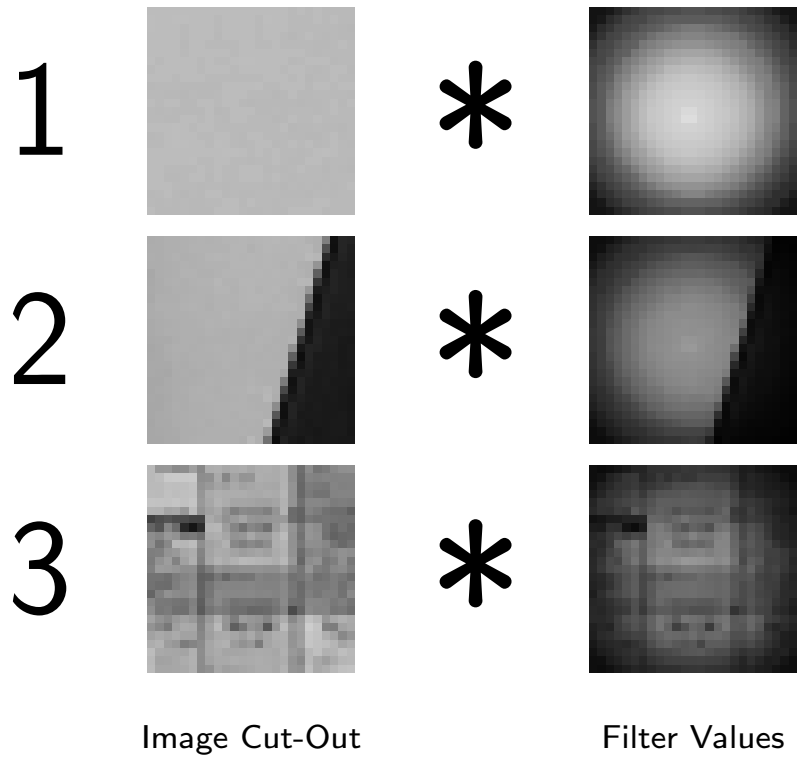


Image Cut-Out Filter Values

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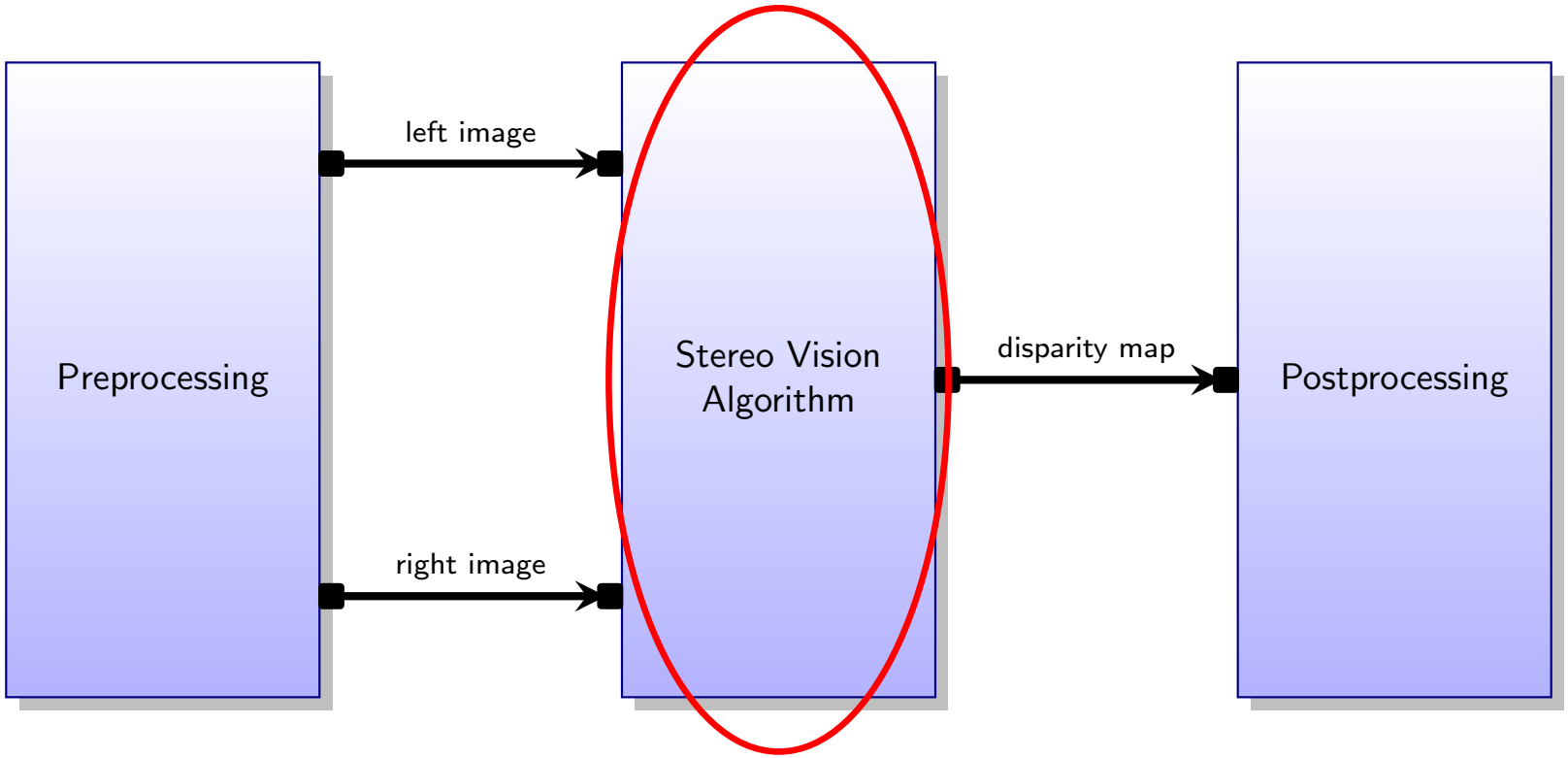
Illustration





Vision Core: Scan-Line based Segmentation

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Vision Core: Scan-Line based Segmentation

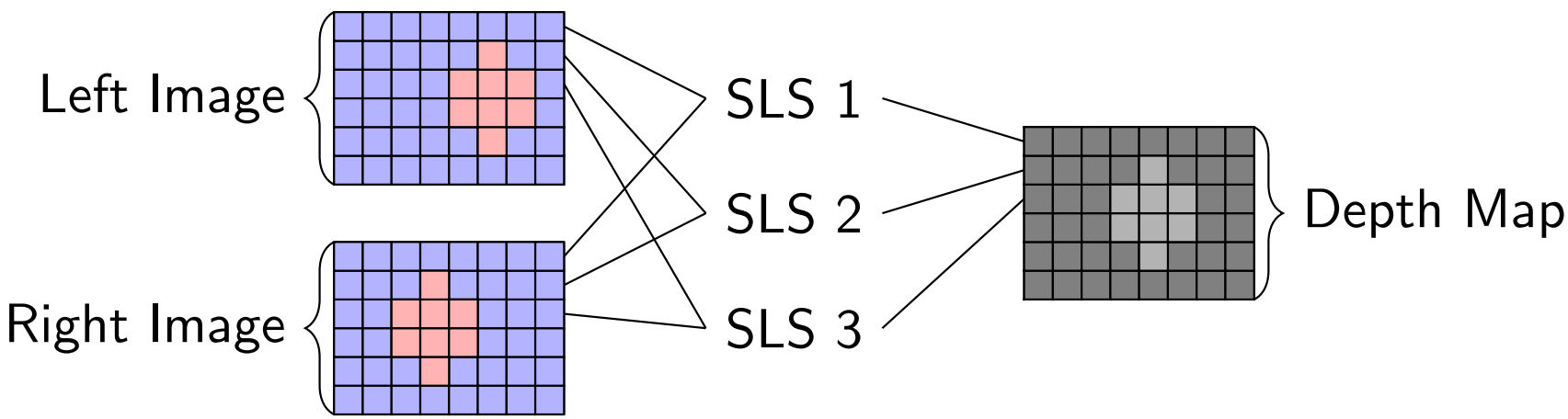
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Implementation

- Straight forward
- Buffer one line from left and right image respectively
- Parallelization as in preprocessing problematic
- Other parallelization possibilities?

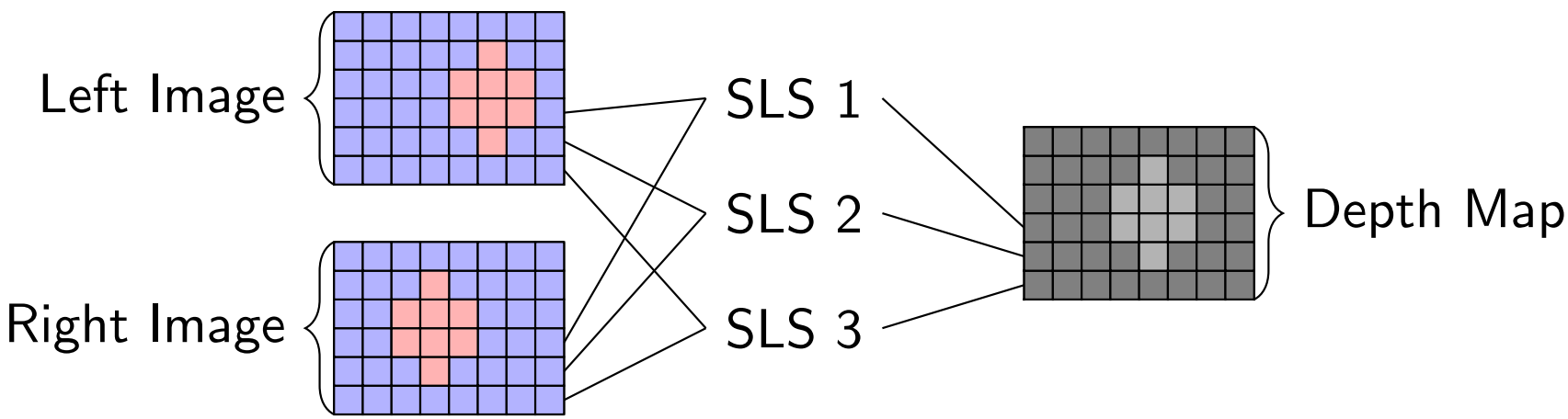
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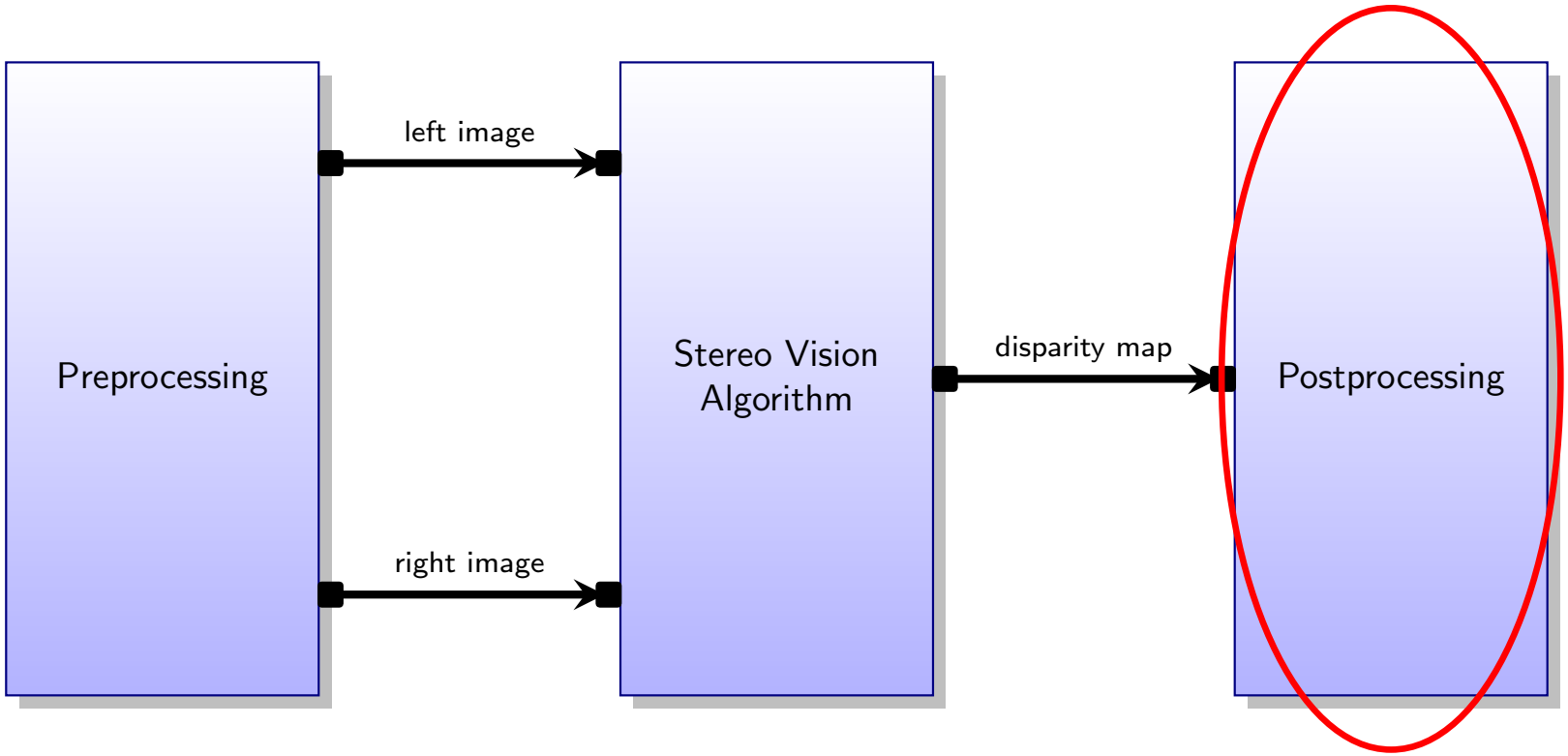
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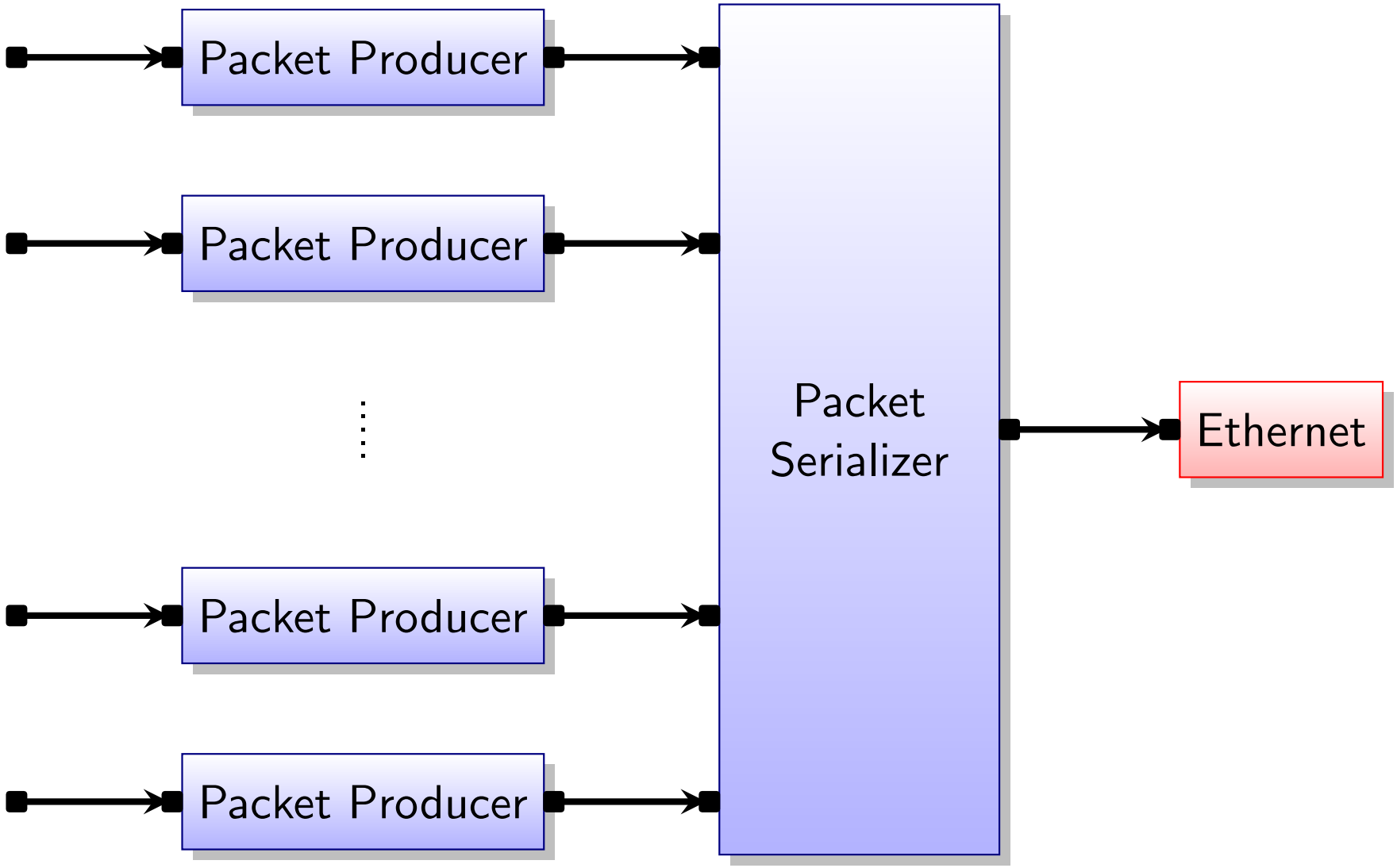
Vision Core: Scan-Line based Segmentation

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Vision Core: Postprocessing

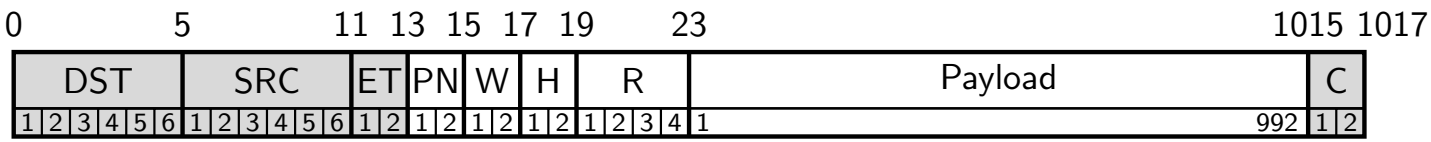
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Packet Producer

- Packets must allow host PC to distinguish between images
  - Packet type (ET)
  - Packet number (PN)
  - Width (W) and height (H)
- Raw Ethernet frames (IEEE 802.3) are used



Packet Serializer

- Buffers packets for VHDL Ethernet entity

Agenda

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Motivation

Basics

System Design

Stereo Vision System

Results

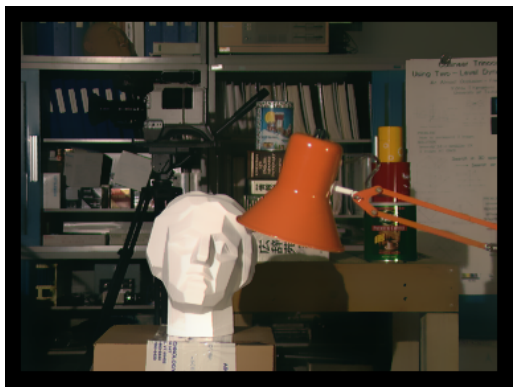
Summary and Outlook

Results: Bilateral Filter

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Unfiltered



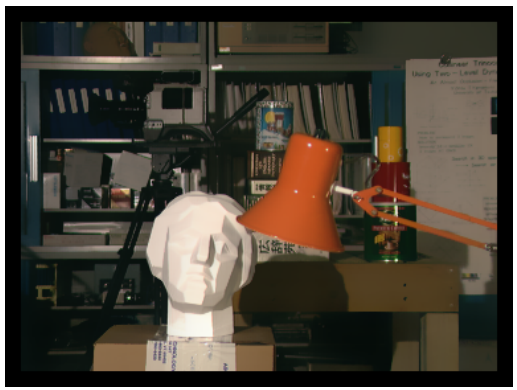
$\sigma = 0.05$



$\sigma = 0.15$

Results: Bilateral Filter

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Unfiltered | $\sigma = 0.05$ | $\sigma = 0.15$

Results: Scan-Line based Segmentation

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Left image



Right image



Bilateral filtered



Without bilateral filter



With bilateral filter

Results: Scan-Line based Segmentation

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Left image



Right image



Bilateral filtered



Without bilateral filter



With bilateral filter

Results: Interpretation

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- Smoothing is important in the present of noise
- Rectification more important
- Good illumination necessary for good results

Results: Performance

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Framework

	Frequency	Read transfer rate	Write transfer rate
Ethernet	10 MHz	–	154 Mbit/s
	25 MHz	–	386 Mbit/s
	50 MHz	–	772 Mbit/s
	100 MHz	–	954 Mbit/s
	200 MHz	–	954 Mbit/s
DDR	10 MHz	80 Mbit/s	53 Mbit/s
	25 MHz	200 Mbit/s	133 Mbit/s
	50 MHz	400 Mbit/s	267 Mbit/s
	100 MHz	457 Mbit/s	457 Mbit/s
	200 MHz	533 Mbit/s	533 Mbit/s

Results: Performance

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Vision Core

Component	Optimization	FPS
Bilateral Filter	without	3.742
	with	5.403
Median Filter	without	10.69
	with	14.79
Scan-Line based Segmentation	without	2.23
	with	5.70
Parallel Scan-Line based Segmentation	without	5.16
	with	12.08

Agenda

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Motivation

Basics

System Design

Stereo Vision System

Results

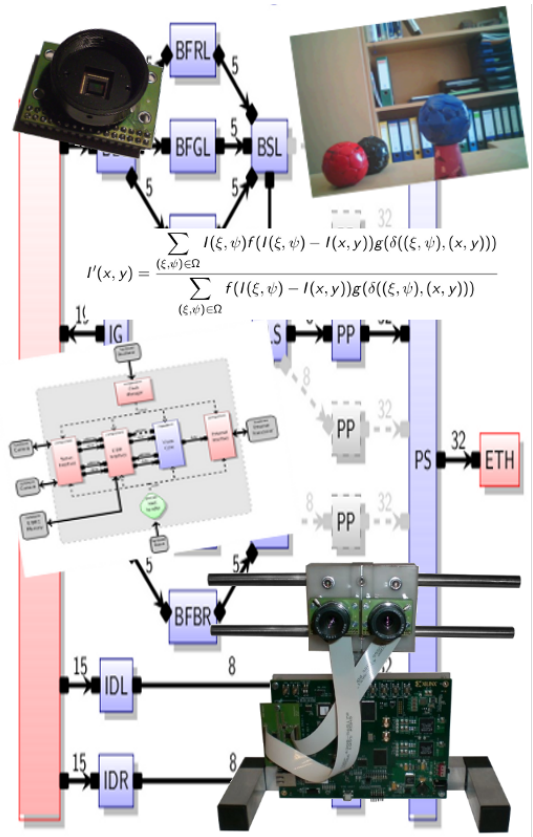
Summary and Outlook

Summary

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Contributions:

- Achieved cost-efficient prototyping Stereo Vision System
- Performed requirement analysis
- Analyzed available hardware components
- Designed own hardware adapters and cameras
- Developed generic framework for C developers
- Implemented Vision Core in Impulse C
- Developed system model for simulation
- Evaluated and optimized power dissipation, performance and resource requirements



Outlook

Possible enhancements:

- More sophisticated pre and post-processing
  - Other solutions often use simple algorithms (SAD) with complex pre and post-processing
- System configurable at run-time

Questions?

Figure References

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Slide Motivation 1

https://getwww.uni-paderborn.de/wiki/msr/images/2/2f/TSR.jpg
http:
//www-robotics.jpl.nasa.gov/projects/projectImage.cfm?Project=1&Image=335
http://astronomy.hccs.edu/astronomy/images/1152619main_panelsdeploy_med.jpg
http://www.eri.harvard.edu/faculty/peli/projects/enhanced.jpg

Slide Basics FPGA

http://samkerr.files.wordpress.com/2009/09/556px-fpga_xilinx_spartan.jpg

Slide Basics FPGA 2

http://www.xilinx.com/images/circuitblock.jpg

Slide Hardware: SP601

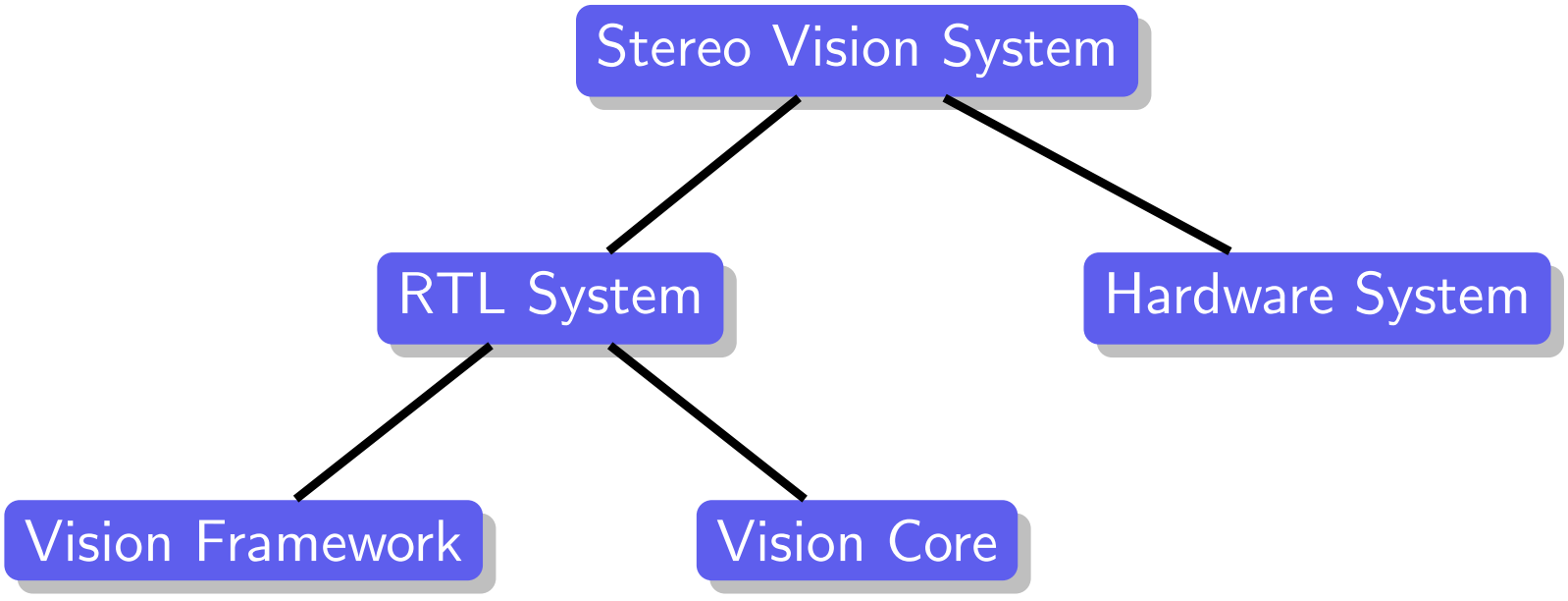
http://www.xilinx.com/products/devkits/EK-S6-SP601-G-image.htm

Stereo Example Pictures

http://cat.middlebury.edu/stereo/data.html

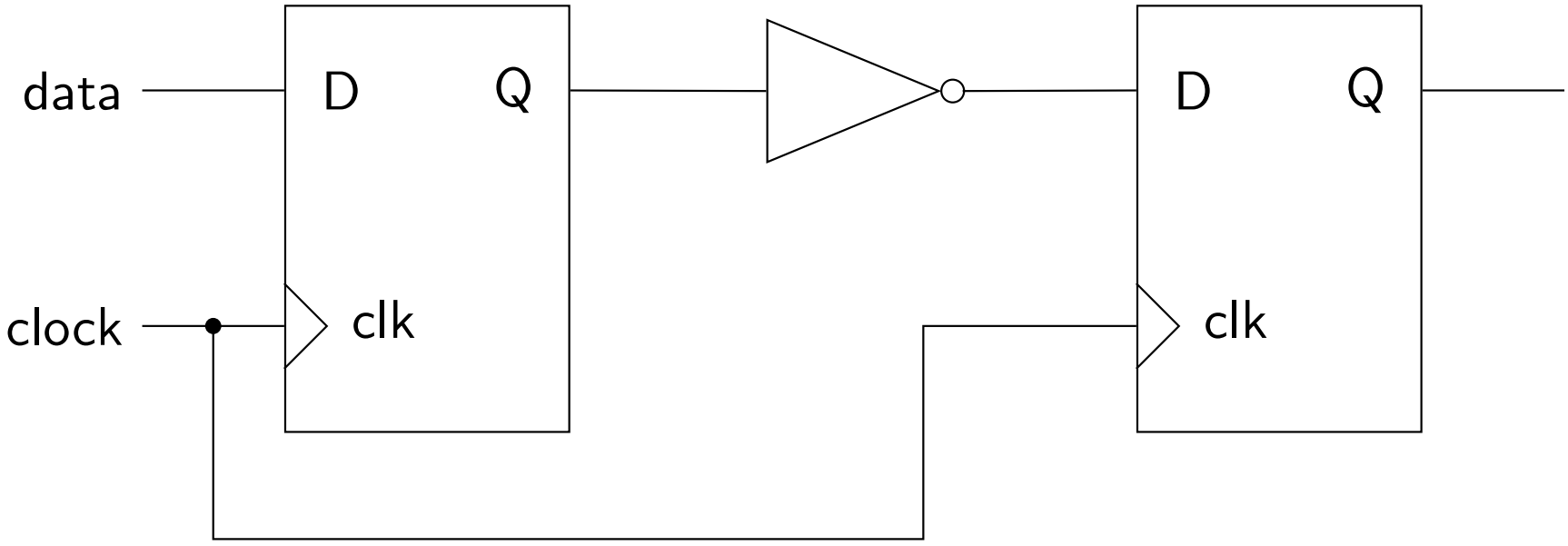
Appendix: Taxonomy

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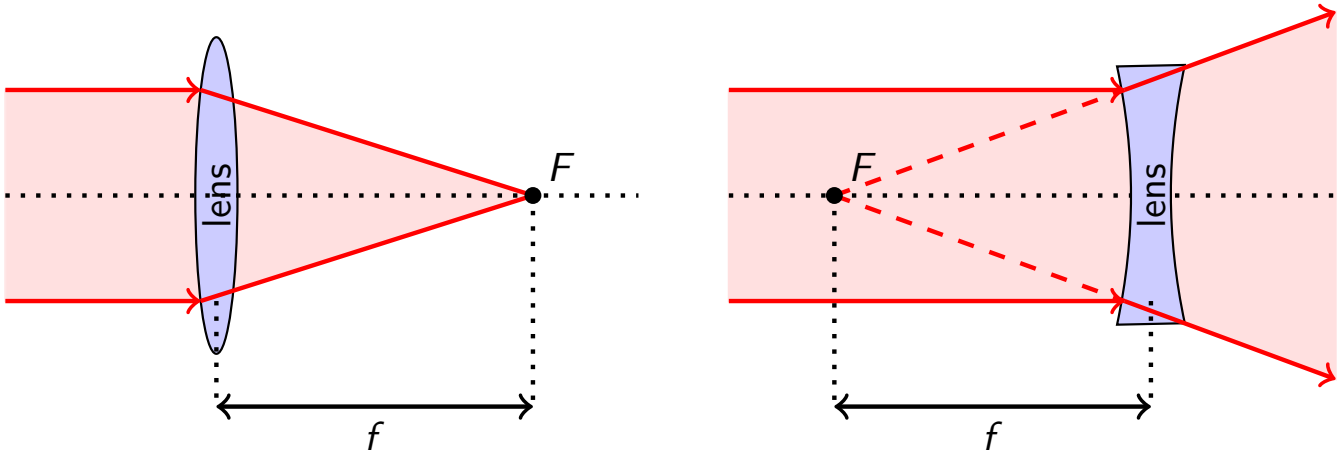
Appendix: Register Transfer Logic

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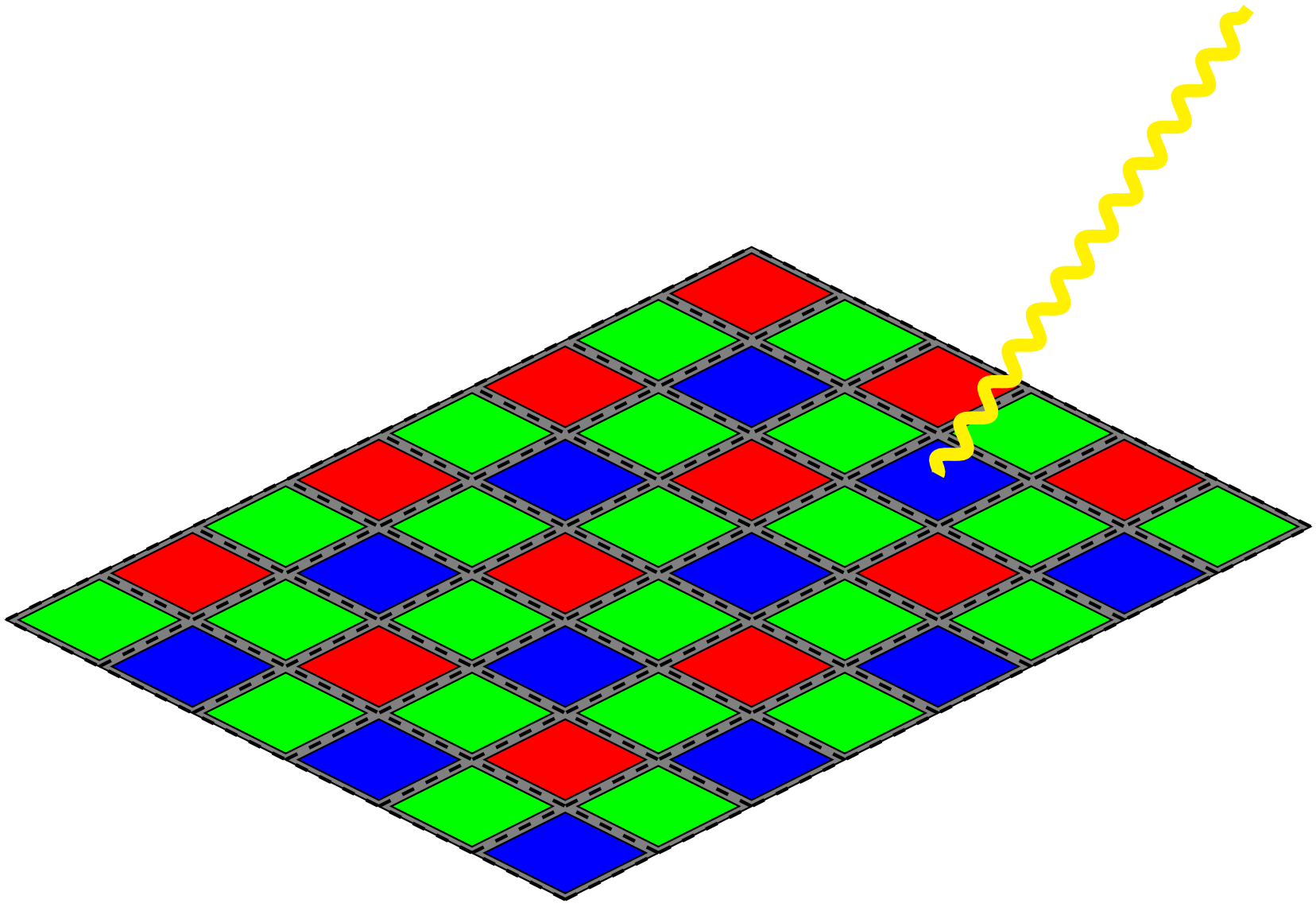
Appendix: Focal Length

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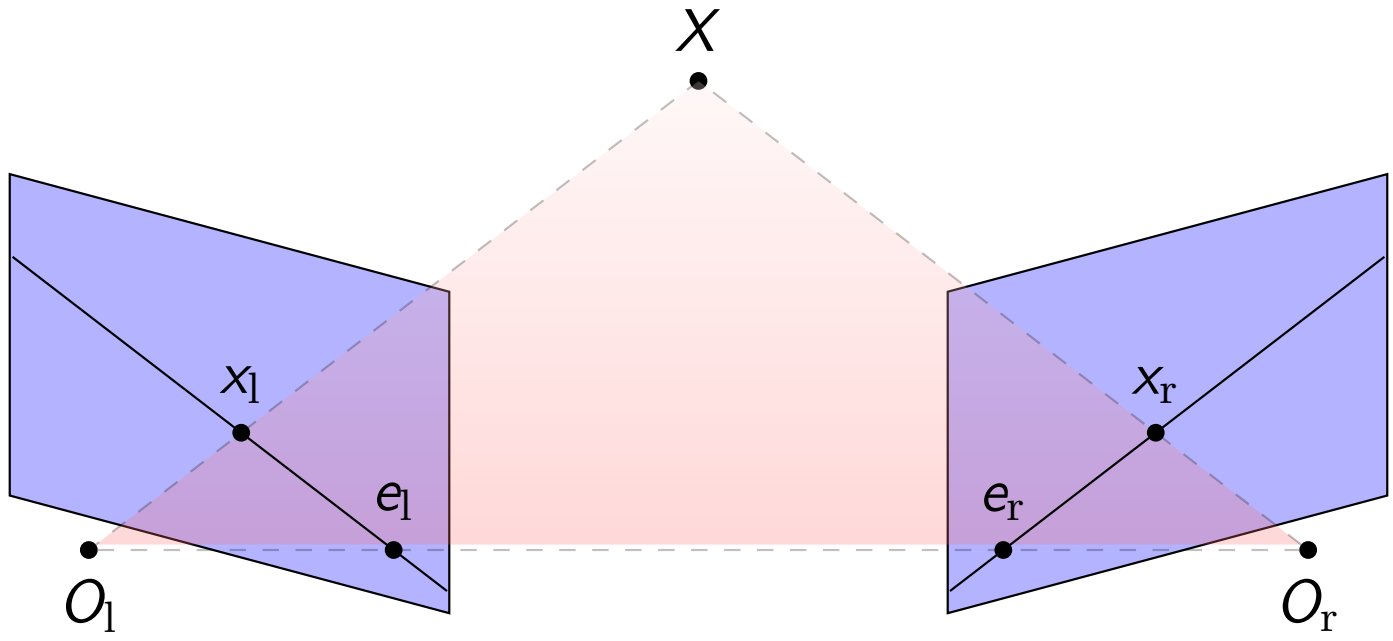
Appendix: Bayer Pattern

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Appendix: Epipolar Geometry

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Appendix: Formulae 1

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Gaussian

$$G_\sigma(x,y) = \frac{1}{\sqrt{2\pi\sigma^2}} e^{-\frac{x^2+y^2}{2\sigma^2}},$$

Bilateral Filter

$$I'(x,y) = \frac{\int_{-\infty}^{\infty}\int_{-\infty}^{\infty} I(\xi,\psi) f(I(\xi,\psi) - I(x,y)) g(\delta((\xi,\psi),(x,y)))\,\mathrm{d}\xi\,\mathrm{d}\psi}{\int_{-\infty}^{\infty}\int_{-\infty}^{\infty} f(I(\xi,\psi) - I(x,y)) g(\delta((\xi,\psi),(x,y)))\,\mathrm{d}\xi\,\mathrm{d}\psi}$$

Geometric Distance

$$\delta((\xi,\psi),(x,y)) = \sqrt{(\xi-\psi)^2 + (x-y)^2}.$$

Appendix: Formulae 2

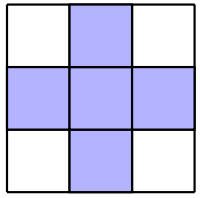
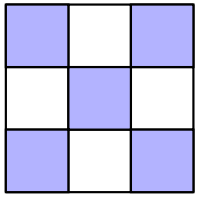
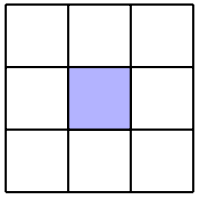
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Bilateral Filter with Histogram

$$I'(x,y) = \frac{\sum_{i=0}^{2^d-1} i \cdot G_\sigma(i - I(x,y)) \cdot H(i)}{\sum_{i=0}^{2^d-1} G_\sigma(i - I(x,y)) \cdot H(i)}.$$

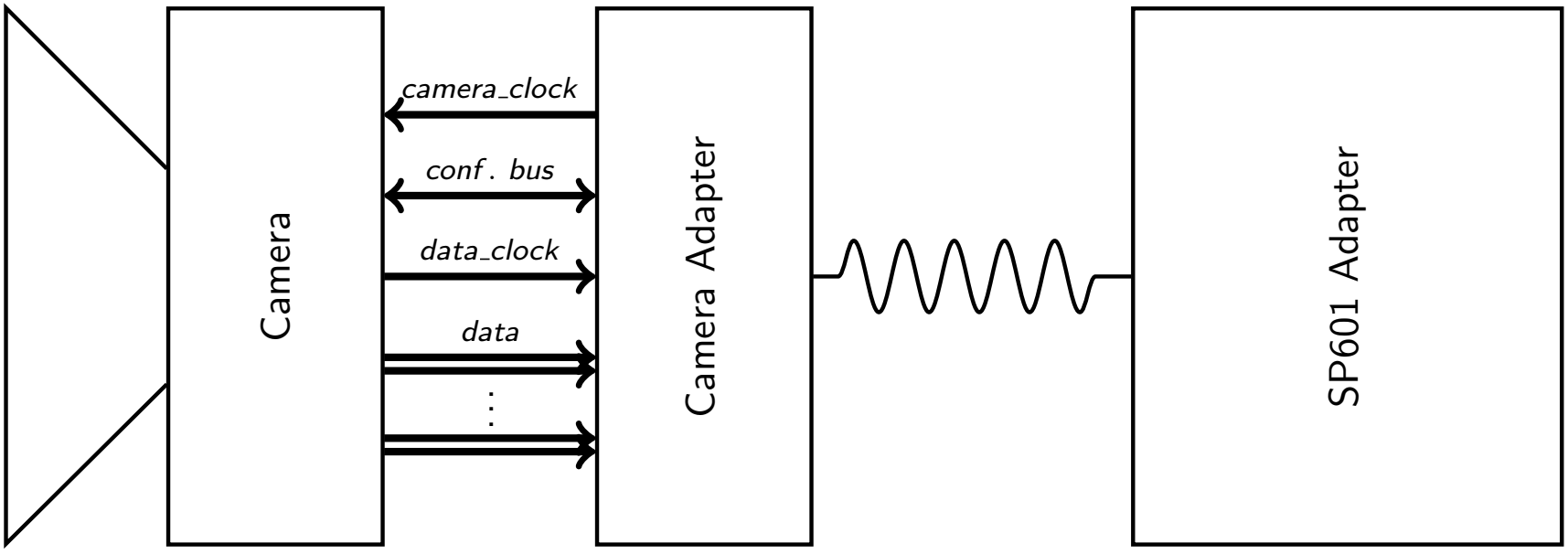
Appendix: Hybrid Median

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$$\text{med}\left(\text{med}\left(\ \right.\right.$$  $$\left.\left.\ \right), \text{med}\left(\ \right.\right.$$  $$\left.\left.\ \right), \text{med}\left(\ \right.\right.$$  $$\left.\left.\ \right)\right)$$

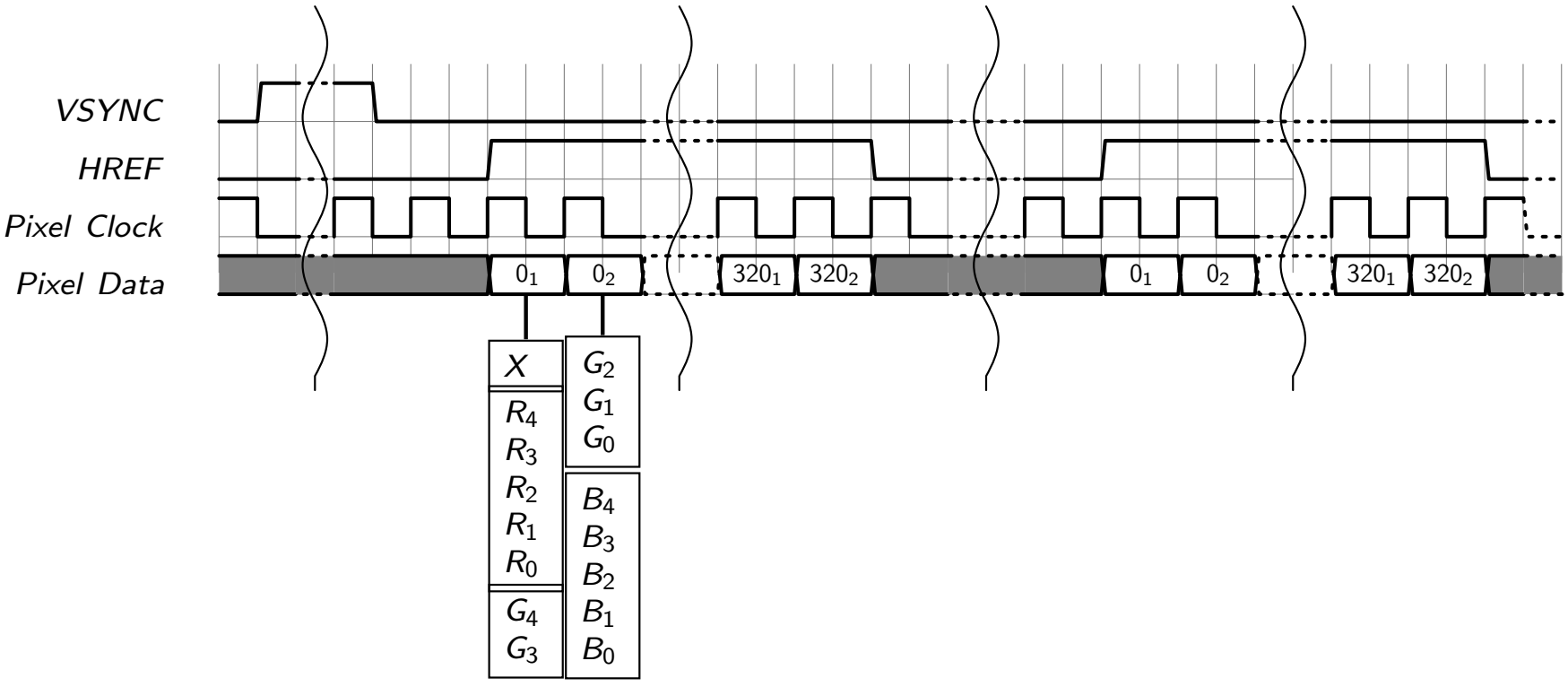
Appendix: Adapter Board Architecture

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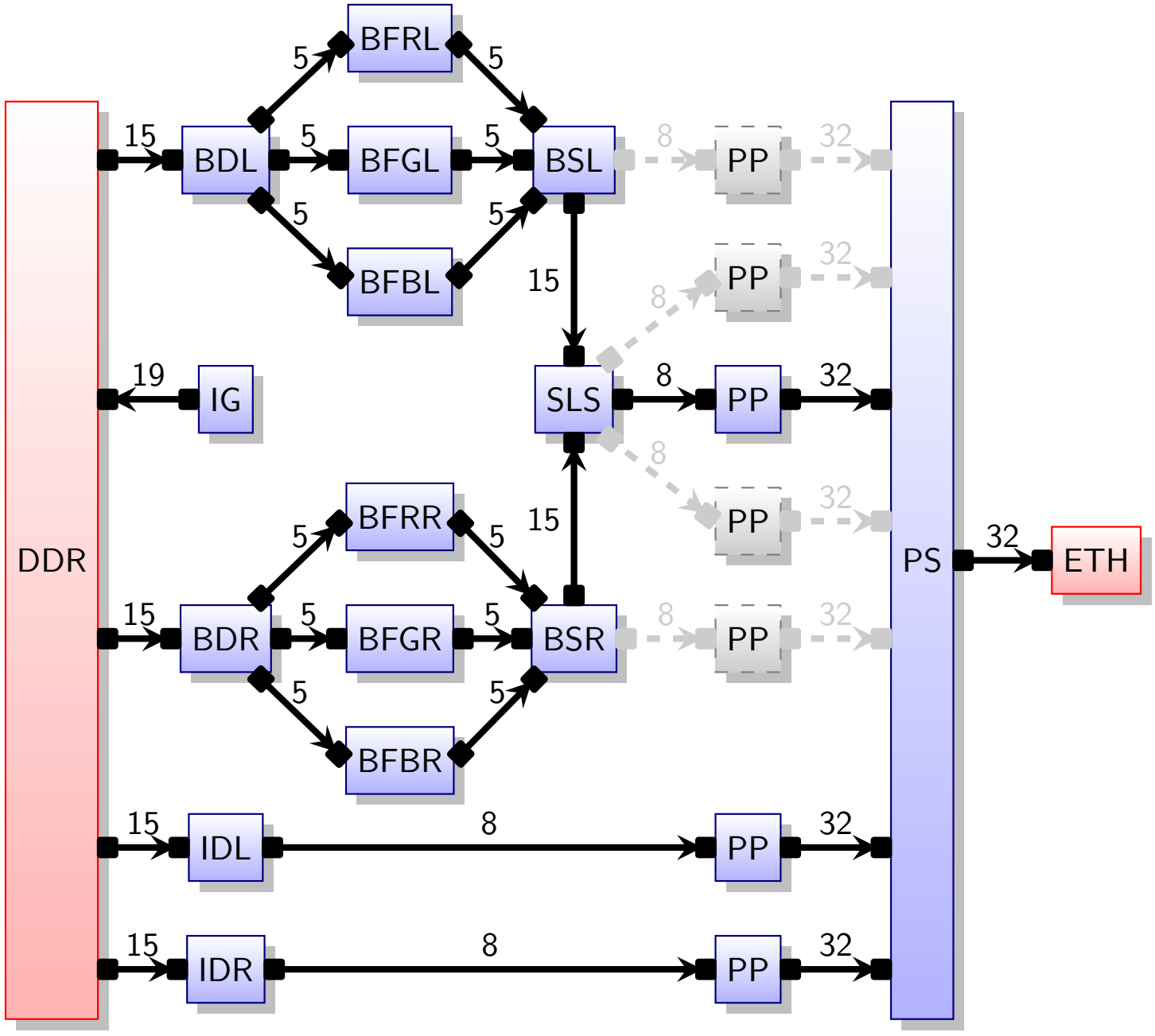
Appendix: Camera Timing Diagram

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Appendix: Vision Core Architecture

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Appendix: Vision Framework Clocks

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Signal	Speed	Purpose
*CLK*600	600 MHz	Doubled clock for DDR memory
*CLK*300	300 MHz	Clock for DDR memory
*CLK*200	200 MHz	Clock for DDR Interface operations
*CLK*125	125 MHz	Clock for Ethernet transceiver
*CLK*100	100 MHz	Clock for Stereo Interface
*CLK*66	66 MHz	Clock for Vision Core
*CLK*25	25 MHz	Clock to drive external cameras

Appendix: Hardware Selection

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	Development Board	Number of Slices/LE	Price	USB 2.0 High Speed	Gigabit Ethernet
Altera	Stratix IV GX	124 k	4,500 $	no	yes
	Stratix IV E	531 k	10,000 $	no	yes
	Arria II GX	124 k	1,500 $	no	yes
	Cyclone II	20 k	200 $	no	no
	Cyclone III	24 k	200 $	no	no
Xilinx	ML405	19 k	800 $	no	yes
	ML605	241 k	2,500 $	no	yes
	SP601	14 k	300 $	no	yes
	SP605	43 k	500 $	no	yes

Appendix: Vision Framework Slices

GET Lab

Component	Slices	Slice Register	Slice LUTs	BRAM blocks
Available on SP601	2278	18224	9112	32^2
Clock Manager	5	25	1	0
Block RAM Double Buffer	16	52	14	1
Stereo Interface (OV7)	382	675	889	2
OV7 Interface	181	295	407	0
Stereo Interface (MT9)	374	675	909	4
MT9 Interface	173	295	417	2
Camera Configurator	120	183	330	0
DDR Interface	336	634	668	0
DDR Port Interface	66	215	105	0
Ethernet Interface	536	1259	1040	4

Appendix: Vision Core Slices

GET Lab

		Slices	Slice Register	Slice LUTs	BRAM blocks
	Available on SP601	2278	18224	9112	32/64[3]
	Optimization				
Bilateral Filter	without	138	309	339	9
	+ pipel. convolution	35	106	93	9
	+ pipel. histogram update	51	103	132	18
	+ pipel. distributor/serializer	55	106	131	11
	+ non-recursive arrays	54	103	132	9
	+ primitive function flatten	56	106	130	14
Median Filter	without	64	107	145	14
	+ pipel. convolution	65	127	164	14
	+ pipel. histogram update	90	146	222	14
	+ pipel. distributor/serializer	96	146	218	14
	+ non-recursive arrays	94	145	211	14
	+ primitive function flatten	96	140	224	14
SLS	without	320	340	1046	16
	+ pipel. pixel conversion	279	398	874	36
	+ pipel. distance calculation	424	825	1089	36
	+ pipel. image calculation	403	826	1078	36
	+ non-recursive arrays	438	826	1065	36
PSLS	without	1104	1020	2987	33
	+ SLS optimizations	1101	2406	3295	30
	+ pipel. distributor/serializer	1155	2406	3309	30

Appendix: Vision Core Slices 2

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		Slices	Slice Register	Slice LUTs	BRAM blocks
Available on SP601		2278	18224	9112	32/64
Filter	Optimized				
Median	no	1742	3382	5279	35
	yes	1949	4122	5953	35
Bilateral	no	2118	4474	6718	35
	yes	2224	5677	7623	35

Appendix: Vision Core Power Dissipation

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	Optimization	Overall power consumption
Bilateral Filter	without	316.36 mW
	+ pipelining convolution	309.79 mW
	+ pipelining histogram update	309.89 mW
	+ pipelining distributor/serializer	306.85 mW
	+ non-recursive arrays	307.73 mW
	+ primitive function flatten	311.46 mW
Median Filter	without	309.14 mW
	+ pipelining convolution	310.79 mW
	+ pipelining histogram update	312.13 mW
	+ pipelining distributor/serializer	300.75 mW
	+ non-recursive arrays	299.14 mW
	+ primitive function flatten	298.61 mW
SLS	without	322.79 mW
	+ pipelining pixel conversion	321.77 mW
	+ pipelining distance calculation	321.28 mW
	+ pipelining image calculation	321.67 mW
	+ non-recursive arrays	320.43 mW
PSLS	without	379.84 mW
	+ SLS optimizations	379.84 mW
	+ pipel. distributor/serializer	359.15 mW