

# Xilinx OpenCV User Guide

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# Revision History

The following table shows the revision history for this document.

Section	Revision Summary
<b>07/02/2018 Version 2018.2</b>	
<a href="#">Houghlines</a>	Updated the function description and its respective tables
<a href="#">xfOpenCV Library Functions</a>	Added a note to the xfOpenCV Library Functions table
<b>06/06/2018 Version 2018.2</b>	
<a href="#">Houghlines</a>	Added a new function
<a href="#">Semi Global Method for Stereo Disparity Estimation</a>	Added a new function
<b>04/04/2018 Version 2018.1</b>	
General Updates	Minor editorial updates for 2018.1 release
<a href="#">InitUndistortRectifyMapInverse</a>	Added a new function
<a href="#">cornersImgToList()</a>	Added a new function

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# Overview

This document describes the FPGA device optimized OpenCV library, called the Xilinx<sup>®</sup> xfOpenCV library and is intended for application developers using Zynq<sup>®</sup>-7000 SoC and Zynq UltraScale+ MPSoC devices. xfOpenCV library has been designed to work in the SDx<sup>™</sup> development environment, and provides a software interface for computer vision functions accelerated on an FPGA device. xfOpenCV library functions are mostly similar in functionality to their OpenCV equivalent. Any deviations, if present, are documented.

**Note:** For more information on the xfOpenCV library prerequisites, see the [Prerequisites](#). To familiarize yourself with the steps required to use the xfOpenCV library functions, see the [Using the xfOpenCV Library](#).

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## Basic Features

All xfOpenCV library functions follow a common format. The following properties hold true for all the functions.

- All the functions are designed as templates and all arguments that are images, must be provided as `xf::Mat`.
- All functions are defined in the `xf` namespace.
- Some of the major template arguments are:
  - Maximum size of the image to be processed
  - Datatype defining the properties of each pixel
  - Number of pixels to be processed per clock cycle
  - Other compile-time arguments relevant to the functionality.

The xfOpenCV library contains enumerated datatypes which enables you to configure `xf::Mat`. For more details on `xf::Mat`, see the [xf::Mat Image Container Class](#).

# xfOpenCV Kernel on the reVISION Platform

The xfOpenCV library is designed to be used with the SDx™ development environment. xfOpenCV kernels are evaluated on the reVISION™ platform.

The following steps describe the general flow of an example design, where both the input and the output are image files.

1. Read the image using `cv::imread()`.
2. Copy the data to `xf::Mat`.
3. Call the processing function(s) in xfOpenCV.
4. Copy the data from `xf::Mat` to `cv::Mat`.
5. Write the output to image using `cv::imwrite()`.

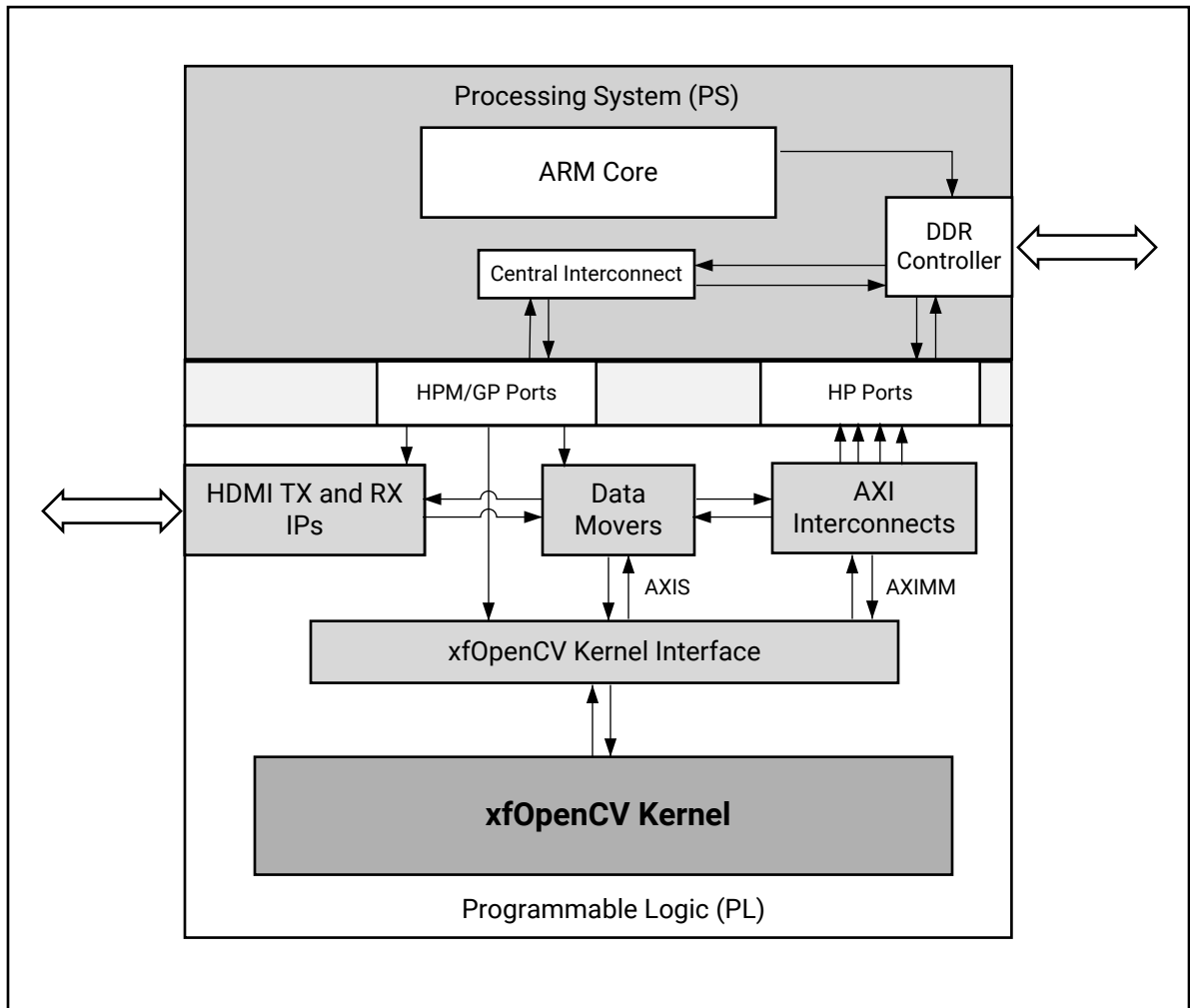
The entire code is written as the host code for the pipeline, from which all the calls to xfOpenCV functions are moved to hardware. Functions from OpenCV are used to read and write images in the memory. The image containers for xfOpenCV library functions are `xf::Mat` objects. For more information, see the [xf::Mat Image Container Class](#).

The reVISION platform supports both live and file input-output (I/O) modes. For more details, see the [reVISION Getting Started Guide](#).

- File I/O mode enables the controller to transfer images from SD Card to the hardware kernel. The following steps describe the file I/O mode.
  1. Processing system (PS) reads the image frame from the SD Card and stores it in the DRAM.
  2. The xfOpenCV kernel reads the image from the DRAM, processes it and stores the output back in the DRAM memory.
  3. The PS reads the output image frame from the DRAM and writes it back to the SD Card.
- Live I/O mode enables streaming frames into the platform, processing frames with the xfOpenCV kernel, and streaming out the frames through the appropriate interface. The following steps describe the live I/O mode.
  1. Video capture IPs receive a frame and store it in the DRAM.
  2. The xfOpenCV kernel fetches the image from the DRAM, processes the image, and stores the output in the DRAM.
  3. Display IPs read the output frame from the DRAM and transmits the frame through the appropriate display interface.

Following figure shows the reVISION platform with the xfOpenCV kernel block:

Figure 1: xfOpenCV Kernel on the reVISION Platform



**Note:** For more information on the PS-PL interfaces and PL-DDR interfaces, see the *Zynq UltraScale+ Device Technical Reference Manual* ([UG1085](#)).

# Getting Started

This chapter provides the information you need to bring up your design using the xfOpenCV library functions.

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## Prerequisites

This section lists the prerequisites for using the xfOpenCV library functions on ZCU102 based platforms. The methodology holds true for ZC702 and ZC706 reVISION platforms as well.

- Download and install the SDx development environment according to the directions provided in *SDSoC Environments Release Notes, Installation, and Licensing Guide (UG1294)*. Before launching the SDx development environment on Linux, set the `$SYSROOT` environment variable to point to the Linux root file system, delivered with the reVISION platform. For example:

```
export SYSROOT = <local folder>/zcu102_[es2_]rv_ss/sw/aarch64-linux-gnu/  
sysroot
```

- Download the Zynq<sup>®</sup> UltraScale+<sup>™</sup> MPSoC Embedded Vision Platform zip file and extract its contents. Create the SDx development environment workspace in the `zcu102_[es2_]rv_ss` folder of the extracted design file hierarchy. For more details, see the [reVISION Getting Started Guide](#).
- Set up the ZCU102 evaluation board. For more details, see the [reVISION Getting Started Guide](#).
- Download the xfOpenCV library. This library is made available through github. Run the following `git clone` command to clone the xfOpenCV repository to your local disk:

```
git clone https://github.com/Xilinx/xfopencv.git
```

---

## xfOpenCV Library Contents

The following table lists the contents of the xfOpenCV library.

Table 1: xfOpenCV Library Contents

Folder	Details
<code>include</code>	Contains the header files required by the library.
<code>include/common</code>	Contains the common library infrastructure headers, such as types specific to the library.
<code>include/core</code>	Contains the core library functionality headers, such as the <code>math</code> functions.
<code>include/features</code>	Contains the feature extraction kernel function definitions. For example, <code>Harris</code> .
<code>include/imgproc</code>	Contains all the kernel function definitions, except the ones available in the <code>features</code> folder.
<code>examples</code>	Contains the sample test bench code to facilitate running unit tests. The <code>examples/</code> folder contains the folders with algorithm names. Each algorithm folder contains host files, <code>.json</code> file, and <code>data</code> folder. For more details on how to use the xfOpenCV library, see <a href="#">xfOpenCV Kernel on the reVISION Platform</a> .

## Using the xfOpenCV Library

This section describes using the xfOpenCV library in the SDx development environment.

**Note:** The instructions in this section assume that you have downloaded and installed all the required packages. For more information, see the [Prerequisites](#).

The xfOpenCV library is structured as shown in the following table. The `include` folder constitutes all the necessary components to build a Computer Vision or Image Processing pipeline using the library. The folders `common` and `core` contain the infrastructure that the library functions need for basic functions, `Mat` class, and macros. The library functions are categorized into two folders, `features` and `imgproc` based on the operation they perform. The names of the folders are self-explanatory.

To work with the library functions, you need to include the path to the `include` folder in the SDx project. You can include relevant header files for the library functions you will be working with after you source the `include` folder's path to the compiler. For example, if you would like to work with Harris Corner Detector and Bilateral Filter, you must use the following lines in the host code:

```
#include "features/xf_harris.hpp" //for Harris Corner Detector
#include "imgproc/xf_bilateral_filter.hpp" //for Bilateral Filter
```



After the headers are included, you can work with the library functions as described in the [Chapter 3: xfOpenCV Library API Reference](#) using the examples in the `examples` folder as reference.

The following table gives the name of the header file, including the folder name, which contains the library function.

**Table 2: xfOpenCV Library Contents**

Function Name	File Path in the <code>include</code> folder
<code>xf::accumulate</code>	<code>imgproc/xf_accumulate_image.hpp</code>
<code>xf::accumulateSquare</code>	<code>imgproc/xf_accumulate_squared.hpp</code>
<code>xf::accumulateWeighted</code>	<code>imgproc/xf_accumulate_weighted.hpp</code>
<code>xf::absdiff</code> , <code>xf::add</code> , <code>xf::subtract</code> , <code>xf::bitwise_and</code> , <code>xf::bitwise_or</code> , <code>xf::bitwise_not</code> , <code>xf::bitwise_xor</code>	<code>core/xf_arithm.hpp</code>
<code>xf::bilateralFilter</code>	<code>imgproc/xf_histogram.hpp</code>
<code>xf::boxFilter</code>	<code>imgproc/xf_box_filter.hpp</code>
<code>xf::Canny</code>	<code>imgproc/xf_canny.hpp</code>
<code>xf::merge</code>	<code>imgproc/xf_channel_combine.hpp</code>
<code>xf::extractChannel</code>	<code>imgproc/xf_channel_extract.hpp</code>
<code>xf::convertTo</code>	<code>imgproc/xf_convert_bitdepth.hpp</code>
<code>xf::filter2D</code>	<code>imgproc/xf_custom_convolution.hpp</code>
<code>xf::nv122iyuv</code> , <code>xf::nv122rgba</code> , <code>xf::nv122yuv4</code> , <code>xf::nv212iyuv</code> , <code>xf::nv212rgba</code> , <code>xf::nv212yuv4</code> , <code>xf::rgba2yuv4</code> , <code>xf::rgba2iyuv</code> , <code>xf::rgba2nv12</code> , <code>xf::rgba2nv21</code> , <code>xf::uyvy2iyuv</code> , <code>xf::uyvy2nv12</code> , <code>xf::uyvy2rgba</code> , <code>xf::yuyv2iyuv</code> , <code>xf::yuyv2nv12</code> , <code>xf::yuyv2rgba</code>	<code>imgproc/xf_cvt_color.hpp</code>
<code>xf::dilate</code>	<code>imgproc/xf_dilation.hpp</code>
<code>xf::erode</code>	<code>imgproc/xf_erosion.hpp</code>
<code>xf::fast</code>	<code>features/xf_fast.hpp</code>
<code>xf::GaussianBlur</code>	<code>imgproc/xf_gaussian_filter.hpp</code>
<code>xf::cornerHarris</code>	<code>features/xf_harris.hpp</code>
<code>xf::calcHist</code>	<code>imgproc/xf_histogram.hpp</code>
<code>xf::equalizeHist</code>	<code>imgproc/xf_hist_equalize.hpp</code>
<code>xf::HOGDescriptor</code>	<code>imgproc/xf_hog_descriptor.hpp</code>
<code>xf::Houghlines</code>	<code>imgproc/xf_houghlines.hpp</code>
<code>xf::integralImage</code>	<code>imgproc/xf_integral_image.hpp</code>
<code>xf::densePyrOpticalFlow</code>	<code>imgproc/xf_pyr_dense_optical_flow.hpp</code>
<code>xf::DenseNonPyrOpticalFlow</code>	<code>imgproc/xf_dense_npyr_optical_flow.hpp</code>
<code>xf::LUT</code>	<code>imgproc/xf_lut.hpp</code>
<code>xf::magnitude</code>	<code>core/xf_magnitude.hpp</code>
<code>xf::MeanShift</code>	<code>imgproc/xf_mean_shift.hpp</code>
<code>xf::meanStdDev</code>	<code>core/xf_mean_stddev.hpp</code>
<code>xf::medianBlur</code>	<code>imgproc/xf_median_blur.hpp</code>
<code>xf::minMaxLoc</code>	<code>core/xf_min_max_loc.hpp</code>

Table 2: **xfOpenCV Library Contents** (cont'd)

Function Name	File Path in the <code>include</code> folder
xf::OtsuThreshold	imgproc/xf_otsuthreshold.hpp
xf::phase	core/xf_phase.hpp
xf::pyrDown	imgproc/xf_pyr_down.hpp
xf::pyrUp	imgproc/xf_pyr_up.hpp
xf::remap	imgproc/xf_remap.hpp
xf::resize	imgproc/xf_resize.hpp
xf::Scharr	imgproc/xf_scharr.hpp
xf::SemiGlobalBM	imgproc/xf_sgbm.hpp
xf::Sobel	imgproc/xf_sobel.hpp
xf::StereoPipeline	imgproc/xf_stereo_pipeline.hpp
xf::StereoBM	imgproc/xf_stereoBM.hpp
xf::SVM	imgproc/xf_svm.hpp
xf::Threshold	imgproc/xf_threshold.hpp
xf::warpAffine	imgproc/xf_warpaffine.hpp
xf::warpPerspective	imgproc/xf_warpperspective.hpp
xf::warpTransform	imgproc/xf_warp_transform.hpp

The different ways to use the xfOpenCV library examples are listed below:

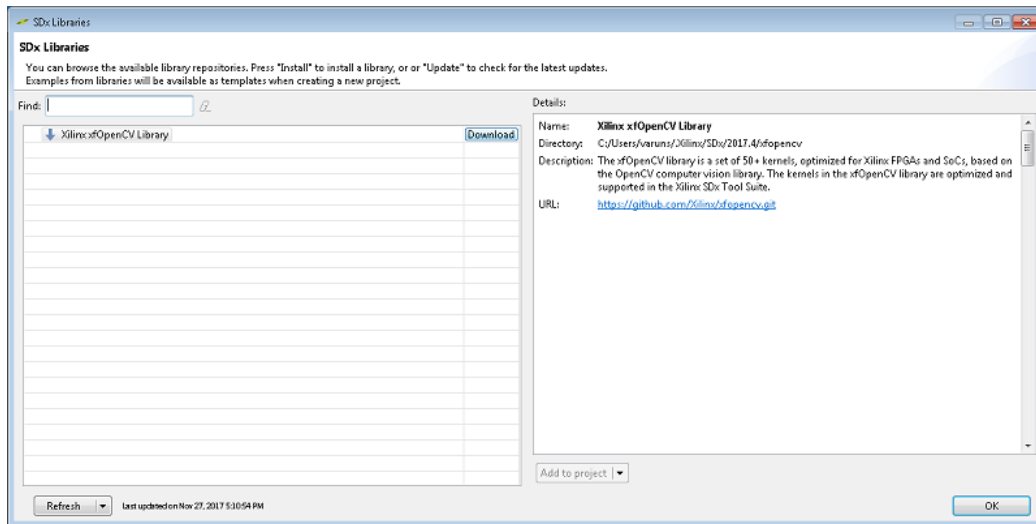
- [Downloading and Using xfOpenCV Libraries from SDx GUI](#)
- [Building a Project Using the Example Makefiles on Linux](#)
- [Using reVISION Samples on the reVISION Platform](#)
- [Using the xfOpenCV Library on a non-reVISION Platform](#)

## Downloading and Using xfOpenCV Libraries from SDx GUI

You can download xfOpenCV directly from SDx GUI. To build a project using the example makefiles on the Linux platform:

1. From SDx IDE, click **Xilinx** and select **SDx Libraries**.
2. Click **Download** next to the **Xilinx xfOpenCV Library**.

Figure 2: SDx Libraries



The library is downloaded into `<home directory>/Xilinx/SDx/2018.2/xfopencv`. After the library is downloaded, the entire set of examples in the library are available in the list of templates while creating a new project.

**Note:** The library can be added to any project from the IDE menu options.

3. To add a library to a project, from SDx IDE, click **Xilinx** and select **SDx Libraries**.
4. Select **Xilinx xfOpenCV Library** and click **Add to project**. The dropdown menu consists of options of which project the libraries need to be included to.

All the headers as part of the `include/` folder in xfOpenCV library would be copied into the local project directory as `<project_dir>/libs/xfopencv/include`. All the settings required for the libraries to be run are also set when this action is completed.

## Building a Project Using the Example Makefiles on Linux

Use the following steps to build a project using the example makefiles on the Linux platform:

1. Open a terminal.
2. Set the environment variable `SYSROOT` to the `<path to sysroot folder>/sw/aarch64-linux-gnu/sysroot` folder.
3. Change the platform variable to point to the downloaded platform folder in makefile. Ensure that the folder name of the downloaded platform is unchanged.
4. Change the directory to the location where you want to build the example.

```
cd <path to example>
```

5. Set the environment variables to run SDx development environment.

- For c shell:

```
source <SDx tools install path>/settings.csh
```

- For bash shell:

```
source <SDx tools install path>/settings.sh
```

6. Type the `make` command in the terminal. The `sd_card` folder is created and can be found in the `<path to example>` folder.

## Using reVISION Samples on the reVISION Platform

Use the following steps to run a unit test for bilateral filter on `zcu102_es2_reVISION`:

1. Launch the SDx development environment using the desktop icon or the **Start** menu.

The **Workspace Launcher** dialog appears.

2. Click **Browse** to enter a workspace folder used to store your projects (you can use workspace folders to organize your work), then click **OK** to dismiss the **Workspace Launcher** dialog.

**Note:** Before launching the SDx IDE on Linux, ensure that you use the same shell that you have used to set the `$SYSROOT` environment variable. This is usually the file path to the Linux root file system.

The SDx development environment window opens with the **Welcome** tab visible when you create a new workspace. The **Welcome** tab can be closed by clicking the **X** icon or minimized if you do not wish to use it.

3. Select **File** → **New** → **Xilinx SDx Project** from the SDx development environment menu bar.

The **New Project** dialog box opens.

4. Specify the name of the project. For example **Bilateral**.

5. Click **Next**.

The **Choose Hardware Platform** page appears.

6. From the **Choose Hardware Platform** page, click the **Add Custom Platform** button.

7. Browse to the directory where you extracted the reVISION platform files. Ensure that you select the `zcu102_es2_reVISION` folder.

8. From the **Choose Hardware Platform** page, select **zcu102\_es2\_reVISION (custom)**.

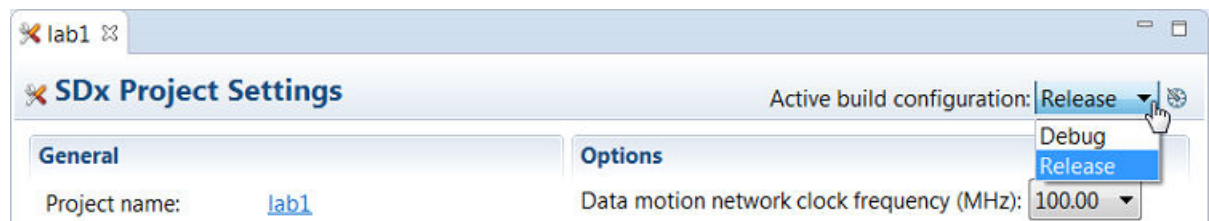
9. Click **Next**.

The **Templates** page appears, containing source code examples for the selected platform.

10. From the list of application templates, select **bilateral - File I/O** and click **Finish**.
11. Click the **Active build configurations** drop-down from the **SDx Project Settings** window, to select the active configuration or create a build configuration.

The standard build configurations are Debug and Release. To get the best runtime performance, switch to use the **Release** build configuration as it uses a higher compiler optimization setting than the Debug build configuration.

Figure 3: **SDx Project Settings - Active Build Configuration**



12. Set the **Data motion network clock frequency (MHz)** to the required frequency, on the **SDx Project Settings** page.
13. Right-click the project and select **Build Project** or press Ctrl+B keys to build the project, in the **Project Explorer** view.
14. Copy the contents of the newly created `sd_card` folder to the SD card.

The `sd_card` folder contains all the files required to run designs on the ZCU102 board.

15. Insert the SD card in the ZCU102 board card slot and switch it ON.

**Note:** A serial port emulator (Teraterm/ minicom) is required to interface the user commands to the board.

16. Upon successful boot, run the following command in the Teraterm terminal (serial port emulator.)

```
#cd /media/card
#remount
```

17. Run the `.elf` file for the respective functions.

For more information, see the [Using the xfOpenCV Library Functions on Hardware](#).

## Using the xfOpenCV Library on a non-reVISION Platform

This section describes using the xfOpenCV library on a non-reVISION platform, in the SDx development environment. The examples in xfOpenCV require OpenCV libraries for successful compilation. In the case of a non-reVISION platform, you are responsible for providing the required OpenCV libraries, either as part of the platform or otherwise.

**Note:** The instructions in this section assume that you have downloaded and installed all the required packages. For more information, see the [Prerequisites](#).

Use the following steps to import the xfOpenCV library into a SDx project and execute it on a custom platform:

1. Launch the SDx development environment using the desktop icon or the **Start** menu.

The **Workspace Launcher** dialog appears.

2. Click **Browse** to enter a workspace folder used to store your projects (you can use workspace folders to organize your work), then click **OK** to dismiss the **Workspace Launcher** dialog.

**Note:** Before launching the SDx IDE on Linux, ensure that you use the same shell that you have used to set the \$SYSROOT environment variable. This is usually the file path to the Linux root file system.

The SDx development environment window opens with the **Welcome** tab visible when you create a new workspace. The **Welcome** tab can be closed by clicking the **X** icon or minimized if you do not wish to use it.

3. Select **File** → **New** → **Xilinx SDx Project** from the SDx development environment menu bar.

The **New Project** dialog box opens.

4. Specify the name of the project. For example **Test**.
5. Click **Next**.

The **Choose Hardware Platform** page appears.

6. From the **Choose Hardware Platform** page, select a suitable platform. For example, **zcu102**.
7. Click **Next**.

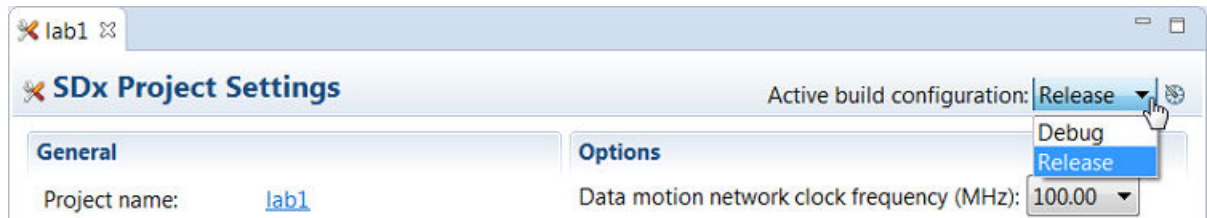
The **Choose Software Platform and Target CPU** page appears.

8. From the **Choose Software Platform and Target CPU** page, select an appropriate software platform and the target CPU. For example, select **A9** from the **CPU** dropdown list for ZC702 and ZC706 reVISION platforms.
9. Click **Next**. The **Templates** page appears, containing source code examples for the selected platform.
10. From the list of application templates, select **Empty Application** and click **Finish**.

The **New Project** dialog box closes. A new project with the specified configuration is created. The **SDx Project Settings** view appears. Notice the progress bar in the lower right border of the view, Wait for a few moments for the **C/C++ Indexer** to finish.


11. The standard build configurations are Debug and Release. To get the best run-time performance, switch to use the **Release** build configuration as it uses a higher compiler optimization setting than the Debug build configuration.

Figure 4: SDx Project Settings - Active Build Configuration



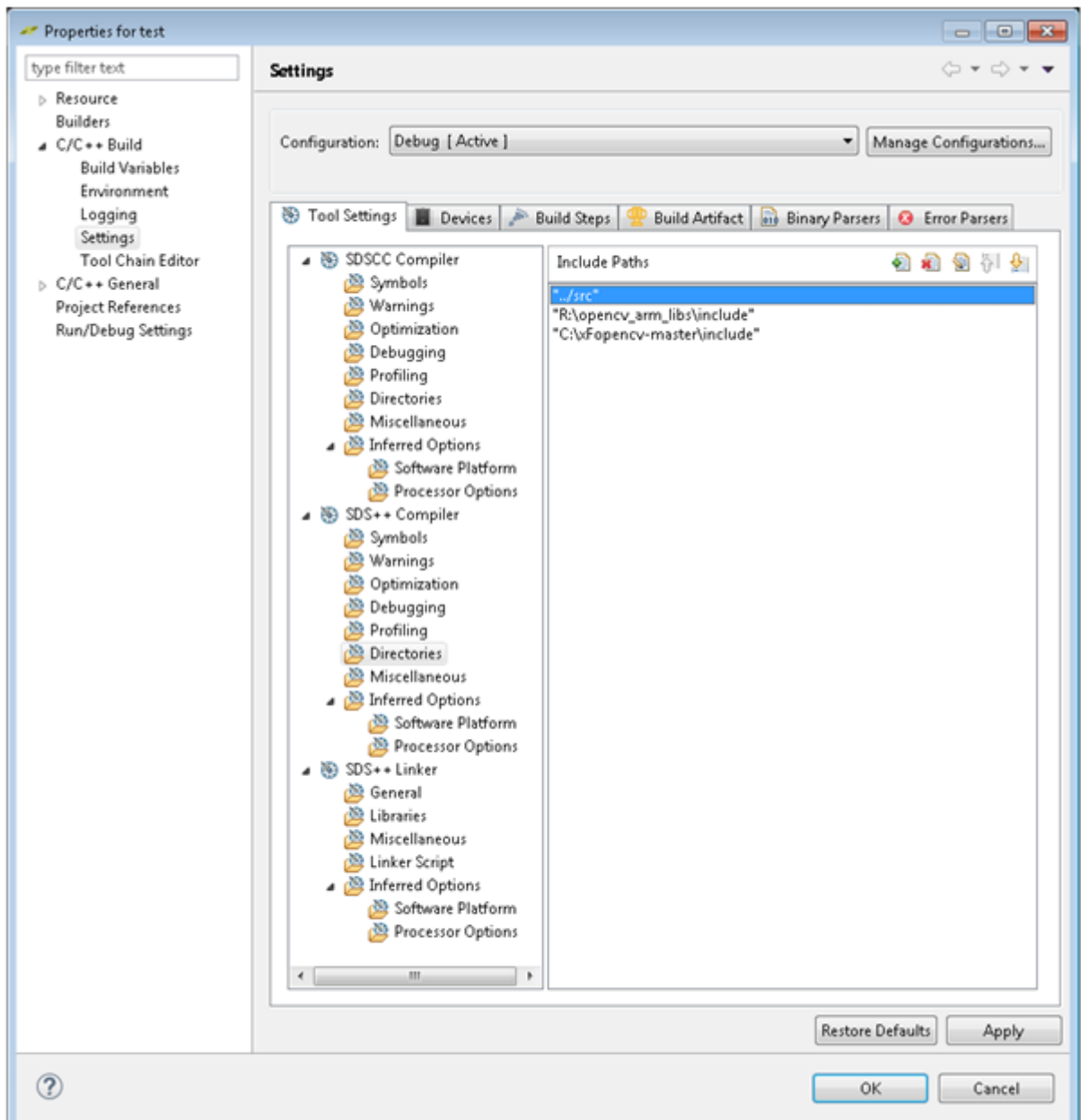
12. Set the **Data motion network clock frequency (MHz)** to the required frequency, on the **SDx Project Settings** page.
13. Select the **Generate bitstream** and **Generate SD card image** check boxes.
14. Right-click on the newly created project in the **Project Explorer** view.
15. From the context menu that appears, select **C/C++ Build Settings**.

The **Properties for <project>** dialog box appears.

16. Click the **Tool Settings** tab.
17. Expand the **SDS++ Compiler → Directories** tree.
18. Click the  icon to add the “<xfopencv\_location>\include and “<OpenCV\_location>\include folder locations to the **Include Paths** list.


**Note:** The OpenCV library is not provided by Xilinx for custom platforms. You are required to provide the library. Use the reVISION platform in order to use the OpenCV library provided by Xilinx.

Figure 5: SDS++ Compiler Settings



19. Click **Apply**.


20. Expand the **SDS++ Linker** → **Libraries** tree.

21. Click the  icon and add the following libraries to the **Libraries(-l)** list. These libraries are required by OpenCV.

- opencv\_core
- opencv\_imgproc

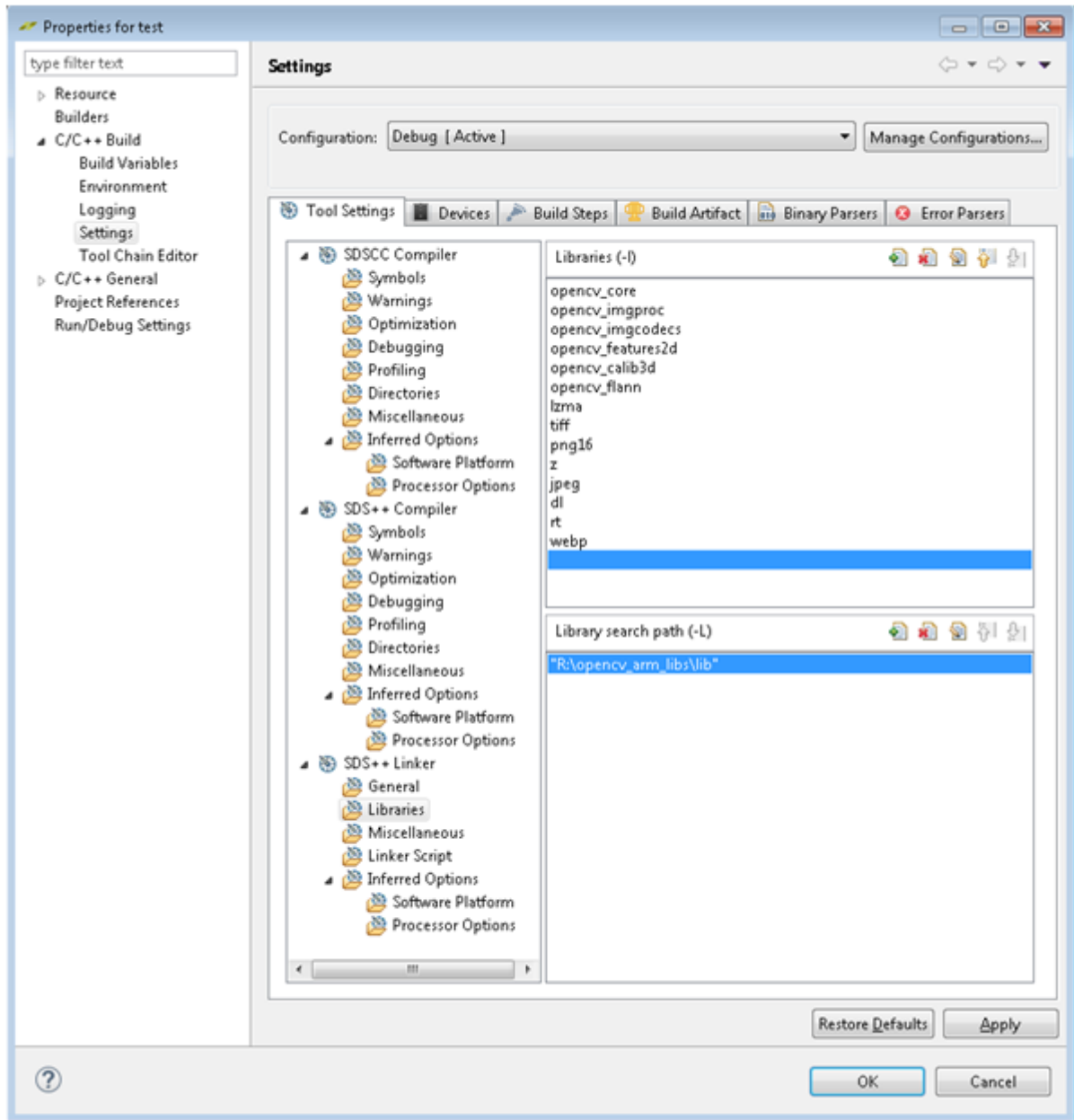


- opencv\_imgcodecs
- opencv\_features2d
- opencv\_calib3d
- opencv\_flann
- lzma
- tiff
- png16
- z
- jpeg
- dl
- rt
- webp

22. Click the  icon and add `<opencv_Location>/lib` folder location to the **Libraries search path (-L)** list.

**Note:** The OpenCV library is not provided by Xilinx for custom platforms. You are required to provide the library. Use the reVISION platform in order to use the OpenCV library provided by Xilinx.

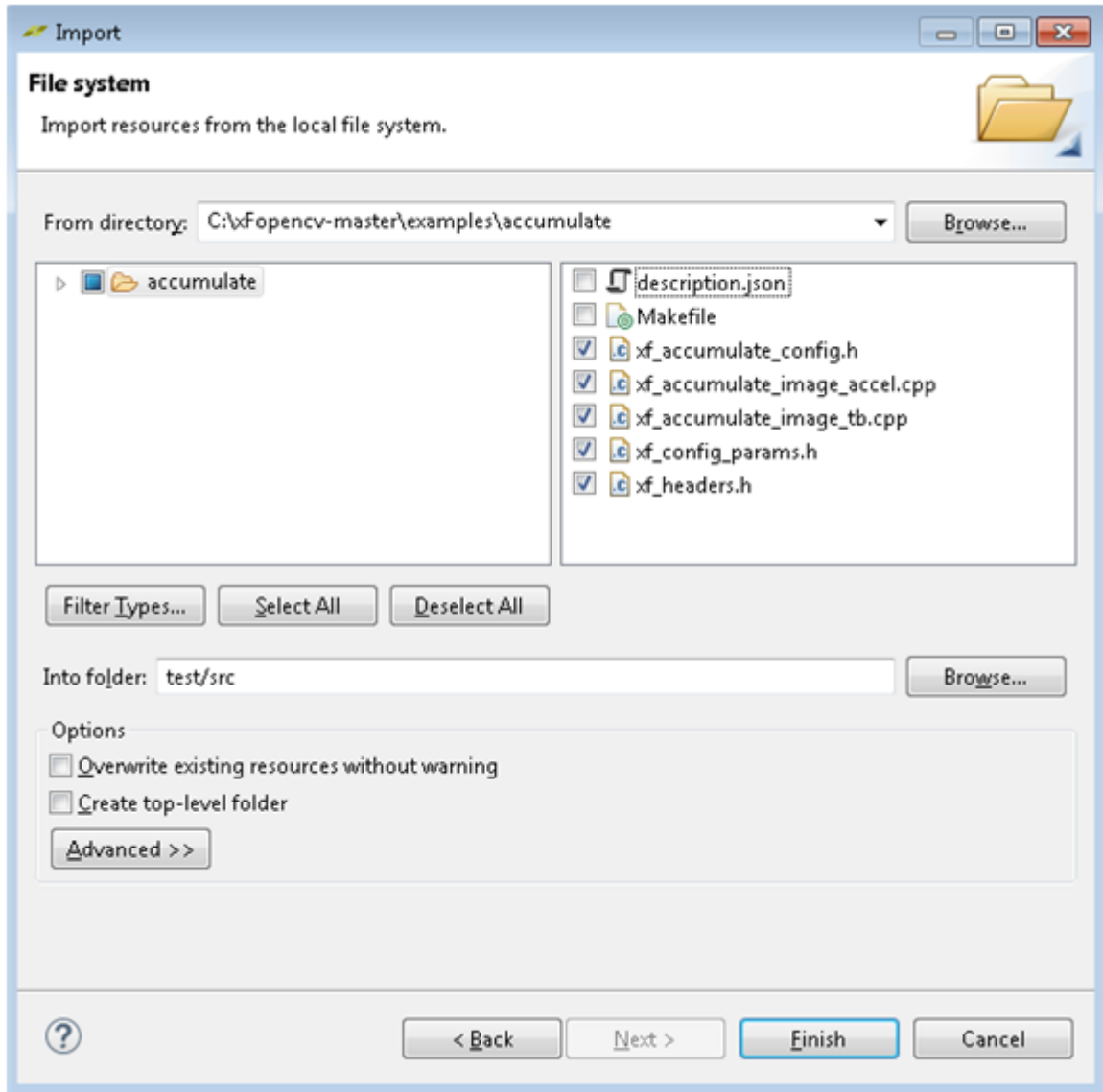
Figure 6: SDS++ Linker Settings



23. Click **Apply** to save the configuration.
24. Click **OK** to close the **Properties for <project>** dialog box.
25. Expand the newly created project tree in the **Project Explorer** view.
26. Right-click the **src** folder and select **Import**. The **Import** dialog box appears.
27. Select **File System** and click **Next**.
28. Click **Browse** to navigate to the `<xfoopencv_Location>/examples` folder location.

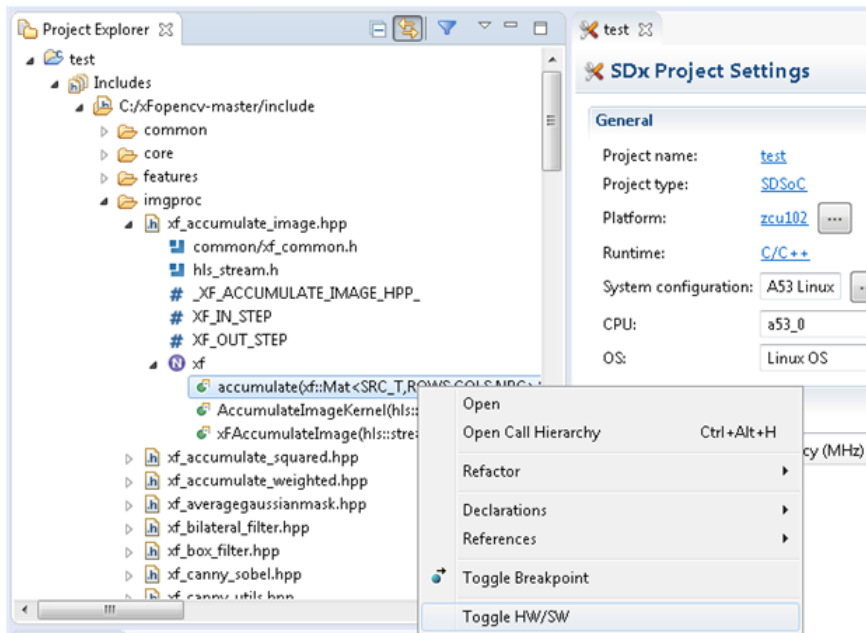
29. Select the folder that corresponds to the library that you desire to import. For example, `accumulate`.

Figure 7: **Import Library Example Source Files**



30. Right-click the library function in the **Project Explorer** view and select **Toggle HW/SW** to move the function to the hardware.

Figure 8: Moving a Library Function to the Hardware



31. Right-click the project and select **Build Project** or press Ctrl+B keys to build the project, in the **Project Explorer** view.

The build process may take anytime between few minutes to several hours, depending on the power of the host machine and the complexity of the design. By far, the most time is spent processing the routines that have been tagged for realization in hardware.

32. Copy the contents of the newly created `.\<workspace>\<function>\Release\sd_card` folder to the SD card. The `sd_card` folder contains all the files required to run designs on a board.
33. Insert the SD card in the board card slot and switch it ON.

**Note:** A serial port emulator (Teraterm/ minicom) is required to interface the user commands to the board.

34. Upon successful boot, navigate to the `./mnt` folder and run the following command at the prompt:

```
#cd /mnt
```

**Note:** It is assumed that the OpenCV libraries are a part of the root filesystem. If not, add the location of OpenCV libraries to `LD_LIBRARY_PATH` using the `$ export LD_LIBRARY_PATH=<location of OpenCV libraries>/lib` command.

35. Run the `.elf` executable file. For more information, see the [Using the xfOpenCV Library Functions on Hardware](#).

## Changing the Hardware Kernel Configuration

Use the following steps to change the hardware kernel configuration:

1. Update the `<path to xfOpenCV git folder>/xfOpenCV/examples/<function>/xf_config_params.h` file.
2. Update the makefile along with the `xf_config_params.h` file:
  - a. Find the line with the function name in the makefile. For bilateral filter, the line in the makefile will be `xf::BilateralFilter<3,1,0,1080,1920,1>`.
  - b. Update the template parameters in the makefile to reflect changes made in the `xf_config_params.h` file. For more details, see the [Chapter 3: xfOpenCV Library API Reference](#).

## Using the xfOpenCV Library Functions on Hardware

The following table lists the xfOpenCV library functions and the command to run the respective examples on hardware. It is assumed that your design is completely built and the board has booted up correctly.

*Table 3: Using the xfOpenCV Library Function on Hardware*

Example	Function Name	Usage on Hardware
accumulate	xf::accumulate	<code>./&lt;executable name&gt;.elf &lt;path to input image 1&gt; &lt;path to input image 2&gt;</code>
accumulatesquared	xf::accumulateSquare	<code>./&lt;executable name&gt;.elf &lt;path to input image 1&gt; &lt;path to input image 2&gt;</code>
accumulateweighted	xf::accumulateWeighted	<code>./&lt;executable name&gt;.elf &lt;path to input image 1&gt; &lt;path to input image 2&gt;</code>
arithm	xf::absdiff, xf::add, xf::subtract, xf::bitwise_and, xf::bitwise_or, xf::bitwise_not, xf::bitwise_xor	<code>./&lt;executable name&gt;.elf &lt;path to input image 1&gt; &lt;path to input image 2&gt;</code>
Bilateralfilter	xf::bilateralFilter	<code>./&lt;executable name&gt;.elf &lt;path to input image&gt;</code>
Boxfilter	xf::boxFilter	<code>./&lt;executable name&gt;.elf &lt;path to input image&gt;</code>
Canny	xf::Canny	<code>./&lt;executable name&gt;.elf &lt;path to input image&gt;</code>
channelcombine	xf::merge	<code>./&lt;executable name&gt;.elf &lt;path to input image 1&gt; &lt;path to input image 2&gt; &lt;path to input image 3&gt; &lt;path to input image 4&gt;</code>

Table 3: Using the xfOpenCV Library Function on Hardware (cont'd)

Example	Function Name	Usage on Hardware
Channelextract	xf::extractChannel	./<executable name>.elf <path to input image>
Colordetect	xf::RGB2HSV, xf::colorthresholding, xf:: erode, and xf:: dilate	./<executable name>.elf <path to input image>
Convertbitdepth	xf::convertTo	./<executable name>.elf <path to input image>
Cornertracker	xf::cornerTracker	./exe <input video> <no. of frames> <Harris Threshold> <No. of frames after which Harris Corners are Reset>
Customconv	xf::filter2D	./<executable name>.elf <path to input image>
cvtcolor IYUV2NV12	xf::iyuv2nv12	./<executable name>.elf <path to input image 1> <path to input image 2> <path to input image 3>
cvtcolor IYUV2RGBA	xf::iyuv2rgba	./<executable name>.elf <path to input image 1> <path to input image 2> <path to input image 3>
cvtcolor IYUV2YUV4	xf::iyuv2yuv4	./<executable name>.elf <path to input image 1> <path to input image 2> <path to input image 3> <path to input image 4> <path to input image 5> <path to input image 6>
cvtcolor NV122IYUV	xf::nv122iyuv	./<executable name>.elf <path to input image 1> <path to input image 2>
cvtcolor NV122RGBA	xf::nv122rgba	./<executable name>.elf <path to input image 1> <path to input image 2>
cvtcolor NV122YUV4	xf::nv122yuv4	./<executable name>.elf <path to input image 1> <path to input image 2>
cvtcolor NV212IYUV	xf::nv212iyuv	./<executable name>.elf <path to input image 1> <path to input image 2>
cvtcolor NV212RGBA	xf::nv212rgba	./<executable name>.elf <path to input image 1> <path to input image 2>
cvtcolor NV212YUV4	xf::nv212yuv4	./<executable name>.elf <path to input image 1> <path to input image 2>
cvtcolor RGBA2YUV4	xf::rgba2yuv4	./<executable name>.elf <path to input image>
cvtcolor RGBA2IYUV	xf::rgba2iyuv	./<executable name>.elf <path to input image>
cvtcolor RGBA2NV12	xf::rgba2nv12	./<executable name>.elf <path to input image>
cvtcolor RGBA2NV21	xf::rgba2nv21	./<executable name>.elf <path to input image>
cvtcolor UYVY2IYUV	xf::uyvy2iyuv	./<executable name>.elf <path to input image>
cvtcolor UYVY2NV12	xf::uyvy2nv12	./<executable name>.elf <path to input image>
cvtcolor UYVY2RGBA	xf::uyvy2rgba	./<executable name>.elf <path to input image>
cvtcolor YUYV2IYUV	xf::yuyv2iyuv	./<executable name>.elf <path to input image>

Table 3: Using the xfOpenCV Library Function on Hardware (cont'd)

Example	Function Name	Usage on Hardware
cvtColor YUYV2NV12	xf::yuyv2nv12	./<executable name>.elf <path to input image>
cvtColor YUYV2RGBA	xf::yuyv2rgba	./<executable name>.elf <path to input image>
Difference of Gaussian	xf:: GaussianBlur, xf:: duplicateMat, xf:: delayMat, and xf::subtract	./<exe-name>.elf <path to input image>
Dilation	xf::dilate	./<executable name>.elf <path to input image>
Erosion	xf::erode	./<executable name>.elf <path to input image>
Fast	xf::fast	./<executable name>.elf <path to input image>
Gaussianfilter	xf::GaussianBlur	./<executable name>.elf <path to input image>
Harris	xf::cornerHarris	./<executable name>.elf <path to input image>
Histogram	xf::calcHist	./<executable name>.elf <path to input image>
Histequalize	xf::equalizeHist	./<executable name>.elf <path to input image>
Hog	xf::HOGDescriptor	./<executable name>.elf <path to input image>
Houghlines	xf::HoughLines	./<executable name>.elf <path to input image>
Integralimg	xf::integralImage	./<executable name>.elf <path to input image>
Lkdensepyrof	xf::densePyrOpticalFlow	./<executable name>.elf <path to input image 1> <path to input image 2>
Lknpyroflow	xf::DenseNonPyrLKOpticalFlow	./<executable name>.elf <path to input image 1> <path to input image 2>
Lut	xf::LUT	./<executable name>.elf <path to input image>
Magnitude	xf::magnitude	./<executable name>.elf <path to input image>
meanshifttracking	xf::MeanShift	./<executable name>.elf <path to input video/input image files> <Number of objects to track>
meanstddev	xf::meanStdDev	./<executable name>.elf <path to input image>
medianblur	xf::medianBlur	./<executable name>.elf <path to input image>
Minmaxloc	xf::minMaxLoc	./<executable name>.elf <path to input image>
otsuthreshold	xf::OtsuThreshold	./<executable name>.elf <path to input image>
Phase	xf::phase	./<executable name>.elf <path to input image>
Pyrdown	xf::pyrDown	./<executable name>.elf <path to input image>

Table 3: Using the xfOpenCV Library Function on Hardware (cont'd)

Example	Function Name	Usage on Hardware
Pyramid	xf::pyrUp	./<executable name>.elf <path to input image>
remap	xf::remap	./<executable name>.elf <path to input image> <path to mapx data> <path to mapy data>
Resize	xf::resize	./<executable name>.elf <path to input image>
scharrfilter	xf::Scharr	./<executable name>.elf <path to input image>
SemiGlobalBM	xf::SemiGlobalBM	./<executable name>.elf <path to left image> <path to right image>
sobelfilter	xf::Sobel	./<executable name>.elf <path to input image>
stereopipeline	xf::StereoPipeline	./<executable name>.elf <path to left image> <path to right image>
stereolbm	xf::StereoBM	./<executable name>.elf <path to left image> <path to right image>
Svm	xf::SVM	./<executable name>.elf
threshold	xf::Threshold	./<executable name>.elf <path to input image>
warpaffine	xf::warpAffine	./<executable name>.elf <path to input image>
warpperspective	xf::warpPerspective	./<executable name>.elf <path to input image>
warptransform	xf::warpTransform	./<executable name>.elf <path to input image>



# xfOpenCV Library API Reference

To facilitate local memory allocation on FPGA devices, the xfOpenCV library functions are provided in templates with compile-time parameters. Data is explicitly copied from `cv::Mat` to `xf::Mat` and is stored in physically contiguous memory to achieve the best possible performance. After processing, the output in `xf::Mat` is copied back to `cv::Mat` to write it into the memory.

---

## xf::Mat Image Container Class

`xf::Mat` is a template class that serves as a container for storing image data and its attributes.

**Note:** The `xf::Mat` image container class is similar to the `cv::Mat` class of the OpenCV library.

### Class Definition

```
template<int TYPE, int ROWS, int COLS, int NPC>
class Mat {
public:
    Mat(); // default constructor
    Mat(int _rows, int _cols);
    Mat(int _rows, int _cols, void *_data);
    Mat(int _size, int _rows, int _cols);
    ~Mat();
    void init(int _rows, int _cols);
    void copyTo(XF_PTSNAME(T,NPC)* fromData);
    unsigned char * copyFrom();
    Mat(const Mat& src);
    Mat& operator=(const Mat& src);
    template<int DST_T>
    void convertTo(Mat<DST_T,ROWS, COLS, NPC> &dst, int otype, double
alpha=1, double beta=0);
    int rows, cols, size; // actual image size
#ifdef __SYNTHESIS__
    XF_TNAME(T,NPC)*data;
#else
    XF_TNAME(T,NPC) data[ROWS*(COLS>> (XF_BITSHIFT(NPC)))]];
#endif
};
```

### Parameter Descriptions

The following table lists the `xf::Mat` class parameters and their descriptions:

Table 4: **xf::Mat Class Parameter Descriptions**

Parameter	Description
rows	The number of rows in the image or height of the image.
cols	The number of columns in the image or width of the image.
size	The number of words stored in the data member. The value is calculated using <code>rows*cols / (number of pixels packed per word)</code> .
*data	The pointer to the words that store the pixels of the image.

## Member Functions Description

The following table lists the member functions and their descriptions:

 Table 5: **xf::Mat Member Function Descriptions**

Member Functions	Description
Mat()	This default constructor initializes the Mat object sizes, using the template parameters ROWS and COLS.
Mat(int _rows, int _cols)	This constructor initializes the Mat object using arguments _rows and _cols.
Mat(const xf::Mat &_src)	This constructor helps clone a Mat object to another. New memory will be allocated for the newly created constructor.
Mat(int _rows, int _cols, void *_data)	This constructor initializes the Mat object using arguments _rows, _cols, and _data. The *data member of the Mat object points to the memory allocated for _data argument, when this constructor is used. No new memory is allocated for the *data member.
convertTo(Mat<DST_T,ROWS, COLS, NPC> &dst, int otype, double alpha=1, double beta=0)	Refer to <a href="#">xf::convertTo</a>
copyTo(* fromData)	Copies the data from Data pointer into physically contiguous memory allocated inside the constructor.
copyFrom()	Returns the pointer to the first location of the *data member.
~Mat()	This is a default destructor of the Mat object.

## Template Parameter Descriptions

Template parameters of the `xf::Mat` class are used to set the depth of the pixel, number of channels in the image, number of pixels packed per word, maximum number of rows and columns of the image. The following table lists the template parameters and their descriptions:

 Table 6: **xf::Mat Template Parameter Descriptions**

Parameters	Description
TYPE	Type of the pixel data. For example, XF_8UC1 stands for 8-bit unsigned and one channel pixel. More types can be found in <code>include/common/xf_params.h</code> .
HEIGHT	Maximum height of an image.
WIDTH	Maximum width of an image.
NPC	The number of pixels to be packed per word. For instance, XF_NPPC1 for 1 pixel per word; and XF_NPPC8 for 8 pixels per word.

## Pixel-Level Parallelism

The amount of parallelism to be implemented in a function from xfOpenCV is kept as a configurable parameter. In most functions, there are two options for processing data.

- Single-pixel processing
- Processing eight pixels in parallel

The following table describes the options available for specifying the level of parallelism required in a particular function:

**Table 7: Options Available for Specifying the Level of Parallelism**

Option	Description
XF_NPPC1	Process 1 pixel per clock cycle
XF_NPPC2	Process 2 pixels per clock cycle
XF_NPPC8	Process 8 pixels per clock cycle

## Macros to Work With Parallelism

There are two macros that are defined to work with parallelism.

- The `XF_NPIXPERCYCLE(flags)` macro resolves to the number of pixels processed per cycle.
  - `XF_NPIXPERCYCLE(XF_NPPC1)` resolves to 1
  - `XF_NPIXPERCYCLE(XF_NPPC2)` resolves to 2
  - `XF_NPIXPERCYCLE(XF_NPPC8)` resolves to 8
- The `XF_BITSHIFT(flags)` macro resolves to the number of times to shift the image size to right to arrive at the final data transfer size for parallel processing.
  - `XF_BITSHIFT(XF_NPPC1)` resolves to 0
  - `XF_BITSHIFT(XF_NPPC2)` resolves to 1
  - `XF_BITSHIFT(XF_NPPC8)` resolves to 3

## Pixel Types

Parameter types will differ, depending on the combination of the depth of pixels and the number of channels in the image. The generic nomenclature of the parameter is listed below.

```
XF_<Number of bits per pixel><signed (S) or unsigned (U) or float (F)>C<number of channels>
```

For example, for an 8-bit pixel - unsigned - 1 channel the data type is `XF_8UC1`.

The following table lists the available data types for the `xf::Mat` class:

**Table 8: xf::Mat Class - Available Data Types**

Option	Number of bits per Pixel	Unsigned/ Signed/ Float Type	Number of Channels
XF_8UC1	8	Unsigned	1
XF_16UC1	16	Unsigned	1
XF_16SC1	16	Signed	1
XF_32UC1	32	Unsigned	1
XF_32FC1	32	Float	1
XF_32SC1	32	Signed	1
XF_8UC2	8	Unsigned	2
XF_8UC4	8	Unsigned	4
XF_2UC1	2	Unsigned	1

## Manipulating Data Type

Based on the number of pixels to process per clock cycle and the type parameter, there are different possible data types. The xfOpenCV library uses these datatypes for internal processing and inside the `xf::Mat` class. The following are a few supported types:

- `XF_TNAME(TYPE, NPPC)` resolves to the data type of the data member of the `xf::Mat` object. For instance, `XF_TNAME(XF_8UC1, XF_NPPC8)` resolves to `ap_uint<64>`.
- `Word width = pixel depth * number of channels * number of pixels to process per cycle (NPPC)`.
- `XF_DTUNAME(TYPE, NPPC)` resolves to the data type of the pixel. For instance, `XF_DTUNAME(XF_32FC1, XF_NPPC1)` resolves to `float`.
- `XF_PTSNAME(TYPE, NPPC)` resolves to the 'C' data type of the pixel. For instance, `XF_PTSNAME(XF_16UC1, XF_NPPC2)` resolves to `unsigned short`.

**Note:** `ap_uint<>`, `ap_int<>`, `ap_fixed<>`, and `ap_ufixed<>` types belong to the high-level synthesis (HLS) library. For more information, see the *Vivado Design Suite User Guide: High-Level Synthesis (UG902)*.

## Sample Illustration

The following code illustrates the configurations that are required to build the gaussian filter on an image, using SDSoC tool for Zynq® UltraScale™ platform.

**Note:** In case of a real-time application, where the video is streamed in, it is recommended that the location of frame buffer is `xf::Mat` and is processed using the library function. The resultant location pointer is passed to display IPs.

xf\_config\_params.h

```
#define FILTER_SIZE_3 1
#define FILTER_SIZE_5 0
#define FILTER_SIZE_7 0
#define RO 0
#define NO 1

#if NO
#define NPC1 XF_NPPC1
#endif
#if RO
#define NPC1 XF_NPPC8
#endif
```

xf\_gaussian\_filter\_tb.cpp

```
int main(int argc, char **argv)
{
    cv::Mat in_img, out_img, ocv_ref;
    cv::Mat in_gray, in_gray1, diff;
    in_img = cv::imread(argv[1], 1); // reading in the color image
        extractChannel(in_img, in_gray, 1);

    xf::Mat<XF_8UC1, HEIGHT, WIDTH, NPC1> imgInput(in_img.rows, in_img.cols);
    xf::Mat<XF_8UC1, HEIGHT, WIDTH, NPC1> imgOutput(in_img.rows, in_img.cols);

    imgInput.copyTo(in_gray.data);

    gaussian_filter_accel(imgInput, imgOutput, sigma);

    // Write output image
    xf::imwrite("hls_out.jpg", imgOutput);
}
```

xf\_gaussian\_filter\_accel.cpp

```
#include "xf_gaussian_filter_config.h"

void gaussian_filter_accel(xf::Mat<XF_8UC1, HEIGHT, WIDTH, NPC1>
    &imgInput, xf::Mat<XF_8UC1, HEIGHT, WIDTH, NPC1> &imgOutput, float sigma)
{
    xf::GaussianBlur<FILTER_WIDTH, XF_BORDER_CONSTANT, XF_8UC1, HEIGHT,
    WIDTH, NPC1>(imgInput, imgOutput, sigma);
}
```

xf\_gaussian\_filter.hpp

```
#pragma SDS data data_mover("_src.data":AXIDMA_SIMPLE)
    #pragma SDS data data_mover("_dst.data":AXIDMA_SIMPLE)
    #pragma SDS data access_pattern("_src.data":SEQUENTIAL)
    #pragma SDS data copy("_src.data"[0:"_src.size"])
    #pragma SDS data access_pattern("_dst.data":SEQUENTIAL)
    #pragma SDS data copy("_dst.data"[0:"_dst.size"])

    template<int FILTER_SIZE, int BORDER_TYPE, int SRC_T, int ROWS,
    int COLS, int NPC = 1>
```

```

void GaussianBlur(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src,
xf::Mat<SRC_T, ROWS, COLS, NPC> & _dst, float sigma)
{
    //function body
}
    
```

The design fetches data from external memory (with the help of SDSoC data movers) and is transferred to the function in 8-bit or 64-bit packets, based on the configured mode. Assuming 8-bits per pixel, 8 pixels can be packed into 64-bits. Therefore, 8 pixels are available to be processed in parallel.

Enable the `FILTER_SIZE_3` and the `NO` macros in the `xf_config_params.h` file. The macro is used to set the filter size to 3x3 and `#define NO 1` macro enables 1 pixel parallelism.

Specify the SDSoC tool specific pragmas, in the `xf_gaussian_filter.hpp` file.

```

#pragma SDS data data_mover("_src.data":AXIDMA_SIMPLE)
#pragma SDS data data_mover("_dst.data":AXIDMA_SIMPLE)
#pragma SDS data access_pattern("_src.data":SEQUENTIAL)
#pragma SDS data copy("_src.data"[0:"_src.size"])
#pragma SDS data access_pattern("_dst.data":SEQUENTIAL)
#pragma SDS data copy("_dst.data"[0:"_dst.size"])
    
```

**Note:** For more information on the pragmas used for hardware accelerator functions in SDSoC, see *SDSoC Environment User Guide* ([UG1027](#)).

## Additional Utility Functions for Software

### *xf::imread*

The function `xf::imread` loads an image from the specified file path, copies into `xf::Mat` and returns it. If the image cannot be read (because of missing file, improper permissions, unsupported or invalid format), the function exits with a non-zero return code and an error statement.

**Note:** In an HLS standalone mode like Cosim, use `cv::imread` followed by `copyTo` function, instead of `xf::imread`.

### API Syntax

```

template<int PTYPE, int ROWS, int COLS, int NPC>
xf::Mat<PTYPE, ROWS, COLS, NPC> imread(char *filename, int type)
    
```

### Parameter Descriptions

The table below describes the template and the function parameters.

Table 9: **xf::imread** Function Parameter Descriptions

Parameter	Description
PTYPE	Input pixel type. Value should be in accordance with the 'type' argument's value.
ROWS	Maximum height of the image to be read
COLS	Maximum width of the image to be read
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
filename	Name of the file to be loaded
type	Flag that depicts the type of image. The values are: <ul style="list-style-type: none"> <li>'0' for gray scale</li> <li>'1' for color image</li> </ul>

### ***xf::imwrite***

The function `xf::imwrite` saves the image to the specified file from the given `xf::Mat`. The image format is chosen based on the file name extension. This function internally uses `cv::imwrite` for the processing. Therefore, all the limitations of `cv::imwrite` are also applicable to `xf::imwrite`.

#### **API Syntax**

```
template <int PTYPE, int ROWS, int COLS, int NPC>
void imwrite(const char *img_name, xf::Mat<PTYPE, ROWS, COLS, NPC> &img)
```

#### **Parameter Descriptions**

The table below describes the template and the function parameters.

 Table 10: **xf::imwrite** Function Parameter Descriptions

Parameter	Description
PTYPE	Input pixel type. Supported types are: XF_8UC1, XF_16UC1, XF_8UC3, XF_16UC3, XF_8UC4, and XF_16UC4
ROWS	Maximum height of the image to be read
COLS	Maximum width of the image to be read
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
img_name	Name of the file with the extension
img	xf::Mat array to be saved

### ***xf::absDiff***

The function `xf::absDiff` computes the absolute difference between each individual pixels of an `xf::Mat` and a `cv::Mat`, and returns the difference values in a `cv::Mat`.

## API Syntax

```
template <int PTYPE, int ROWS, int COLS, int NPC>
void absDiff(cv::Mat &cv_img, xf::Mat<PTYPE, ROWS, COLS, NPC>& xf_img,
cv::Mat &diff_img )
```

## Parameter Descriptions

The table below describes the template and the function parameters.

Table 11: **xf::absDiff** Function Parameter Descriptions

Parameter	Description
PTYPE	Input pixel type
ROWS	Maximum height of the image to be read
COLS	Maximum width of the image to be read
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1, XF_NPPC4, and XF_NPPC8 for 1-pixel, 4-pixel, and 8-pixel parallel operations respectively.
cv_img	cv::Mat array to be compared
xf_img	xf::Mat array to be compared
diff_img	Output difference image(cv::Mat)

## xf::convertTo

The `xf::convertTo` function performs bit depth conversion on each individual pixel of the given input image. This method converts the source pixel values to the target data type with appropriate casting.

$$dst(x,y) = cast<target-data-type>(a(src(x,y) + \beta))$$

**Note:** The output and input Mat cannot be the same. That is, the converted image cannot be stored in the Mat of the input image.

## API Syntax

```
template<int DST_T> void convertTo(xf::Mat<DST_T, ROWS, COLS, NPC> &dst,
int ctype, double alpha=1, double beta=0)
```

## Parameter Descriptions

The table below describes the template and function parameters.



Table 12: **xf::convertTo** Function Parameter Descriptions

Parameter	Description
DST_T	Output pixel type. Possible values are XF_8UC1, XF_16UC1, XF_16SC1, and XF_32SC1.
ROWS	Maximum height of image to be read
COLS	Maximum width of image to be read
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1, XF_NPPC4, and XF_NPPC8 for 1-pixel, 4-pixel, and 8-pixel parallel operations respectively.
dst	Converted xf Mat
ctype	Conversion type : Possible values are listed here. //Down-convert: <ul style="list-style-type: none"> <li>• XF_CONVERT_16U_TO_8U</li> <li>• XF_CONVERT_16S_TO_8U</li> <li>• XF_CONVERT_32S_TO_8U</li> <li>• XF_CONVERT_32S_TO_16U</li> <li>• XF_CONVERT_32S_TO_16S</li> </ul> //Up-convert: <ul style="list-style-type: none"> <li>• XF_CONVERT_8U_TO_16U</li> <li>• XF_CONVERT_8U_TO_16S</li> <li>• XF_CONVERT_8U_TO_32S</li> <li>• XF_CONVERT_16U_TO_32S</li> <li>• XF_CONVERT_16S_TO_32S</li> </ul>
alpha	Optional scale factor
beta	Optional delta added to the scaled values

## xfOpenCV Library Functions

The xfOpenCV library is a set of select OpenCV functions optimized for Zynq®-7000 SoC and Zynq UltraScale+ MPSoC devices. The following table lists the xfOpenCV library functions.

 Table 13: **xfOpenCV Library Functions**

Computations	Input Processing	Filters	Other
<a href="#">Absolute Difference</a>	<a href="#">Bit Depth Conversion</a>	<a href="#">Bilateral Filter</a>	<a href="#">Canny Edge Detection</a>
<a href="#">Accumulate</a>	<a href="#">Channel Combine</a>	<a href="#">Box Filter</a>	<a href="#">FAST Corner Detection</a>
<a href="#">Accumulate Squared</a>	<a href="#">Channel Extract</a>	<a href="#">Custom Convolution</a>	<a href="#">Harris Corner Detection</a>
<a href="#">Accumulate Weighted</a>	<a href="#">Color Conversion</a>	<a href="#">Dilate</a>	<a href="#">Histogram Computation</a>

Table 13: xfOpenCV Library Functions (cont'd)

Computations	Input Processing	Filters	Other
Atan2	Histogram Equalization	Erode	Dense Pyramidal LK Optical Flow
Bitwise AND, Bitwise NOT, Bitwise OR, Bitwise XOR	Look Up Table	Gaussian Filter	Dense Non-Pyramidal LK Optical Flow
Gradient Magnitude	Remap	Sobel Filter	MinMax Location
Gradient Phase	Resolution Conversion (Resize)	Median Blur Filter	Thresholding
Integral Image		Scharr Filter	WarpAffine
Inverse (Reciprocal)			WarpPerspective
Pixel-Wise Addition			SVM
Pixel-Wise Multiplication			Otsu Threshold
Pixel-Wise Subtraction			Mean Shift Tracking
Square Root			HOG
Mean and Standard Deviation			Stereo Local Block Matching
			WarpTransform
			Pyramid Up
			Pyramid Down
			Delay
			Duplicate
			Color Thresholding
			RGB2HSV
			InitUndistortRectifyMapInverse
			Houghlines
			Semi Global Method for Stereo Disparity Estimation

**Notes:**

1. The maximum resolution supported for all the functions is 4K, except Houghlines, HOG (RB mode), and Canny Edge Detection.

The following table lists the functions that are not supported on Zynq-7000 SoC devices, when configured to use 128-bit interfaces in 8 pixel per cycle mode.

Table 14: Unsupported Functions Using 128-bit Interfaces in 8 Pixel Per Cycle Mode on Zynq-7000 SoC

Computations	Input Processing	Filters
Accumulate	Bit Depth Conversion	Box Filter: signed 16-bit pixel type, and unsigned 16-bit pixel type
Accumulate Squared		Custom Convolution: signed 16-bit output pixel type

**Table 14: Unsupported Functions Using 128-bit Interfaces in 8 Pixel Per Cycle Mode on Zynq-7000 SoC (cont'd)**

Computations	Input Processing	Filters
Accumulate Weighted		Sobel Filter
Gradient Magnitude		Scharr Filter
Gradient Phase		
Pixel-Wise Addition: signed 16-bit pixel type, and unsigned 16-bit pixel type		
Pixel-Wise Multiplication: signed 16-bit pixel type, and unsigned 16-bit pixel type		
Pixel-Wise Subtraction: signed 16-bit pixel type, and unsigned 16-bit pixel type		

**Note:** Resolution Conversion (Resize) in 8 pixel per cycle mode, Dense Pyramidal LK Optical Flow, and Dense Non-Pyramidal LK Optical Flow functions are not supported on the Zynq-7000 SoC ZC702 devices, due to the higher resource utilization.

## Absolute Difference

The `absdiff` function finds the pixel wise absolute difference between two input images and returns an output image. The input and the output images must be the XF\_8UC1 type.

$$I_{\text{out}}(x, y) = |I_{\text{in1}}(x, y) - I_{\text{in2}}(x, y)|$$

Where,

- $I_{\text{out}}(x, y)$  is the intensity of output image at (x,y) position.
- $I_{\text{in1}}(x, y)$  is the intensity of first input image at (x,y) position.
- $I_{\text{in2}}(x, y)$  is the intensity of second input image at (x,y) position.

### API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1>
void absdiff(
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src1,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src2,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> dst )
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 15: **absdiff** Function Parameter Descriptions

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src1	Input image
src2	Input image
dst	Output image

### Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado® HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

 Table 16: **absdiff** Function Resource Utilization Summary

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	62	67	17
8 pixel	150	0	0	67	234	39

### Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

 Table 17: **absdiff** Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.69

### Deviation from OpenCV

There is no deviation from OpenCV, except that the `absdiff` function supports 8-bit pixels.

## Accumulate

The `accumulate` function adds an image (`src1`) to the accumulator image (`src2`), and generates the accumulated result image (`dst`).

$$dst(x, y) = src1(x, y) + src2(x, y)$$

### API Syntax

```
template<int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void accumulate (
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src1,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src2,
    xf::Mat<int DST_T, int ROWS, int COLS, int NPC> dst )
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 18: accumulate Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
DST_T	Output pixel type. Only 16-bit, unsigned, 1 channel is supported (XF_16UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src1	Input image
src2	Input image
dst	Output image

### Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

**Table 19: accumulate Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48E	FF	LUT	CLB
1 pixel	300	0	0	62	55	12
8 pixel	150	0	0	389	285	61

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 20: **accumulate Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

## Deviation from OpenCV

In OpenCV the accumulated image is stored in the second input image. The src2 image acts as both input and output, as shown below:

$$src2(x, y) = src1(x, y) + src2(x, y)$$

Whereas, in the xfOpenCV implementation, the accumulated image is stored separately, as shown below:

$$dst(x, y) = src1(x, y) + src2(x, y)$$

## Accumulate Squared

The `accumulateSquare` function adds the square of an image (src1) to the accumulator image (src2) and generates the accumulated result (dst).

$$dst(x, y) = src1(x, y)^2 + src2(x, y)$$

The accumulated result is a separate argument in the function, instead of having src2 as the accumulated result. In this implementation, having a bi-directional accumulator is not possible as the function makes use of streams.

## API Syntax

```
template<int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void accumulateSquare (
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src1,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src2,
    xf::Mat<int DST_T, int ROWS, int COLS, int NPC> dst)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 21: accumulateSquare Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
DST_T	Output pixel type. Only 16-bit, unsigned, 1 channel is supported (XF_16UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src1	Input image
src2	Input image
dst	Output image

## Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

**Table 22: accumulateSquare Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48E	FF	LUT	CLB
1 pixel	300	0	1	71	52	14
8 pixel	150	0	8	401	247	48

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

**Table 23: accumulateSquare Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.6

## Deviation from OpenCV

In OpenCV the accumulated squared image is stored in the second input image. The src2 image acts as input as well as output.

$$src2(x, y) = src1(x, y)^2 + src2(x, y)$$

Whereas, in the xfOpenCV implementation, the accumulated squared image is stored separately.

$$dst(x, y) = src1(x, y)^2 + src2(x, y)$$

## Accumulate Weighted

The `accumulateWeighted` function computes the weighted sum of the input image (src1) and the accumulator image (src2) and generates the result in dst.

$$dst(x, y) = alpha * src1(x, y) + (1 - alpha) * src2(x, y)$$

The accumulated result is a separate argument in the function, instead of having src2 as the accumulated result. In this implementation, having a bi-directional accumulator is not possible, as the function uses streams.

### API Syntax

```
template<int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void accumulateWeighted (
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src1,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src2,
    xf::Mat<int DST_T, int ROWS, int COLS, int NPC> dst,
    float alpha )
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 24: **accumulateWeighted Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
DST_T	Output pixel type. Only 16-bit, unsigned, 1 channel is supported (XF_16UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src1	Input image
src2	Input image



Table 24: **accumulateWeighted Function Parameter Descriptions** (cont'd)

Parameter	Description
dst	Output image
alpha	Weight applied to input image

### Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

 Table 25: **accumulateWeighted Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	5	295	255	52
8 pixel	150	0	19	556	476	88

### Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

 Table 26: **accumulateWeighted Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

### Deviation from OpenCV

The resultant image in OpenCV is stored in the second input image. The src2 image acts as input as well as output, as shown below:

$$src2(x, y) = alpha * src1(x, y) + (1 - alpha) * src2(x, y)$$

Whereas, in xfOpenCV implementation, the accumulated weighted image is stored separately.

$$dst(x, y) = alpha * src1(x, y) + (1 - alpha) * src2(x, y)$$

## Bilateral Filter

In general, any smoothing filter smoothens the image which will affect the edges of the image. To preserve the edges while smoothing, a bilateral filter can be used. In an analogous way as the Gaussian filter, the bilateral filter also considers the neighboring pixels with weights assigned to each of them. These weights have two components, the first of which is the same weighing used by the Gaussian filter. The second component takes into account the difference in the intensity between the neighboring pixels and the evaluated one.

The bilateral filter applied on an image is:

$$BF[I]_p = \frac{1}{W_p} \sum_{q \in S} G_{\sigma_s}(\|p - q\|) G_{\sigma_r}(\|I_p - I_q\|) I_q$$

Where

$$W_p = \sum_{q \in S} G_{\sigma_s}(\|p - q\|) G_{\sigma_r}(\|I_p - I_q\|)$$

and  $G_\sigma$  is a gaussian filter with variance  $\sigma$ .

The gaussian filter is given by:  $G_\sigma = e^{-\frac{(x^2+y^2)}{2\sigma^2}}$

### API Syntax

```
template<int FILTER_SIZE, int BORDER_TYPE, int TYPE, int ROWS, int COLS,
int NPC=1>
void bilateralFilter (
xf::Mat<int TYPE, int ROWS, int COLS, int NPC> src,
xf::Mat<int TYPE, int ROWS, int COLS, int NPC> dst,
float sigma_space, float sigma_color )
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 27: **bilateralFilter** Function Parameter Descriptions

Parameter	Description
FILTER_SIZE	Filter size. Filter size of 3 (XF_FILTER_3X3), 5 (XF_FILTER_5X5) and 7 (XF_FILTER_7X7) are supported
BORDER_TYPE	Border type supported is XF_BORDER_CONSTANT
TYPE	Input and output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)

Table 27: **bilateralFilter** Function Parameter Descriptions (cont'd)

Parameter	Description
NPC	Number of pixels to be processed per cycle; this function supports only XF_NPPC1 or 1 pixel per cycle operations.
src	Input image
dst	Output image
sigma_space	Standard deviation of filter in spatial domain
sigma_color	Standard deviation of filter used in color space

### Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

 Table 28: **bilateralFilter** Resource Utilization Summary

Operating Mode	Filter Size	Operating Frequency (MHz)	Utilization Estimate			
			BRAM_18K	DSP_48Es	FF	LUT
1 pixel	3x3	300	6	22	4934	4293
	5x5	300	12	30	5481	4943
	7x7	300	37	48	7084	6195

### Performance Estimate

The following table summarizes a performance estimate of the kernel in different configurations, as generated using Vivado HLS 2018.2 tool for Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

 Table 29: **bilateralFilter** Function Performance Estimate Summary

Operating Mode	Filter Size	Latency Estimate
		168 MHz
		Max (ms)
1 pixel	3x3	7.18
	5x5	7.20
	7x7	7.22

### Deviation from OpenCV

Unlike OpenCV, xfOpenCV only supports filter sizes of 3, 5 and 7.

## Bit Depth Conversion

The `convertTo` function converts the input image bit depth to the required bit depth in the output image.

### API Syntax

```
template <int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void convertTo(xf::Mat<SRC_T, ROWS, COLS, NPC> &_src_mat, xf::Mat<DST_T,
ROWS, COLS, NPC> &_dst_mat, ap_uint<4> _convert_type, int _shift)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 30: convertTo Function Parameter Descriptions*

Parameter	Description
SRC_T	Input pixel type. 8-bit, unsigned, 1 channel (XF_8UC1), 16-bit, unsigned, 1 channel (XF_16UC1), 16-bit, signed, 1 channel (XF_16SC1), 32-bit, unsigned, 1 channel (XF_32UC1) 32-bit, signed, 1 channel (XF_32SC1) are supported.
DST_T	Output pixel type. 8-bit, unsigned, 1 channel (XF_8UC1), 16-bit, unsigned, 1 channel (XF_16UC1), 16-bit, signed, 1 channel (XF_16SC1), 32-bit, unsigned, 1 channel (XF_32UC1) 32-bit, signed, 1 channel (XF_32SC1) are supported.
ROWS	Height of input and output images
COLS	Width of input and output images
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_mat	Input image
_dst_mat	Output image
_convert_type	This parameter specifies the type of conversion required. (See XF_convert_bit_depth_e enumerated type in file <code>xf_params.h</code> for possible values.)
_shift	Optional scale factor

### Possible Conversions

The following table summarizes supported conversions. The rows are possible input image bit depths and the columns are corresponding possible output image bit depths (U=unsigned, S=signed).

**Table 31: convertTo Function Supported Conversions**

INPUT/ OUTPUT	U8	U16	S16	U32	S32
U8	NA	yes	yes	NA	yes
U16	yes	NA	NA	NA	yes
S16	yes	NA	NA	NA	yes
U32	NA	NA	NA	NA	NA
S32	yes	yes	yes	NA	NA

### Resource Utilization

The following table summarizes the resource utilization of the convertTo function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

**Table 32: convertTo Function Resource Utilization Summary For XF\_CONVERT\_8U\_TO\_16S Conversion**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	8	581	523	119
8 pixel	150	0	8	963	1446	290

**Table 33: convertTo Function Resource Utilization Summary For XF\_CONVERT\_16U\_TO\_8U Conversion**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	8	591	541	124
8 pixel	150	0	8	915	1500	308

### Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 34: **convertTo** Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency
1 pixel operation (300 MHz)	6.91 ms
8 pixel operation (150 MHz)	1.69 ms

## Bitwise AND

The `bitwise_and` function performs the bitwise AND operation for each pixel between two input images, and returns an output image.

$$I_{out}(x, y) = I_{in1}(x, y) \ \& \ I_{in2}(x, y)$$

Where,

- $I_{out}(x, y)$  is the intensity of output image at (x, y) position
- $I_{in1}(x, y)$  is the intensity of first input image at (x, y) position
- $I_{in2}(x, y)$  is the intensity of second input image at (x, y) position

### API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1>
void bitwise_and (
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src1,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src2,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> dst )
```

### Parameter Descriptions

The following table describes the template and the function parameters.

 Table 35: **bitwise\_and** Function Parameter Descriptions

Parameter	Description
SRC_T	Input and output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src1	Input image
src2	Input image

Table 35: bitwise\_and Function Parameter Descriptions (cont'd)

Parameter	Description
dst	Output image

### Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

Table 36: bitwise\_and Function Resource Utilization Summary

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	62	44	10
8 pixel	150	0	0	59	72	13

### Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 37: bitwise\_and Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

## Bitwise NOT

The `bitwise_not` function performs the pixel wise bitwise NOT operation for the pixels in the input image, and returns an output image.  $I_{out}(x, y) = \sim I_{in}(x, y)$

Where,

- $I_{out}(x, y)$  is the intensity of output image at (x, y) position
- $I_{in}(x, y)$  is the intensity of input image at (x, y) position

## API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1>
void bitwise_not (
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> dst )
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 38: bitwise\_not Function Parameter Descriptions**

Parameter	Description
SRC_T	Input and output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src	Input image
dst	Output image

## Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

**Table 39: bitwise\_not Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	97	78	20
8 pixel	150	0	0	88	97	21

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.



Table 40: bitwise\_not Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

## Bitwise OR

The `bitwise_or` function performs the pixel wise bitwise OR operation between two input images, and returns an output image.  $I_{out}(x, y) = I_{in1}(x, y) | I_{in2}(x, y)$

Where,

- $I_{out}(x, y)$  is the intensity of output image at (x, y) position
- $I_{in1}(x, y)$  is the intensity of first input image at (x, y) position
- $I_{in2}(x, y)$  is the intensity of second input image at (x, y) position

### API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1>
void bitwise_or (
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src1,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src2,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> dst )
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 41: bitwise\_or Function Parameter Descriptions

Parameter	Description
SRC_T	Input and output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src1	Input image
src2	Input image
dst	Output image

## Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

Table 42: bitwise\_or Function Resource Utilization Summary

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	62	44	10
8 pixel	150	0	0	59	72	13

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 43: bitwise\_or Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

## Bitwise XOR

The `bitwise_xor` function performs the pixel wise bitwise XOR operation between two input images, and returns an output image, as shown below:

$$I_{out}(x, y) = I_{in1}(x, y) \oplus I_{in2}(x, y)$$

Where,

- $I_{out}(x, y)$  is the intensity of output image at (x, y) position
- $I_{in1}(x, y)$  is the intensity of first input image at (x, y) position
- $I_{in2}(x, y)$  is the intensity of second input image at (x, y) position

## API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1>
void bitwise_xor(
xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src1,
xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src2,
xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> dst )
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 44: bitwise\_xor Function Parameter Descriptions**

Parameter	Description
SRC_T	Input and output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src1	Input image
src2	Input image
dst	Output image

## Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image:

**Table 45: bitwise\_xor Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	62	44	10
8 pixel	150	0	0	59	72	13

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image:

Table 46: bitwise\_xor Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

## Box Filter

The `boxFilter` function performs box filtering on the input image. Box filter acts as a low-pass filter and performs blurring over the image. The `boxFilter` function or the box blur is a spatial domain linear filter in which each pixel in the resulting image has a value equal to the average value of the neighboring pixels in the image.

$$K_{box} = \frac{1}{(ksize*ksize)} \begin{bmatrix} 1 & \dots & 1 \\ 1 & \dots & 1 \\ 1 & \dots & 1 \end{bmatrix}$$

### API Syntax

```
template<int BORDER_TYPE,int FILTER_TYPE, int SRC_T, int ROWS, int
COLS,int NPC=1>
void boxFilter(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat,xf::Mat<SRC_T,
ROWS, COLS, NPC> & _dst_mat)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 47: boxFilter Function Parameter Descriptions

Parameter	Description
FILTER_SIZE	Filter size. Filter size of 3(XF_FILTER_3X3), 5(XF_FILTER_5X5) and 7(XF_FILTER_7X7) are supported
BORDER_TYPE	Border Type supported is XF_BORDER_CONSTANT
SRC_T	Input and output pixel type. 8-bit, unsigned, 16-bit unsigned and 16-bit signed, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_mat	Input image
_dst_mat	Output image

## Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

**Table 48: boxFilter Function Resource Utilization Summary**

Operating Mode	Filter Size	Operating Frequency (MHz)	Utilization Estimate				
			BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	3x3	300	3	1	545	519	104
	5x5	300	5	1	876	870	189
	7x7	300	7	1	1539	1506	300
8 pixel	3x3	150	6	8	1002	1368	264
	5x5	150	10	8	1576	3183	611
	7x7	150	14	8	2414	5018	942

## Performance Estimate

The following table summarizes the performance of the kernel in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image:

**Table 49: boxFilter Function Performance Estimate Summary**

Operating Mode	Operating Frequency (MHz)	Filter Size	Latency Estimate
			Max (ms)
1 pixel	300	3x3	7.2
	300	5x5	7.21
	300	7x7	7.22
8 pixel	150	3x3	1.7
	150	5x5	1.7
	150	7x7	1.7

## Canny Edge Detection

The Canny edge detector finds the edges in an image or video frame. It is one of the most popular algorithms for edge detection. Canny algorithm aims to satisfy three main criteria:

1. Low error rate: A good detection of only existent edges.

2. Good localization: The distance between edge pixels detected and real edge pixels have to be minimized.
3. Minimal response: Only one detector response per edge.

In this algorithm, the noise in the image is reduced first by applying a Gaussian mask. The Gaussian mask used here is the average mask of size 3x3. Thereafter, gradients along x and y directions are computed using the Sobel gradient function. The gradients are used to compute the magnitude and phase of the pixels. The phase is quantized and the pixels are binned accordingly. Non-maximal suppression is applied on the pixels to remove the weaker edges.

Edge tracing is applied on the remaining pixels to draw the edges on the image. In this algorithm, the canny up to non-maximal suppression is in one kernel and the edge linking module is in another kernel. After non-maxima suppression, the output is represented as 2-bit per pixel, Where:

- 00 - represents the background
- 01 - represents the weaker edge
- 11 - represents the strong edge

The output is packed as 8-bit (four 2-bit pixels) in 1 pixel per cycle operation and packed as 16-bit (eight 2-bit pixels) in 8 pixel per cycle operation. For the edge linking module, the input is 64-bit, such 32 pixels of 2-bit are packed into a 64-bit. The edge tracing is applied on the pixels and returns the edges in the image.

## API Syntax

The API syntax for Canny is:

```
template<int FILTER_TYPE,int NORM_TYPE,int SRC_T,int DST_T, int ROWS, int
COLS,int NPC,int NPC1>
void Canny(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat,xf::Mat<DST_T, ROWS,
COLS, NPC1> & _dst_mat,unsigned char _lowthreshold,unsigned char
_highthreshold)
```

The API syntax for EdgeTracing is:

```
template<int SRC_T, int DST_T, int ROWS, int COLS,int NPC_SRC,int NPC_DST>
voidEdgeTracing(xf::Mat<SRC_T, ROWS, COLS, NPC_SRC> & _src,xf::Mat<DST_T,
ROWS, COLS, NPC_DST> & _dst)
```

## Parameter Descriptions

The following table describes the `xf::Canny` template and function parameters:

Table 50: `xf::Canny` Function Parameter Descriptions

Parameter	Description
<code>FILTER_TYPE</code>	The filter window dimensions. The options are 3 and 5.
<code>NORM_TYPE</code>	The type of norm used. The options for norm type are L1NORM and L2NORM.
<code>SRC_T</code>	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
<code>DST_T</code>	Output pixel type. The output in 1pixel case is 8-bit and packing four 2-bit pixel values into 8-bit. The Output in 8 pixel case is 16-bit, 8-bit, 2-bit pixel values are packing into 16-bit.
<code>ROWS</code>	Maximum height of input and output image (must be a multiple of 8)
<code>COLS</code>	Maximum width of input and output image (must be a multiple of 8)
<code>NPC</code>	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
<code>_src_mat</code>	Input image
<code>_dst_mat</code>	Output image
<code>_lowthreshold</code>	The lower value of threshold for binary thresholding.
<code>_highthreshold</code>	The higher value of threshold for binary thresholding.

The following table describes the `EdgeTracing` template and function parameters:

 Table 51: `EdgeTracing` Function Parameter Descriptions

Parameter	Description
<code>SRC_T</code>	Input pixel type
<code>DST_T</code>	Output pixel type
<code>ROWS</code>	Maximum height of input and output image (must be a multiple of 8)
<code>COLS</code>	Maximum width of input and output image (must be a multiple of 8)
<code>NPC_SRC</code>	Number of pixels to be processed per cycle. Fixed to XF_NPPC32.
<code>NPC_DST</code>	Number of pixels to be written to destination. Fixed to XF_NPPC8.
<code>_src</code>	Input image
<code>_dst</code>	Output image

## Resource Utilization

The following table summarizes the resource utilization of `xf::Canny` and `EdgeTracing` in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-fv1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image for Filter size is 3.

Table 52: xf::Canny and EdgeTracing Function Resource Utilization Summary

Name	Resource Utilization					
	1 pixel		1 pixel		Edge Linking	Edge Linking
	L1NORM,FS: 3	L2NORM,FS: 3	L1NORM,FS: 3	L2NORM,FS: 3		
	300 MHz	300 MHz	150 MHz	150 MHz	300 MHz	150 MHz
BRAM_18K	22	18	36	32	84	84
DSP48E	2	4	16	32	3	3
FF	3027	3507	4899	6208	17600	14356
LUT	2626	3170	6518	9560	15764	14274
CLB	606	708	1264	1871	2955	3241

### Performance Estimate

The following table summarizes the performance of the kernel in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image for L1NORM, filter size is 3 and including the edge linking module.

Table 53: xf::Canny and EdgeTracing Function Performance Estimate Summary

Operating Mode	Latency Estimate	
	Operating Frequency (MHz)	Latency (in ms)
1 pixel	300	10.2
8 pixel	150	8

### Deviation from OpenCV

In OpenCV Canny function, the Gaussian blur is not applied as a pre-processing step.

## Channel Combine

The `merge` function, merges single channel images into a multi-channel image. The number of channels to be merged should be four.

### API Syntax

```
template<int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void merge(xf::Mat<SRC_T, ROWS, COLS, NPC> &_src1, xf::Mat<SRC_T, ROWS,
COLS, NPC> &_src2, xf::Mat<SRC_T, ROWS, COLS, NPC> &_src3, xf::Mat<SRC_T,
ROWS, COLS, NPC> &_src4, xf::Mat<DST_T, ROWS, COLS, NPC> &_dst)
```



## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 54: merge Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 4 channel is supported (XF_8UC1)
DST_T	Output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC4)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 for 1 pixel operation.
_src1	Input single-channel image
_src2	Input single-channel image
_src3	Input single-channel image
_src4	Input single-channel image
_dst	Output multi-channel image

## Resource Utilization

The following table summarizes the resource utilization of the merge function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process 4 single-channel HD (1080x1920) images.

**Table 55: merge Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	8	494	386	85

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process 4 single channel HD (1080x1920) images.

**Table 56: merge Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency
1 pixel operation (300 MHz)	6.92 ms

## Channel Extract

The `extractChannel` function splits a multi-channel array (32-bit pixel-interleaved data) into several single-channel arrays and returns a single channel. The channel to be extracted is specified by using the `channel` argument.

The value of the `channel` argument is specified by macros defined in the `xf_channel_extract_e` enumerated data type. The following table summarizes the possible values for the `xf_channel_extract_e` enumerated data type:

**Table 57: xf\_channel\_extract\_e Enumerated Data Type Values**

Channel	Enumerated Type
Unknown	XF_EXTRACT_CH_0
Unknown	XF_EXTRACT_CH_1
Unknown	XF_EXTRACT_CH_2
Unknown	XF_EXTRACT_CH_3
RED	XF_EXTRACT_CH_R
GREEN	XF_EXTRACT_CH_G
BLUE	XF_EXTRACT_CH_B
ALPHA	XF_EXTRACT_CH_A
LUMA	XF_EXTRACT_CH_Y
Cb/U	XF_EXTRACT_CH_U
Cr/V/Value	XF_EXTRACT_CH_V

### API Syntax

```
template<int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void extractChannel(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat,
xf::Mat<DST_T, ROWS, COLS, NPC> & _dst_mat, uint16_t _channel)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 58: extractChannel Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 4channel is supported (XF_8UC4)
DST_T	Output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 for 1 pixel operation.
_src_mat	Input multi-channel image

Table 58: **extractChannel** Function Parameter Descriptions (cont'd)

Parameter	Description
<code>_dst_mat</code>	Output single channel image
<code>_channel</code>	Channel to be extracted (See <code>xf_channel_extract_e</code> enumerated type in file <code>xf_params.h</code> for possible values.)

## Resource Utilization

The following table summarizes the resource utilization of the `extractChannel` function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a 4 channel HD (1080x1920) image.

 Table 59: **extractChannel** Function Resource Utilization Summary

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	8	508	354	96

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a 4 channel HD (1080x1920) image.

 Table 60: **extractChannel** Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.92

## Color Conversion

The color conversion functions convert one image format to another image format, for the combinations listed in the following table. The rows represent the input formats and the columns represent the output formats. Supported conversions are discussed in the following sections.

I/O Formats	RGBA	NV12	NV21	IYUV	UYVY	YUYV	YUV4
RGBA	N/A	For details, see the <a href="#">RGBA to NV12</a>	For details, see the <a href="#">RGBA to NV21</a>	For details, see the <a href="#">RGBA to IYUV</a>			For details, see the <a href="#">RGBA to YUV4</a>
NV12	For details, see the <a href="#">NV12 to RGBA</a>	N/A		For details, see the <a href="#">NV12 to IYUV</a>			For details, see the <a href="#">NV12 to YUV4</a>

NV21	For details, see the <a href="#">NV21 to RGBA</a>		N/A	For details, see the <a href="#">NV21 to IYUV</a>			For details, see the <a href="#">NV21 to YUV4</a>
IYUV	For details, see the <a href="#">IYUV to RGBA</a>	For details, see the <a href="#">IYUV to NV12</a>		N/A			For details, see the <a href="#">IYUV to YUV4</a>
UYVY	For details, see the <a href="#">UYVY to RGBA</a>	For details, see the <a href="#">UYVY to NV12</a>		For details, see the <a href="#">UYVY to IYUV</a>	N/A		
YUYV	For details, see the <a href="#">YUYV to RGBA</a>	For details, see the <a href="#">YUYV to NV12</a>		For details, see the <a href="#">YUYV to IYUV</a>		N/A	
YUV4							N/A

### RGB to YUV Conversion Matrix

Following is the formula to convert RGB data to YUV data:

$$\begin{bmatrix} Y \\ U \\ V \end{bmatrix} = \begin{bmatrix} 0.257 & 0.504 & 0.098 & 16 \\ -0.148 & -0.291 & 0.439 & 128 \\ 0.439 & -0.368 & -0.071 & 128 \end{bmatrix} \begin{bmatrix} R \\ G \\ B \\ 1 \end{bmatrix}$$

### YUV to RGB Conversion Matrix

Following is the formula to convert YUV data to RGB data:

$$\begin{bmatrix} R \\ G \\ B \end{bmatrix} = \begin{bmatrix} 1.164 & 0 & 1.596 \\ 1.164 & -0.391 & -0.813 \\ 1.164 & 2.018 & 0 \end{bmatrix} \begin{bmatrix} (Y - 16) \\ (U - 128) \\ (V - 128) \end{bmatrix}$$

Source: <http://www.fourcc.org/fccvrgb.php>

### RGBA to YUV4

The `rgba2yuv4` function converts a 4-channel RGBA image to YUV444 format. The function outputs Y, U, and V streams separately.

#### API Syntax

```
template <int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void rgba2yuv4(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, xf::Mat<DST_T,
ROWS, COLS, NPC> & _y_image, xf::Mat<DST_T, ROWS, COLS, NPC> & _u_image,
xf::Mat<DST_T, ROWS, COLS, NPC> & _v_image)
```

#### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 62: rgba2yuv4 Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 4-channel is supported (XF_8UC4).
DST_T	Output pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input Y plane of size (ROWS, COLS).
_y_image	Output Y image of size (ROWS, COLS).
_u_image	Output U image of size (ROWS, COLS).
_v_image	Output V image of size (ROWS, COLS).

### Resource Utilization

The following table summarizes the resource utilization of RGBA to YUV4 for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

**Table 63: rgba2yuv4 Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	9	589	328	96

### Performance Estimate

The following table summarizes the performance of RGBA to YUV4 for different configurations, as generated using the Vivado HLS 2018.2 version for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

**Table 64: rgba2yuv4 Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	1.89

## RGBA to IYUV

The `rgba2iyuv` function converts a 4-channel RGBA image to IYUV (4:2:0) format. The function outputs Y, U, and V planes separately. IYUV holds subsampled data, Y is sampled for every RGBA pixel and U,V are sampled once for 2row and 2column(2x2) pixels. U and V planes are of  $(rows/2)*(columns/2)$  size, by cascading the consecutive rows into a single row the planes size becomes  $(rows/4)*columns$ .

### API Syntax

```
template <int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void rgba2iyuv(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, xf::Mat<DST_T,
ROWS, COLS, NPC> & _y_image, xf::Mat<DST_T, ROWS/4, COLS, NPC> & _u_image,
xf::Mat<DST_T, ROWS/4, COLS, NPC> & _v_image)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 65: rgba2iyuv Function Parameter Descriptions*

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 4-channel is supported (XF_8UC4).
DST_T	Output pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input Y plane of size (ROWS, COLS).
_y_image	Output Y image of size (ROWS, COLS).
_u_image	Output U image of size (ROWS/4, COLS).
_v_image	Output V image of size (ROWS/4, COLS).

### Resource Utilization

The following table summarizes the resource utilization of RGBA to IYUV for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

**Table 66: rgba2iyuv Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	9	816	472	149

### Performance Estimate

The following table summarizes the performance of RGBA to IYUV for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

**Table 67: rgba2iyuv Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	1.8

### RGBA to NV12

The `rgba2nv12` function converts a 4-channel RGBA image to NV12 (4:2:0) format. The function outputs Y plane and interleaved UV plane separately. NV12 holds the subsampled data, Y is sampled for every RGBA pixel and U, V are sampled once for 2row and 2columns (2x2) pixels. UV plane is of  $(rows/2)*(columns/2)$  size as U and V values are interleaved.

### API Syntax

```
template <int SRC_T, int Y_T, int UV_T, int ROWS, int COLS, int NPC=1>
void rgba2nv12(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, xf::Mat<Y_T, ROWS, COLS, NPC> & _y, xf::Mat<UV_T, ROWS/2, COLS/2, NPC> & _uv)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 68: rgba2nv12 Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 4-channel is supported (XF_8UC4).
Y_T	Output pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Output pixel type. Only 8-bit, unsigned, 2-channel is supported (XF_8UC2).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).

Table 68: **rgba2nv12 Function Parameter Descriptions** (cont'd)

Parameter	Description
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input RGBA image of size (ROWS, COLS).
_y	Output Y image of size (ROWS, COLS).
_uv	Output UV image of size (ROWS/2, COLS/2).

### Resource Utilization

The following table summarizes the resource utilization of RGBA to NV12 for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

 Table 69: **rgba2nv12 Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	9	802	452	128

### Performance Estimate

The following table summarizes the performance of RGBA to NV12 for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

 Table 70: **rgba2nv12 Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	1.8

### RGBA to NV21

The `rgba2nv21` function converts a 4-channel RGBA image to NV21 (4:2:0) format. The function outputs Y plane and interleaved VU plane separately. NV21 holds subsampled data, Y is sampled for every RGBA pixel and U, V are sampled once for 2 row and 2 columns (2x2) RGBA pixels. UV plane is of  $(rows/2) * (columns/2)$  size as V and U values are interleaved.



## API Syntax

```
template <int SRC_T, int Y_T, int UV_T, int ROWS, int COLS, int NPC=1>
void rgba2nv21(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, xf::Mat<Y_T, ROWS,
COLS, NPC> & _y, xf::Mat<UV_T, ROWS/2, COLS/2, NPC> & _uv)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

*Table 71: rgba2nv21 Function Parameter Descriptions*

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 4-channel is supported (XF_8UC4).
Y_T	Output pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Output pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC2).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input RGBA image of size (ROWS, COLS).
_y	Output Y image of size (ROWS, COLS).
_uv	Output UV image of size (ROWS/2, COLS/2).

## Resource Utilization

The following table summarizes the resource utilization of RGBA to NV21 for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

*Table 72: rgba2nv21 Function Resource Utilization Summary*

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	9	802	453	131

## Performance Estimate

The following table summarizes the performance of RGBA to NV21 for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 73: **rgba2nv21 Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	1.89

## YUYV to RGBA

The `yuyv2rgba` function converts a single-channel YUYV (YUV 4:2:2) image format to a 4-channel RGBA image. YUYV is a sub-sampled format, a set of YUYV value gives 2 RGBA pixel values. YUYV is represented in 16-bit values where as, RGBA is represented in 32-bit values.

### API Syntax

```
template<int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void yuyv2rgba(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, xf::Mat<DST_T,
ROWS, COLS, NPC> & _dst)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

 Table 74: **yuyv2rgba Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 16-bit, unsigned, 1-channel is supported (XF_16UC1).
DST_T	Output pixel type. Only 8-bit, unsigned, 4-channel is supported (XF_8UC4).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input image of size (ROWS, COLS).
_dst	Output image of size (ROWS, COLS).

### Resource Utilization

The following table summarizes the resource utilization of YUYV to RGBA for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

**Table 75: yuyv2rgba Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	6	765	705	165

### Performance Estimate

The following table summarizes the performance of UYVY to RGBA for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

**Table 76: yuyv2rgba Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9

### YUYV to NV12

The `yuyv2nv12` function converts a single-channel YUYV (YUV 4:2:2) image format to NV12 (YUV 4:2:0) format. YUYV is a sub-sampled format, 1 set of YUYV value gives 2 Y values and 1 U and V value each.

### API Syntax

```
template<int SRC_T,int Y_T,int UV_T,int ROWS,int COLS,int NPC=1,int
NPC_UV=1>
void yuyv2nv12(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src,xf::Mat<Y_T, ROWS,
COLS, NPC> & _y_image,xf::Mat<UV_T, ROWS/2, COLS/2, NPC_UV> & _uv_image)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 77: yuyv2nv12 Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 16-bit, unsigned, 1-channel is supported (XF_16UC1).
Y_T	Output pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Output UV image pixel type. Only 8-bit, unsigned, 2-channel is supported (XF_8UC2).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).

Table 77: **yuyv2nv12 Function Parameter Descriptions** (cont'd)

Parameter	Description
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
NPC_UV	Number of UV image Pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input image of size (ROWS, COLS).
_y_image	Output Y plane of size (ROWS, COLS).
_uv_image	Output U plane of size (ROWS/2, COLS/2).

### Resource Utilization

The following table summarizes the resource utilization of YUYV to NV12 for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

 Table 78: **yuyv2nv12 Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	831	491	149
8 pixel	150	0	0	1196	632	161

### Performance Estimate

The following table summarizes the performance of YUYV to NV12 for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

 Table 79: **yuyv2nv12 Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

## YUYV to IYUV

The `yuyv2iyuv` function converts a single-channel YUYV (YUV 4:2:2) image format to IYUV(4:2:0) format. Outputs of the function are separate Y, U, and V planes. YUYV is a sub-sampled format, 1 set of YUYV value gives 2 Y values and 1 U and V value each. U, V values of the odd rows are dropped as U, V values are sampled once for 2 rows and 2 columns in the IYUV(4:2:0) format.

### API Syntax

```
template<int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void yuyv2iyuv(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, xf::Mat<DST_T,
ROWS, COLS, NPC> & _y_image, xf::Mat<DST_T, ROWS/4, COLS, NPC> & _u_image,
xf::Mat<DST_T, ROWS/4, COLS, NPC> & _v_image)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 80: yuyv2iyuv Function Parameter Descriptions*

Parameter	Description
SRC_T	Input pixel type. Only 16-bit, unsigned, 1 channel is supported (XF_16UC1).
DST_T	Output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input image of size (ROWS, COLS).
_y_image	Output Y plane of size (ROWS, COLS).
_u_image	Output U plane of size (ROWS/4, COLS).
_v_image	Output V plane of size (ROWS/4, COLS).

### Resource Utilization

The following table summarizes the resource utilization of YUYV to IYUV for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

**Table 81: uyvy2iyuv Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	835	497	149
8 pixel	150	0	0	1428	735	210

### Performance Estimate

The following table summarizes the performance of YUYV to IYUV for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

**Table 82: uyvy2iyuv Function Performance Estimate**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

### UYVY to IYUV

The `uyvy2iyuv` function converts a UYVY (YUV 4:2:2) single-channel image to the IYUV format. The outputs of the functions are separate Y, U, and V planes. UYVY is sub sampled format. 1 set of UYVY value gives 2 Y values and 1 U and V value each.

### API Syntax

```
template<int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void uyvy2iyuv(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, xf::Mat<DST_T,
ROWS, COLS, NPC> & _y_image, xf::Mat<DST_T, ROWS/4, COLS, NPC> & _u_image,
xf::Mat<DST_T, ROWS/4, COLS, NPC> & _v_image)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 83: uyvy2iyuv Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 16-bit, unsigned, 1-channel is supported (XF_16UC1).
DST_T	Output pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
ROWS	Maximum height of input and output image (must be a multiple of 8).

Table 83: **uyvy2iyuv Function Parameter Descriptions** (cont'd)

Parameter	Description
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input image of size (ROWS, COLS).
_y_image	Output Y plane of size (ROWS, COLS).
_u_image	Output U plane of size (ROWS/4, COLS).
_v_image	Output V plane of size (ROWS/4, COLS).

### Resource Utilization

The following table summarizes the resource utilization of UYVY to IYUV for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image..

 Table 84: **uyvy2iyuv Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	835	494	139
8 pixel	150	0	0	1428	740	209

### Performance Estimate

The following table summarizes the performance of UYVY to IYUV for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

 Table 85: **uyvy2iyuv Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

### UYVY to RGBA

The `uyvy2rgba` function converts a UYVY (YUV 4:2:2) single-channel image to a 4-channel RGBA image. UYVY is sub sampled format, 1set of UYVY value gives 2 RGBA pixel values. UYVY is represented in 16-bit values where as RGBA is represented in 32-bit values.

## API Syntax

```
template<int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void uyvy2rgba(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, xf::Mat<DST_T,
ROWS, COLS, NPC> & _dst)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

*Table 86: uyvy2rgba Function Parameter Descriptions*

Parameter	Description
SRC_T	Input pixel type. Only 16-bit, unsigned, 1-channel is supported (XF_16UC1).
DST_T	Output pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input image of size (ROWS, COLS).
_dst	Output image of size (ROWS, COLS).

## Resource Utilization

The following table summarizes the resource utilization of UYVY to RGBA for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

*Table 87: uyvy2rgba Function Resource Utilization Summary*

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	6	773	704	160

## Performance Estimate

The following table summarizes the performance of UYVY to RGBA for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.



Table 88: uyvy2rgba Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.8

## UYVY to NV12

The `uyvy2nv12` function converts a UYVY (YUV 4:2:2) single-channel image to NV12 format. The outputs are separate Y and UV planes. UYVY is sub sampled format, 1 set of UYVY value gives 2 Y values and 1 U and V value each.

### API Syntax

```
template<int SRC_T, int Y_T, int UV_T, int ROWS, int COLS, int NPC=1, int
NPC_UV=1>
void uyvy2nv12(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src,xf::Mat<Y_T, ROWS,
COLS, NPC> & _y_image,xf::Mat<UV_T, ROWS/2, COLS/2, NPC_UV> & _uv_image)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 89: uyvy2nv12 Function Parameter Descriptions

Parameter	Description
SRC_T	Input pixel type. Only 16-bit, unsigned, 1-channel is supported (XF_16UC1).
Y_T	Output pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Output UV image pixel type. Only 8-bit, unsigned, 2-channel is supported (XF_8UC2).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
NPC_UV	Number of UV image Pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC4 for 1 pixel and 8 pixel operations respectively.
_src	Input image of size (ROWS, COLS).
_y_image	Output Y plane of size (ROWS, COLS).
_uv_image	Output U plane of size (ROWS/2, COLS/2).

### Resource Utilization

The following table summarizes the resource utilization of UYVY to NV12 for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

Table 90: uyvy2nv12 Function Resource Utilization Summary

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	831	488	131
8 pixel	150	0	0	1235	677	168

### Performance Estimate

The following table summarizes the performance of UYVY to NV12 for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 91: uyvy2nv12 Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

### IYUV to RGBA

The `iyuv2rgba` function converts single channel IYUV (YUV 4:2:0) image to a 4-channel RGBA image. The inputs to the function are separate Y, U, and V planes. IYUV is sub sampled format, U and V values are sampled once for 2 rows and 2 columns of the RGBA pixels. The data of the consecutive rows of size (columns/2) is combined to form a single row of size (columns).

### API Syntax

```
template<int SRC_T, int DST_T, int ROWS, int COLS, int NPC=1>
void iyuv2rgba(xf::Mat<SRC_T, ROWS, COLS, NPC> & src_y, xf::Mat<SRC_T,
ROWS/4, COLS, NPC> & src_u,xf::Mat<SRC_T, ROWS/4, COLS, NPC> & src_v,
xf::Mat<DST_T, ROWS, COLS, NPC> & _dst0)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 92: iyuv2rgba Function Parameter Descriptions

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
DST_T	Output pixel type. Only 8-bit, unsigned, 4-channel is supported (XF_8UC4).

Table 92: **iyuv2rgba Function Parameter Descriptions** (cont'd)

Parameter	Description
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src_y	Input Y plane of size (ROWS, COLS).
src_u	Input U plane of size (ROWS/4, COLS).
src_v	Input V plane of size (ROWS/4, COLS).
_dst0	Output RGBA image of size (ROWS, COLS).

### Resource Utilization

The following table summarizes the resource utilization of IYUV to RGBA for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

 Table 93: **iyuv2rgba Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	2	5	1208	728	196

### Performance Estimate

The following table summarizes the performance of IYUV to RGBA for different configurations, as generated using the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

 Table 94: **iyuv2rgba Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9

### IYUV to NV12

The `iyuv2nv12` function converts single channel IYUV image to NV12 format. The inputs are separate U and V planes. There is no need of processing Y plane as both the formats have a same Y plane. U and V values are rearranged from plane interleaved to pixel interleaved.

## API Syntax

```
template<int SRC_T, int UV_T, int ROWS, int COLS, int NPC =1, int NPC_UV=1>
void iyuv2nv12(xf::Mat<SRC_T, ROWS, COLS, NPC> & src_y, xf::Mat<SRC_T,
ROWS/4, COLS, NPC> & src_u,xf::Mat<SRC_T, ROWS/4, COLS, NPC> &
src_v,xf::Mat<SRC_T, ROWS, COLS, NPC> & _y_image, xf::Mat<UV_T, ROWS/2,
COLS/2, NPC_UV> & _uv_image)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 95: iyuv2nv12 Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Output pixel type. Only 8-bit, unsigned, 2-channel is supported (XF_8UC2).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
NPC_UV	Number of UV Pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC4 for 1 pixel and 4-pixel operations respectively.
src_y	Input Y plane of size (ROWS, COLS).
src_u	Input U plane of size (ROWS/4, COLS).
src_v	Input V plane of size (ROWS/4, COLS).
_y_image	Output V plane of size (ROWS, COLS).
_uv_image	Output UV plane of size (ROWS/2, COLS/2).

## Resource Utilization

The following table summarizes the resource utilization of IYUV to NV12 for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image..

**Table 96: iyuv2nv12 Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	12	907	677	158
8 pixel	150	0	12	1591	1022	235

## Performance Estimate

The following table summarizes the performance of IYUV to NV12 for different configurations, as generated using the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

*Table 97: iyuv2nv12 Function Performance Estimate Summary*

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

## IYUV to YUV4

The `iyuv2yuv4` function converts a single channel IYUV image to a YUV444 format. Y plane is same for both the formats. The inputs are separate U and V planes of IYUV image and the outputs are separate U and V planes of YUV4 image. IYUV stores subsampled U,V values. YUV format stores U and V values for every pixel. The same U, V values are duplicated for 2 rows and 2 columns (2x2) pixels in order to get the required data in the YUV444 format.

## API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1>
void iyuv2yuv4(xf::Mat<SRC_T, ROWS, COLS, NPC> & src_y, xf::Mat<SRC_T,
ROWS/4, COLS, NPC> & src_u,xf::Mat<SRC_T, ROWS/4, COLS, NPC> &
src_v,xf::Mat<SRC_T, ROWS, COLS, NPC> & _y_image, xf::Mat<SRC_T, ROWS,
COLS, NPC> & _u_image, xf::Mat<SRC_T, ROWS, COLS, NPC> & _v_image)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

*Table 98: iyuv2yuv4 Function Parameter Descriptions*

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src_y	Input Y plane of size (ROWS, COLS).
src_u	Input U plane of size (ROWS/4, COLS).
src_v	Input V plane of size (ROWS/4, COLS).
_y_image	Output Y image of size (ROWS, COLS).

Table 98: **iyuv2yuv4 Function Parameter Descriptions** (cont'd)

Parameter	Description
<code>_u_image</code>	Output U image of size (ROWS, COLS).
<code>_v_image</code>	Output V image of size (ROWS, COLS).

### Resource Utilization

The following table summarizes the resource utilization of IYUV to YUV4 for different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

 Table 99: **iyuv2yuv4 Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	1398	870	232
8 pixel	150	0	0	2134	1214	304

### Performance Estimate

The following table summarizes the performance of IYUV to YUV4 for different configurations, as generated using the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

 Table 100: **iyuv2yuv4 Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	13.8
8 pixel operation (150 MHz)	3.4

### NV12 to IYUV

The `nv122iyuv` function converts NV12 format to IYUV format. The function inputs the interleaved UV plane and the outputs are separate U and V planes. There is no need of processing the Y plane as both the formats have a same Y plane. U and V values are rearranged from pixel interleaved to plane interleaved.

## API Syntax

```
template<int SRC_T, int UV_T, int ROWS, int COLS, int NPC=1, int NPC_UV=1>
void nv122iyuv(xf::Mat<SRC_T, ROWS, COLS, NPC> & src_y, xf::Mat<UV_T,
ROWS/2, COLS/2, NPC_UV> & src_uv, xf::Mat<SRC_T, ROWS, COLS, NPC> &
_y_image, xf::Mat<SRC_T, ROWS/4, COLS, NPC> & _u_image, xf::Mat<SRC_T,
ROWS/4, COLS, NPC> & _v_image)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 101: nv122iyuv Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Input pixel type. Only 8-bit, unsigned, 2-channel is supported (XF_8UC2).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
NPC_UV	Number of UV image Pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC4 for 1 pixel and 4-pixel operations respectively.
src_y	Input Y plane of size (ROWS, COLS).
src_uv	Input UV plane of size (ROWS/2, COLS/2).
_y_image	Output Y plane of size (ROWS, COLS).
_u_image	Output U plane of size (ROWS/4, COLS).
_v_image	Output V plane of size (ROWS/4, COLS).

## Resource Utilization

The following table summarizes the resource utilization of NV12 to IYUV for different configurations, as generated in the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

**Table 102: nv122iyuv Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	1	1344	717	208
8 pixel	150	0	1	1961	1000	263

## Performance Estimate

The following table summarizes the performance of NV12 to IYUV for different configurations, as generated using the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 103: **nv12iyuv Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

## NV12 to RGBA

The `nv122rgba` function converts NV12 image format to a 4-channel RGBA image. The inputs to the function are separate Y and UV planes. NV12 holds sub sampled data, Y plane is sampled at unit rate and 1 U and 1V value each for every 2x2 Y values. To generate the RGBA data, each U and V value is duplicated (2x2) times.

## API Syntax

```
template<int SRC_T, int UV_T, int DST_T, int ROWS, int COLS, int NPC=1>
void nv122rgba(xf::Mat<SRC_T, ROWS, COLS, NPC> & src_y,xf::Mat<UV_T,
ROWS/2, COLS/2, NPC> & src_uv,xf::Mat<DST_T, ROWS, COLS, NPC> & _dst0)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

Table 104: **nv122rgba Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Input pixel type. Only 8-bit, unsigned, 2-channel is supported (XF_8UC2).
DST_T	Output pixel type. Only 8-bit, unsigned, 4channel is supported (XF_8UC4).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src_y	Input Y plane of size (ROWS, COLS).
src_uv	Input UV plane of size (ROWS/2, COLS/2).
_dst0	Output RGBA image of size (ROWS, COLS).



## Resource Utilization

The following table summarizes the resource utilization of NV12 to RGBA for different configurations, as generated in the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

Table 105: **nv122rgba Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	2	5	1191	708	195

## Performance Estimate

The following table summarizes the performance of NV12 to RGBA for different configurations, as generated using the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 106: **nv122rgba Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9

## NV12 to YUV4

The `nv122yuv4` function converts a NV12 image format to a YUV444 format. The function outputs separate U and V planes. Y plane is same for both the image formats. The UV planes are duplicated 2x2 times to represent one U plane and V plane of the YUV444 image format.

## API Syntax

```
template<int SRC_T,int UV_T, int ROWS, int COLS, int NPC=1, int NPC_UV=1>
void nv122yuv4(xf::Mat<SRC_T, ROWS, COLS, NPC> & src_y, xf::Mat<UV_T,
ROWS/2, COLS/2, NPC_UV> & src_uv,xf::Mat<SRC_T, ROWS, COLS, NPC> &
_y_image, xf::Mat<SRC_T, ROWS, COLS, NPC> & _u_image,xf::Mat<SRC_T, ROWS,
COLS, NPC> & _v_image)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

Table 107: **nv122yuv4 Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Input pixel type. Only 8-bit, unsigned, 2-channel is supported (XF_8UC2).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
NPC_UV	Number of UV image Pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC4 for 1 pixel and 4-pixel operations respectively.
src_y	Input Y plane of size (ROWS, COLS).
src_uv	Input UV plane of size (ROWS/2, COLS/2).
_y_image	Output Y plane of size (ROWS, COLS).
_u_image	Output U plane of size (ROWS, COLS).
_v_image	Output V plane of size (ROWS, COLS).

### Resource Utilization

The following table summarizes the resource utilization of NV12 to YUV4 for different configurations, as generated in the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

 Table 108: **nv122yuv4 Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	1383	832	230
8 pixel	150	0	0	1772	1034	259

### Performance Estimate

The following table summarizes the performance of NV12 to YUV4 for different configurations, as generated using the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

 Table 109: **nv122yuv4 Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	13.8
8 pixel operation (150 MHz)	3.4

## NV21 to IYUV

The `nv212iyuv` function converts a NV21 image format to an IYUV image format. The input to the function is the interleaved VU plane only and the outputs are separate U and V planes. There is no need of processing Y plane as both the formats have same the Y plane. U and V values are rearranged from pixel interleaved to plane interleaved.

### API Syntax

```
template<int SRC_T, int UV_T, int ROWS, int COLS, int NPC=1,int NPC_UV=1>
void nv212iyuv(xf::Mat<SRC_T, ROWS, COLS, NPC> & src_y, xf::Mat<UV_T,
ROWS/2, COLS/2, NPC_UV> & src_uv,xf::Mat<SRC_T, ROWS, COLS, NPC> &
_y_image, xf::Mat<SRC_T, ROWS/4, COLS, NPC> & _u_image,xf::Mat<SRC_T,
ROWS/4, COLS, NPC> & _v_image)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 110: `nv212iyuv` Function Parameter Descriptions

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Input pixel type. Only 8-bit, unsigned, 2-channel is supported (XF_8UC2).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
NPC_UV	Number of UV image Pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC4 for 1 pixel and 4-pixel operations respectively.
src_y	Input Y plane of size (ROWS, COLS).
src_uv	Input UV plane of size (ROWS/2, COLS/2).
_y_image	Output Y plane of size (ROWS, COLS).
_u_image	Output U plane of size (ROWS/4, COLS).
_v_image	Output V plane of size (ROWS/4, COLS).

### Resource Utilization

The following table summarizes the resource utilization of NV21 to IYUV for different configurations, as generated in the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

Table 111: nv212iyuv Function Resource Utilization Summary

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	1	1377	730	219
8 pixel	150	0	1	1975	1012	279

### Performance Estimate

The following table summarizes the performance of NV21 to IYUV for different configurations, as generated using the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 112: nv212iyuv Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

### NV21 to RGBA

The `nv212rgba` function converts a NV21 image format to a 4-channel RGBA image. The inputs to the function are separate Y and VU planes. NV21 holds sub sampled data, Yplane is sampled at unit rate and 1 U and 1V value each for every 2x2 Yvalues. To generate the RGBA data, each U and V value is duplicated (2x2) times.

### API Syntax

```
template<int SRC_T, int UV_T, int DST_T, int ROWS, int COLS, int NPC=1>
void nv212rgba(xf::Mat<SRC_T, ROWS, COLS, NPC> & src_y, xf::Mat<UV_T,
ROWS/2, COLS/2, NPC> & src_uv,xf::Mat<DST_T, ROWS, COLS, NPC> & _dst0)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 113: nv212rgba Function Parameter Descriptions

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Input pixel type. Only 8-bit, unsigned, 2-channel is supported (XF_8UC2).
DST_T	Output pixel type. Only 8-bit, unsigned, 4-channel is supported (XF_8UC4).

Table 113: **nv212rgba Function Parameter Descriptions (cont'd)**

Parameter	Description
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src_y	Input Y plane of size (ROWS, COLS).
src_uv	Input UV plane of size (ROWS/2, COLS/2).
_dst0	Output RGBA image of size (ROWS, COLS).

### Resource Utilization

The following table summarizes the resource utilization of NV21 to RGBA for different configurations, as generated in the Vivado HLS 2018.2 version tool for the Xilinx Xcзу9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

 Table 114: **nv212rgba Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	2	5	1170	673	183

### Performance Estimate

The following table summarizes the performance of NV12 to RGBA for different configurations, as generated using the Vivado HLS 2018.2 version tool for the Xilinx Xcзу9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

 Table 115: **nv212rgba Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9

### NV21 to YUV4

The `nv212yuv4` function converts an image in the NV21 format to a YUV444 format. The function outputs separate U and V planes. Y plane is same for both formats. The UV planes are duplicated 2x2 times to represent one U plane and V plane of YUV444 format.

## API Syntax

```
template<int SRC_T, int UV_T, int ROWS, int COLS, int NPC=1,int NPC_UV=1>
void nv212yuv4(xf::Mat<SRC_T, ROWS, COLS, NPC> & src_y, xf::Mat<UV_T,
ROWS/2, COLS/2, NPC_UV> & src_uv, xf::Mat<SRC_T, ROWS, COLS, NPC> &
_y_image, xf::Mat<SRC_T, ROWS, COLS, NPC> & _u_image, xf::Mat<SRC_T, ROWS,
COLS, NPC> & _v_image)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 116: nv212yuv4 Function Parameter Descriptions**

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
UV_T	Input pixel type. Only 8-bit, unsigned, 2-channel is supported (XF_8UC2).
ROWS	Maximum height of input and output image (must be a multiple of 8).
COLS	Maximum width of input and output image (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
NPC_UV	Number of UV image Pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC4 for 1 pixel and 4-pixel operations respectively.
src_y	Input Y plane of size (ROWS, COLS).
src_uv	Input UV plane of size (ROWS/2, COLS/2).
_y_image	Output Y plane of size (ROWS, COLS).
_u_image	Output U plane of size (ROWS, COLS).
_v_image	Output V plane of size (ROWS, COLS).

## Resource Utilization

The following table summarizes the resource utilization of NV21 to YUV4 for different configurations, as generated in the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a HD (1080x1920) image.

**Table 117: nv212yuv4 Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	1383	817	233
8 pixel	150	0	0	1887	1087	287

## Performance Estimate

The following table summarizes the performance of NV21 to YUV4 for different configurations, as generated using the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 118: **nv21yuv4 Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	13.8
8 pixel operation (150 MHz)	3.5

## Color Thresholding

The `colorthresholding` function compares the color space values of the source image with low and high threshold values, and returns either 255 or 0 as the output.

### API Syntax

```
template<int SRC_T,int DST_T,int MAXCOLORS, int ROWS, int COLS,int NPC>
    void colorthresholding(xf::Mat<SRC_T, ROWS, COLS, NPC> &
        _src_mat,xf::Mat<DST_T, ROWS, COLS, NPC> & _dst_mat,unsigned char
        low_thresh[MAXCOLORS*3], unsigned char high_thresh[MAXCOLORS*3])
```

### Parameter Descriptions

The table below describes the template and the function parameters.

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 4 channel is supported (XF_8UC4)
DST_T	Output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
MAXCOLORS	Maximum number of color values
ROWS	Maximum height of input and output image
COLS	Maximum width of input and output image
NPC	Number of pixels to be processed per cycle. Only XF_NPPC1 supported.
_src_mat	Input image
_dst_mat	Thresholded image
low_thresh	Lowest threshold values for the colors
high_thresh	Highest threshold values for the colors

## Custom Convolution

The `filter2D` function performs convolution over an image using a user-defined kernel.

Convolution is a mathematical operation on two functions  $f$  and  $g$ , producing a third function. The third function is typically viewed as a modified version of one of the original functions, that gives the area overlap between the two functions to an extent that one of the original functions is translated.

The filter can be unity gain filter or a non-unity gain filter. The filter must be of type AU\_16SP. If the co-efficients are floating point, it must be converted into the Qm.n and provided as the input as well as the shift parameter has to be set with the 'n' value. Else, if the input is not of floating point, the filter is provided directly and the shift parameter is set to zero.

### API Syntax

```
template<int BORDER_TYPE,int FILTER_WIDTH,int FILTER_HEIGHT, int SRC_T,int
DST_T, int ROWS, int COLS,int NPC=1>
void filter2D(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat,xf::Mat<DST_T,
ROWS, COLS, NPC> & _dst_mat,short int
filter[FILTER_HEIGHT*FILTER_WIDTH],unsigned char _shift)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 119: filter2D Function Parameter Descriptions**

Parameter	Description
BORDER_TYPE	Border Type supported is XF_BORDER_CONSTANT
FILTER_HEIGHT	Number of rows in the input filter
FILTER_WIDTH	Number of columns in the input filter
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
DST_T	Output pixel type.8-bit unsigned single channel (XF_8UC1) and 16-bit signed single channel (XF_16SC1) supported.
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_mat	Input image
_dst_mat	Output image
filter	The input filter of any size, provided the dimensions should be an odd number. The filter co-efficients either a 16-bit value or a 16-bit fixed point equivalent value.
_shift	The filter must be of type XF_16SP. If the co-efficients are floating point, it must be converted into the Qm.n and provided as the input as well as the shift parameter has to be set with the 'n' value. Else, if the input is not of floating point, the filter is provided directly and the shift parameter is set to zero.



## Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

*Table 120: filter2D Function Resource Utilization Summary*

Operating Mode	Filter Size	Operating Frequency (MHz)	Utilization Estimate				
			BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	3x3	300	3	9	1701	1161	269
	5x5	300	5	25	3115	2144	524
8 pixel	3x3	150	6	72	2783	2768	638
	5x5	150	10	216	3020	4443	1007

## Performance Estimate

The following table summarizes the performance of the kernel in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

*Table 121: filter2D Function Performance Estimate Summary*

Operating Mode	Operating Frequency (MHz)	Filter Size	Latency Estimate
			Max (ms)
1 pixel	300	3x3	7
	300	5x5	7.1
8 pixel	150	3x3	1.86
	150	5x5	1.86

## Delay

In image processing pipelines, it is possible that the inputs to a function with FIFO interfaces are not synchronized. That is, the first data packet for first input might arrive a finite number of clock cycles after the first data packet of the second input. If the function has FIFOs at its interface with insufficient depth, this causes the whole design to stall on hardware. To synchronize the inputs, we provide this function to delay the input packet that arrives early, by a finite number of clock cycles.

## API Syntax

```
template<int MAXDELAY, int SRC_T, int ROWS, int COLS, int NPC=1 >
    void delayMat(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src,
        xf::Mat<SRC_T, ROWS, COLS, NPC> & _dst)
```

## Parameter Descriptions

The table below describes the template and the function parameters.

Parameter	Description
SRC_T	Input and output pixel type
ROWS	Maximum height of input and output image (must be multiple of 8)
COLS	Maximum width of input and output image (must be multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
MAXDELAY	Maximum delay that the function is to be instantiated for.
_src	Input image
_dst	Output image

## Dilate

During a dilation operation, the current pixel intensity is replaced by the maximum value of the intensity in a 3x3 neighborhood of the current pixel.

$$dst(x, y) = \max_{\substack{x-1 \leq x' \leq x+1 \\ y-1 \leq y' \leq y+1}} src(x', y')$$

## API Syntax

```
template<int BORDER_TYPE, int SRC_T, int ROWS, int COLS, int NPC=1>
    void dilate(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat, xf::Mat<SRC_T,
        ROWS, COLS, NPC> & _dst_mat)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 122: dilate Function Parameter Descriptions**

Parameter	Description
BORDER_TYPE	Border Type supported is XF_BORDER_CONSTANT

Table 122: dilate Function Parameter Descriptions (cont'd)

Parameter	Description
SRC_T	Input and output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_mat	Input image
_dst_mat	Output image

### Resource Utilization

The following table summarizes the resource utilization of the Dilation function for 1 pixel operation and 8 pixel operation, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

Table 123: dilate Function Resource Utilization Summary

Name	Resource Utilization	
	1 pixel per clock operation	8 pixel per clock operation
	300 MHz	150 MHz
BRAM_18K	3	6
DSP48E	0	0
FF	339	644
LUT	350	1325
CLB	81	245

### Performance Estimate

The following table summarizes a performance estimate of the Dilation function for Normal Operation (1 pixel) and Resource Optimized (8 pixel) configurations, generated using Vivado HLS 2018.2 tool for Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

Table 124: dilate Function Performance Estimate Summary

Operating Mode	Latency Estimate	
	Min (ms)	Max (ms)
1 pixel (300 MHz)	7.0	7.0
8 pixel (150 MHz)	1.87	1.87

## Duplicate

When various functions in a pipeline are implemented by a programmable logic, FIFOs are instantiated between two functions for dataflow processing. When the output from one function is consumed by two functions in a pipeline, the FIFOs need to be duplicated. This function facilitates the duplication process of the FIFOs.

### API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1>
    void duplicateMat(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src,
                    xf::Mat<SRC_T, ROWS, COLS, NPC> & _dst1, xf::Mat<SRC_T, ROWS, COLS, NPC> &
                    _dst2)
```

### Parameter Descriptions

The table below describes the template and the function parameters.

Parameter	Description
SRC_T	Input and output pixel type
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle. Possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input image
_dst1	Duplicate output for _src
_dst2	Duplicate output for _src

## Erode

The `erode` function finds the minimum pixel intensity in the 3x3 neighborhood of a pixel and replaces the pixel intensity with the minimum value.

$$dst(x, y) = \min_{\substack{x-1 \leq x' \leq x+1 \\ y-1 \leq y' \leq y+1}} src(x', y')$$

### API Syntax

```
template<int BORDER_TYPE, int SRC_T, int ROWS, int COLS, int NPC=1>
    void erode(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat, xf::Mat<SRC_T,
    ROWS, COLS, NPC> & _dst_mat)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 125: erode Function Parameter Descriptions**

Parameter	Description
BORDER_TYPE	Border type supported is XF_BORDER_CONSTANT
SRC_T	Input and output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_mat	Input image
_dst_mat	Output image

## Resource Utilization

The following table summarizes the resource utilization of the Erosion function generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

**Table 126: erode Function Resource Utilization Summary**

Name	Resource Utilization	
	1 pixel per clock operation	8 pixel per clock operation
	300 MHz	150 MHz
BRAM_18K	3	6
DSP48E	0	0
FF	342	653
LUT	351	1316
CLB	79	230

## Performance Estimate

The following table summarizes a performance estimate of the Erosion function for Normal Operation (1 pixel) and Resource Optimized (8 pixel) configurations, generated using Vivado HLS 2018.2 tool for Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

**Table 127: erode Function Performance Estimate Summary**

Operating Mode	Latency Estimate	
	Min (ms)	Max (ms)
1 pixel (300 MHz)	7.0	7.0
8 pixel (150 MHz)	1.85	1.85

## FAST Corner Detection

Features from accelerated segment test (FAST) is a corner detection algorithm, that is faster than most of the other feature detectors.

The `fast` function picks up a pixel in the image and compares the intensity of 16 pixels in its neighborhood on a circle, called the Bresenham's circle. If the intensity of 9 contiguous pixels is found to be either more than or less than that of the candidate pixel by a given threshold, then the pixel is declared as a corner. Once the corners are detected, the non-maximal suppression is applied to remove the weaker corners.

This function can be used for both still images and videos. The corners are marked in the image. If the corner is found in a particular location, that location is marked with 255, otherwise it is zero.

### API Syntax

```
template<int NMS,int SRC_T,int ROWS, int COLS,int NPC=1>
void fast(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat,xf::Mat<SRC_T, ROWS,
COLS, NPC> & _dst_mat,unsigned char _threshold)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 128: fast Function Parameter Descriptions*

Parameter	Description
NMS	If NMS == 1, non-maximum suppression is applied to detected corners (keypoints). The value should be 0 or 1.
SRC_T	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1)
ROWS	Maximum height of input image (must be a multiple of 8)
COLS	Maximum width of input image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_mat	Input image
_dst_mat	Output image. The corners are marked in the image.
_threshold	Threshold on the intensity difference between the center pixel and its neighbors. Usually it is taken around 20.

### Resource Utilization

The following table summarizes the resource utilization of the kernel for different configurations, generated using Vivado HLS 2018.2 for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image with NMS.

Table 129: fast Function Resource Utilization Summary

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	10	20
DSP48E	0	0
FF	2695	7310
LUT	3792	20956
CLB	769	3519

### Performance Estimate

The following table summarizes the performance of kernel for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image with non-maximum suppression (NMS).

Table 130: fast Function Performance Estimate Summary

Operating Mode	Operating Frequency (MHz)	Filter Size	Latency Estimate
			Max (ms)
1 pixel	300	3x3	7
8 pixel	150	3x3	1.86

## Gaussian Filter

The `GaussianBlur` function applies Gaussian blur on the input image. Gaussian filtering is done by convolving each point in the input image with a Gaussian kernel.

$$G_0(x, y) = e^{-\frac{(x - \mu_x)^2}{2\sigma_x^2} - \frac{(y - \mu_y)^2}{2\sigma_y^2}}$$

Where  $\mu_x, \mu_y$  are the mean values and  $\sigma_x, \sigma_y$  are the variances in x and y directions respectively. In the `GaussianBlur` function, values of  $\mu_x, \mu_y$  are considered as zeroes and the values of  $\sigma_x, \sigma_y$  are equal.

## API Syntax

```
template<int FILTER_SIZE, int BORDER_TYPE, int SRC_T, int ROWS, int COLS,
int NPC = 1>
void GaussianBlur(xf::Mat<SRC_T, ROWS, COLS, NPC> & src, xf::Mat<SRC_T,
ROWS, COLS, NPC> & dst, float sigma)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 131: GaussianBlur Function Parameter Descriptions**

Parameter	Description
FILTER_SIZE	Filter size. Filter size of 3 (XF_FILTER_3X3), 5 (XF_FILTER_5X5) and 7 (XF_FILTER_7X7) are supported.
BORDER_TYPE	Border type supported is XF_BORDER_CONSTANT
SRC_T	Input and output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible values are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src	Input image
dst	Output image
sigma	Standard deviation of Gaussian filter

## Resource Utilization

The following table summarizes the resource utilization of the Gaussian Filter in different configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to progress a grayscale HD (1080x1920) image.

**Table 132: GaussianBlur Function Resource Utilization Summary**

Operating Mode	Filter Size	Operating Frequency (MHz)	Utilization Estimate				
			BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	3x3	300	3	17	3641	2791	610
	5x5	300	5	27	4461	3544	764
	7x7	250	7	35	4770	4201	894
8 pixel	3x3	150	6	52	3939	3784	814
	5x5	150	10	111	5688	5639	1133
	7x7	150	14	175	7594	7278	1518



## Performance Estimate

The following table summarizes a performance estimate of the Gaussian Filter in different configurations, as generated using Vivado HLS 2018.2 tool for Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

Table 133: GaussianBlur Function Performance Estimate Summary

Operating Mode	Filter Size	Latency Estimate
		Max Latency (ms)
1 pixel operation (300 MHz)	3x3	7.01
	5x5	7.03
	7x7	7.06
8 pixel operation (150 MHz)	3x3	1.6
	5x5	1.7
	7x7	1.74

## Gradient Magnitude

The `magnitude` function computes the magnitude for the images. The input images are x-gradient and y-gradient images of type 16S. The output image is of same type as the input image.

For L1NORM normalization, the magnitude computed image is the pixel-wise added image of absolute of x-gradient and y-gradient, as shown below:

$$g = |g_x| + |g_y|$$

For L2NORM normalization, the magnitude computed image is as follows:

$$g = \sqrt{(g_x^2 + g_y^2)}$$

## API Syntax

```
template< int NORM_TYPE ,int SRC_T,int DST_T, int ROWS, int COLS,int NPC=1>
void magnitude(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_matx,xf::Mat<DST_T,
ROWS, COLS, NPC> & _src_maty,xf::Mat<DST_T, ROWS, COLS, NPC> & _dst_mat)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 134: magnitude Function Parameter Descriptions**

Parameter	Description
NORM_TYPE	Normalization type can be either L1 or L2 norm. Values are XF_L1NORM or XF_L2NORM
SRC_T	Input pixel type. Only 16-bit, signed, 1 channel is supported (XF_16SC1)
DST_T	Output pixel type. Only 16-bit, signed, 1 channel is supported (XF_16SC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible values are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_matx	First input, x-gradient image.
_src_maty	Second input, y-gradient image.
_dst_mat	Output, magnitude computed image.

### Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image and for L2 normalization.

**Table 135: magnitude Function Resource Utilization Summary**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	0	0
DSP48E	2	16
FF	707	2002
LUT	774	3666
CLB	172	737

### Performance Estimate

The following table summarizes the performance of the kernel in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image and for L2 normalization.

**Table 136: magnitude Function Performance Estimate Summary**

Operating Mode	Operating Frequency (MHz)	Latency Estimate
		Max (ms)
1 pixel	300	7.2
8 pixel	150	1.7

## Gradient Phase

The `phase` function computes the polar angles of two images. The input images are x-gradient and y-gradient images of type 16S. The output image is of same type as the input image.

For radians:

$$\text{angle}(x, y) = \text{atan2}(g_y, g_x)$$

For degrees:

$$\text{angle}(x, y) = \text{atan2}(g_y, g_x) * \frac{180}{\pi}$$

### API Syntax

```
template<int RET_TYPE ,int SRC_T,int DST_T, int ROWS, int COLS,int NPC=1 >
void phase(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_matx,xf::Mat<DST_T,
ROWS, COLS, NPC> & _src_maty,xf::Mat<DST_T, ROWS, COLS, NPC> & _dst_mat)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 137: phase Function Parameter Descriptions**

Parameter	Description
RET_TYPE	Output format can be either in radians or degrees. Options are XF_RADIANS or XF_DEGREES. <ul style="list-style-type: none"> <li>If the XF_RADIANS option is selected, phase API will return result in Q4.12 format. The output range is (0, 2 pi)</li> <li>If the XF_DEGREES option is selected, xFphaseAPI will return result in Q10.6 degrees and output range is (0, 360)</li> </ul>
SRC_T	Input pixel type. Only 16-bit, signed, 1 channel is supported (XF_16SC1)
DST_T	Output pixel type. Only 16-bit, signed, 1 channel is supported (XF_16SC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_matx	First input, x-gradient image.
_src_maty	Second input, y-gradient image.
_dst_mat	Output, phase computed image.

## Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

**Table 138: phase Function Resource Utilization Summary**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	6	24
DSP48E	6	19
FF	873	2396
LUT	753	3895
CLB	185	832

## Performance Estimate

The following table summarizes the performance of the kernel in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

**Table 139: phase Function Performance Estimate Summary**

Operating Mode	Operating Frequency (MHz)	Latency Estimate (ms)
1 pixel	300	7.2
8 pixel	150	1.7

## Deviation from OpenCV

In phase implementation, the output is returned in a fixed point format. If XF\_RADIANS option is selected, phase API will return result in Q4.12 format. The output range is (0, 2 pi). If XF\_DEGREES option is selected, phase API will return result in Q10.6 degrees and output range is (0, 360);

## Harris Corner Detection

In order to understand Harris Corner Detection, let us consider a grayscale image. Sweep a window  $w(x, y)$  (with displacements  $u$  in the x-direction and  $v$  in the y-direction),  $I$  calculates the variation of intensity  $w(x, y)$ .

$$E(u, v) = \sum w(x, y)[I(x + u, y + v) - I(x, y)]^2$$

Where:

- $w(x, y)$  is the window position at  $(x, y)$
- $I(x, y)$  is the intensity at  $(x, y)$
- $I(x + u, y + v)$  is the intensity at the moved window  $(x + u, y + v)$ .

Since we are looking for windows with corners, we are looking for windows with a large variation in intensity. Hence, we have to maximize the equation above, specifically the term:

$$[I(x + u, y + v) - I(x, y)]^2$$

Using Taylor expansion:

$$E(u, v) = \sum [I(x, y) + uI_x + vI_y - I(x, y)]^2$$

Expanding the equation and cancelling  $I(x, y)$  with  $-I(x, y)$ :

$$E(u, v) = \sum u^2 I_x^2 + 2uv I_x I_y + v^2 I_y^2$$

The above equation can be expressed in a matrix form as:

$$E(u, v) = [u \ v] \left( \sum w(x, y) \begin{bmatrix} I_x^2 & I_x I_y \\ I_x I_y & I_y^2 \end{bmatrix} \right) \begin{bmatrix} u \\ v \end{bmatrix}$$

So, our equation is now:

$$E(u, v) = [u \ v] M \begin{bmatrix} u \\ v \end{bmatrix}$$

A score is calculated for each window, to determine if it can possibly contain a corner:

$$R = \det(M) - k(\text{trace}(M))^2$$

Where,

- $\det(M) = \lambda_1 \lambda_2$
- $\text{trace}(M) = \lambda_1 + \lambda_2$

Non-Maximum Suppression:

In non-maximum suppression (NMS) if radius = 1, then the bounding box is  $2*r+1 = 3$ .

In this case, consider a 3x3 neighborhood across the center pixel. If the center pixel is greater than the surrounding pixel, then it is considered a corner. The comparison is made with the surrounding pixels, which are within the radius.

Radius = 1

x-1, y-1	x-1, y	x-1, y+1
x, y-1	x, y	x, y+1
x+1, y-1	x+1, y	x+1, y+1

Threshold:

A threshold=442, 3109 and 566 is used for 3x3, 5x5, and 7x7 filters respectively. This threshold is verified over 40 sets of images. The threshold can be varied, based on the application. The corners are marked in the output image. If the corner is found in a particular location, that location is marked with 255, otherwise it is zero.

## API Syntax

```
template<int FILTERSIZE, int BLOCKWIDTH, int NMSRADIUS, int SRC_T, int ROWS,
int COLS, int NPC=1>
void cornerHarris(xf::Mat<SRC_T, ROWS, COLS, NPC> & src, xf::Mat<SRC_T,
ROWS, COLS, NPC> & dst, uint16_t threshold, uint16_t k)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 140: cornerHarris Function Parameter Descriptions**

Parameter	Description
FILTERSIZE	Size of the Sobel filter. 3, 5, and 7 supported.
BLOCKWIDTH	Size of the box filter. 3, 5, and 7 supported.
NMSRADIUS	Radius considered for non-maximum suppression. Values supported are 1 and 2.
TYPE	Input pixel type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1)
ROWS	Maximum height of input image (must be a multiple of 8)
COLS	Maximum width of input image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src	Input image
dst	Output image.
threshold	Threshold applied to the corner measure.
k	Harris detector parameter

## Resource Utilization

The following table summarizes the resource utilization of the Harris corner detection in different configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

The following table summarizes the resource utilization for Sobel Filter = 3, Box filter=3 and NMS\_RADIUS =1

**Table 141: Resource Utilization Summary - For Sobel Filter = 3, Box filter=3 and NMS\_RADIUS =1**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	33	66
DSP48E	10	80
FF	3254	9330
LUT	3522	13222
CLB	731	2568

The following table summarizes the resource utilization for Sobel Filter = 3, Box filter=5 and NMS\_RADIUS =1

**Table 142: Resource Utilization Summary - Sobel Filter = 3, Box filter=5 and NMS\_RADIUS =1**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	45	90
DSP48E	10	80
FF	5455	12459
LUT	5675	24594
CLB	1132	4498

The following table summarizes the resource utilization for Sobel Filter = 3, Box filter=7 and NMS\_RADIUS =1

**Table 143: Resource Utilization Summary - Sobel Filter = 3, Box filter=7 and NMS\_RADIUS =1**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	57	114
DSP48E	10	80
FF	8783	16593
LUT	9157	39813
CLB	1757	6809

The following table summarizes the resource utilization for Sobel Filter = 5, Box filter=3 and NMS\_RADIUS =1

**Table 144: Resource Utilization Summary - Sobel Filter = 5, Box filter=3 and NMS\_RADIUS =1**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	200 MHz
BRAM_18K	35	70
DSP48E	10	80
FF	4656	11659
LUT	4681	17394
CLB	1005	3277

The following table summarizes the resource utilization for Sobel Filter = 5, Box filter=5 and NMS\_RADIUS =1

**Table 145: Resource Utilization Summary - Sobel Filter = 5, Box filter=5 and NMS\_RADIUS =1**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	47	94
DSP48E	10	80
FF	6019	14776
LUT	6337	28795
CLB	1353	5102



The following table summarizes the resource utilization for Sobel Filter = 5, Box filter=7 and NMS\_RADIUS =1

**Table 146: Resource Utilization Summary - Sobel Filter = 5, Box filter=7 and NMS\_RADIUS =1**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	59	118
DSP48E	10	80
FF	9388	18913
LUT	9414	43070
CLB	1947	7508

The following table summarizes the resource utilization for Sobel Filter = 7, Box filter=3 and NMS\_RADIUS =1

**Table 147: Resource Utilization Summary - Sobel Filter = 7, Box filter=3 and NMS\_RADIUS =1**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	37	74
DSP48E	11	88
FF	6002	13880
LUT	6337	25573
CLB	1327	4868

The following table summarizes the resource utilization for Sobel Filter = 7, Box filter=5 and NMS\_RADIUS =1

**Table 148: Resource Utilization Summary - Sobel Filter = 7, Box filter=5 and NMS\_RADIUS =1**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	49	98
DSP48E	11	88
FF	7410	17049
LUT	8076	36509

**Table 148: Resource Utilization Summary - Sobel Filter = 7, Box filter=5 and NMS\_RADIUS =1 (cont'd)**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
CLB	1627	6518

The following table summarizes the resource utilization for Sobel Filter = 7, Box filter=7 and NMS\_RADIUS =1

**Table 149: Resource Utilization Summary - Sobel Filter = 7, Box filter=7 and NMS\_RADIUS =1**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	61	122
DSP48E	11	88
FF	10714	21137
LUT	11500	51331
CLB	2261	8863

The following table summarizes the resource utilization for Sobel Filter = 3, Box filter=3 and NMS\_RADIUS =2

**Table 150: Resource Utilization Summary - Sobel Filter = 3, Box filter=3 and NMS\_RADIUS =2**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	41	82
DSP48E	10	80
FF	5519	10714
LUT	5094	16930
CLB	1076	3127

Resource utilization: For Sobel Filter = 3, Box filter=5 and NMS\_RADIUS =2

**Table 151: Resource Utilization Summary**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	53	106
DSP48E	10	80
FF	6798	13844
LUT	6866	28286
CLB	1383	4965

The following table summarizes the resource utilization for Sobel Filter = 3, Box filter=7 and NMS\_RADIUS =2

**Table 152: Resource Utilization Summary - Sobel Filter = 3, Box filter=7 and NMS\_RADIUS =2**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	65	130
DSP48E	10	80
FF	10137	17977
LUT	10366	43589
CLB	1940	7440

The following table summarizes the resource utilization for Sobel Filter = 5, Box filter=3 and NMS\_RADIUS =2

**Table 153: Resource Utilization Summary - Sobel Filter = 5, Box filter=3 and NMS\_RADIUS =2**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	43	86
DSP48E	10	80
FF	5957	12930
LUT	5987	21187
CLB	1244	3922

The following table summarizes the resource utilization for Sobel Filter = 5, Box filter=5 and NMS\_RADIUS =2

**Table 154: Resource Utilization Summary - Sobel Filter = 5, Box filter=5 and NMS\_RADIUS =2**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	55	110
DSP48E	10	80
FF	5442	16053
LUT	6561	32377
CLB	1374	5871

The following table summarizes the resource utilization for Sobel Filter = 5, Box filter=7 and NMS\_RADIUS =2

**Table 155: Resource Utilization Summary - Sobel Filter = 5, Box filter=7 and NMS\_RADIUS =2**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	67	134
DSP48E	10	80
FF	10673	20190
LUT	10793	46785
CLB	2260	8013

The following table summarizes the resource utilization for Sobel Filter = 7, Box filter=3 and NMS\_RADIUS =2

**Table 156: Resource Utilization Summary - Sobel Filter = 7, Box filter=3 and NMS\_RADIUS =2**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	45	90
DSP48E	11	88
FF	7341	15161
LUT	7631	29185
CLB	1557	5425

The following table summarizes the resource utilization for Sobel Filter = 7, Box filter=5 and NMS\_RADIUS =2

**Table 157: Resource Utilization Summary - Sobel Filter = 7, Box filter=5 and NMS\_RADIUS =2**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	57	114
DSP48E	11	88
FF	8763	18330
LUT	9368	40116
CLB	1857	7362

The following table summarizes the resource utilization for Sobel Filter = 7, Box filter=7 and NMS\_RADIUS =2

**Table 158: Resource Utilization Summary - Sobel Filter = 7, Box filter=7 and NMS\_RADIUS =2**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	69	138
DSP48E	11	88
FF	12078	22414
LUT	12831	54652
CLB	2499	9628

### Performance Estimate

The following table summarizes a performance estimate of the Harris corner detection in different configurations, as generated using Vivado HLS 2018.2 tool for Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

**Table 159: cornerHarris Function Performance Estimate Summary**

Operating Mode	Operating Frequency (MHz)	Configuration			Latency Estimate
		Sobel	Box	NMS Radius	Latency(In ms)
1 pixel	300 MHz	3	3	1	7
1 pixel	300 MHz	3	5	1	7.1

Table 159: cornerHarris Function Performance Estimate Summary (cont'd)

Operating Mode	Operating Frequency (MHz)	Configuration			Latency Estimate
		Sobel	Box	NMS Radius	Latency(In ms)
1 pixel	300 MHz	3	7	1	7.1
1 pixel	300 MHz	5	3	1	7.2
1 pixel	300 MHz	5	5	1	7.2
1 pixel	300 MHz	5	7	1	7.2
1 pixel	300 MHz	7	3	1	7.22
1 pixel	300 MHz	7	5	1	7.22
1 pixel	300 MHz	7	7	1	7.22
8 pixel	150 MHz	3	3	1	1.7
8 pixel	150 MHz	3	5	1	1.7
8 pixel	150 MHz	3	7	1	1.7
8 pixel	150 MHz	5	3	1	1.71
8 pixel	150 MHz	5	5	1	1.71
8 pixel	150 MHz	5	7	1	1.71
8 pixel	150 MHz	7	3	1	1.8
8 pixel	150 MHz	7	5	1	1.8
8 pixel	150 MHz	7	7	1	1.8
1 pixel	300 MHz	3	3	2	7.1
1 pixel	300 MHz	3	5	2	7.1
1 pixel	300 MHz	3	7	2	7.1
1 pixel	300 MHz	5	3	2	7.21
1 pixel	300 MHz	5	5	2	7.21
1 pixel	300 MHz	5	7	2	7.21
1 pixel	300 MHz	7	3	2	7.22
1 pixel	300 MHz	7	5	2	7.22
1 pixel	300 MHz	7	7	2	7.22
8 pixel	150 MHz	3	3	2	1.8
8 pixel	150 MHz	3	5	2	1.8
8 pixel	150 MHz	3	7	2	1.8
8 pixel	150 MHz	5	3	2	1.81
8 pixel	150 MHz	5	5	2	1.81
8 pixel	150 MHz	5	7	2	1.81
8 pixel	150 MHz	7	3	2	1.9
8 pixel	150 MHz	7	5	2	1.91
8 pixel	150 MHz	7	7	2	1.92

## Deviation from OpenCV

In xfOpenCV thresholding and NMS are included, but in OpenCV they are not included. In xfOpenCV, all the blocks are implemented in fixed point. Whereas, in OpenCV, all the blocks are implemented in floating point.

## Histogram Computation

The `calcHist` function computes the histogram of given input image.

$$H[src(x, y)] = H[src(x, y)] + 1$$

Where, H is the array of 256 elements.

### API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1>
void calcHist(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, uint32_t *histogram)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 160: calcHist Function Parameter Descriptions*

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle
_src	Input image
histogram	Output array of 256 elements

### Resource Utilization

The following table summarizes the resource utilization of the `calcHist` function for Normal Operation (1 pixel) and Resource Optimized (8 pixel) configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA at 300 MHz for 1 pixel case and at 150 MHz for 8 pixel mode.

*Table 161: calcHist Function Resource Utilization Summary*

Name	Resource Utilization	
	Normal Operation (1 pixel)	Resource Optimized (8 pixel)
BRAM_18K	2	16

Table 161: **calcHist Function Resource Utilization Summary (cont'd)**

Name	Resource Utilization	
	Normal Operation (1 pixel)	Resource Optimized (8 pixel)
DSP48E	0	0
FF	196	274
LUT	240	912
CLB	57	231

### Performance Estimate

The following table summarizes a performance estimate of the calcHist function for Normal Operation (1 pixel) and Resource Optimized (8 pixel) configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA at 300 MHz for 1 pixel and 150 MHz for 8 pixel mode.

 Table 162: **calcHist Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max (ms)
1 pixel	6.9
8 pixel	1.7

## Histogram Equalization

The `equalizeHist` function performs histogram equalization on input image or video. It improves the contrast in the image, to stretch out the intensity range. This function maps one distribution (histogram) to another distribution (a wider and more uniform distribution of intensity values), so the intensities are spread over the whole range.

For histogram  $H[i]$ , the cumulative distribution  $H'[i]$  is given as:

$$H'[i] = \sum_{0 \leq j < i} H[j]$$

The intensities in the equalized image are computed as:

$$dst(x, y) = H'(src(x, y))$$



## API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC = 1>
void equalizeHist(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, xf::Mat<SRC_T,
ROWS, COLS, NPC> & _src1, xf::Mat<SRC_T, ROWS, COLS, NPC> & _dst)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 163: equalizeHist Function Parameter Descriptions**

Parameter	Description
SRC_T	Input and output pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle
_src	Input image
_src1	Input image
_dst	Output image

## Resource Utilization

The following table summarizes the resource utilization of the equalizeHist function for Normal Operation (1 pixel) and Resource Optimized (8 pixel) configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA at 300 MHz for 1 pixel and 150 MHz for 8 pixel mode.

**Table 164: equalizeHist Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	4	5	3492	1807	666
8 pixel	150	25	5	3526	2645	835

## Performance Estimate

The following table summarizes a performance estimate of the equalizeHist function for Normal Operation (1 pixel) and Resource Optimized (8 pixel) configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA at 300 MHz for 1 pixel and 150 MHz for 8 pixel mode.

Table 165: **equalizeHist** Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max (ms)
1 pixel per clock operation	13.8
8 pixel per clock operation	3.4

## HOG

The histogram of oriented gradients (HOG) is a feature descriptor used in computer vision for the purpose of object detection. The feature descriptors produced from this approach is widely used in the pedestrian detection.

The technique counts the occurrences of gradient orientation in localized portions of an image. HOG is computed over a dense grid of uniformly spaced cells and normalized over overlapping blocks, for improved accuracy. The concept behind HOG is that the object appearance and shape within an image can be described by the distribution of intensity gradients or edge direction.

Both RGB and gray inputs are accepted to the function. In the RGB mode, gradients are computed for each plane separately, but the one with the higher magnitude is selected. With the configurations provided, the window dimensions are 64x128, block dimensions are 16x16.

### API Syntax

```
template<int WIN_HEIGHT, int WIN_WIDTH, int WIN_STRIDE, int BLOCK_HEIGHT,
int BLOCK_WIDTH, int CELL_HEIGHT, int CELL_WIDTH, int NOB, int DESC_SIZE,
int IMG_COLOR, int OUTPUT_VARIANT, int SRC_T, int DST_T, int ROWS, int
COLS, int NPC = XE_NPPC1>
void HOGDescriptor(xf::Mat<SRC_T, ROWS, COLS, NPC> &_in_mat,
xf::Mat<DST_T, 1, DESC_SIZE, NPC> &_desc_mat);
```

### Parameter Descriptions

The following table describes the template parameters.

 Table 166: **HOGDescriptor** Template Parameter Descriptions

PARAMETERS	DESCRIPTION
WIN_HEIGHT	The number of pixel rows in the window. This must be a multiple of 8 and should not exceed the number of image rows.
WIN_WIDTH	The number of pixel cols in the window. This must be a multiple of 8 and should not exceed the number of image columns.
WIN_STRIDE	The pixel stride between two adjacent windows. It is fixed at 8.
BLOCK_HEIGHT	Height of the block. It is fixed at 16.
BLOCK_WIDTH	Width of the block. It is fixed at 16.
CELL_HEIGHT	Number of rows in a cell. It is fixed at 8.

Table 166: HOGDescriptor Template Parameter Descriptions (cont'd)

PARAMETERS	DESCRIPTION
CELL_WIDTH	Number of cols in a cell. It is fixed at 8.
NOB	Number of histogram bins for a cell. It is fixed at 9
DESC_SIZE	The size of the output descriptor.
IMG_COLOR	The type of the image, set as either XF_GRAY or XF_RGB
OUTPUT_VARIANT	Must be either XF_HOG_RB or XF_HOG_NRB
SRC_T	Input pixel type. Must be either XF_8UC1 or XF_8UC4, for gray and color respectively.
DST_T	Output descriptor type. Must be XF_32UC1.
ROWS	Number of rows in the image being processed. (Should be a multiple of 8)
COLS	Number of columns in the image being processed. (Should be a multiple of 8)
NPC	Number of pixels to be processed per cycle; this function supports only XF_NPPC1 or 1 pixel per cycle operations.

The following table describes the function parameters.

Table 167: HOGDescriptor Function Parameter Descriptions

PARAMETERS	DESCRIPTION
_in_mat	Input image, of xf::Mat type
_desc_mat	Output descriptors, of xf::Mat type

Where,

- NO is normal operation (single pixel processing)
- RB is repetitive blocks (descriptor data are written window wise)
- NRB is non-repetitive blocks (descriptor data are written block wise, in order to reduce the number of writes).

**Note:** In the RB mode, the block data is written to the memory taking the overlap windows into consideration. In the NRB mode, the block data is written directly to the output stream without consideration of the window overlap. In the host side, the overlap must be taken care.

### Resource Utilization

The following table shows the resource utilization of HOGDescriptor function for normal operation (1 pixel) mode as generated in Vivado HLS 2018.2 version tool for the part Xilinx Xczu9eg-ffvb1156-1-i-es1 at 300 MHz to process an image of 1920x1080 resolution.

**Table 168: HOGDescriptor Function Resource Utilization Summary**

Resource	Utilization (at 300 MHz) of 1 pixel operation			
	NRB		RB	
	Gray	RGB	Gray	RGB
BRAM_18K	43	49	171	177
DSP48E	34	46	36	48
FF	15365	15823	15205	15663
LUT	12868	13267	13443	13848

### Performance Estimate

The following table shows the performance estimates of HOGDescriptor() function for different configurations as generated in Vivado HLS 2018.2 version tool for the part Xilinx Xczu9eg-ffvb1156-1-i-es1 to process an image of 1920x1080p resolution.

**Table 169: HOGDescriptor Function Performance Estimate Summary**

Operating Mode	Operating Frequency (MHz)	Latency Estimate	
		Min (ms)	Max (ms)
NRB-Gray	300	6.98	8.83
NRB-RGBA	300	6.98	8.83
RB-Gray	300	176.81	177
RB-RGBA	300	176.81	177

### Deviations from OpenCV

Listed below are the deviations from the OpenCV:

1. Border care

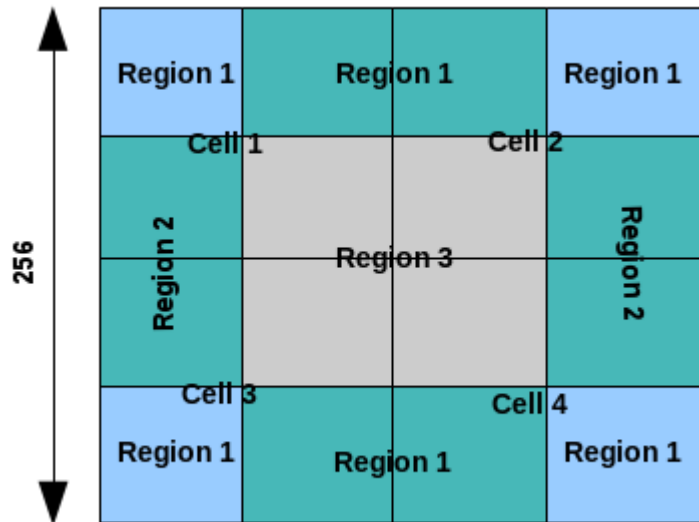
The border care that OpenCV has taken in the gradient computation is BORDER\_REFLECT\_101, in which the border padding will be the neighboring pixels' reflection. Whereas, in the Xilinx implementation, BORDER\_CONSTANT (zero padding) was used for the border care.

2. Gaussian weighing

The Gaussian weights are multiplied on the pixels over the block, that is a block has 256 pixels, and each position of the block are multiplied with its corresponding Gaussian weights. Whereas, in the HLS implementation, gaussian weighing was not performed.

3. Cell-wise interpolation

The magnitude values of the pixels are distributed across different cells in the blocks but on the corresponding bins.



Pixels in the region 1 belong only to its corresponding cells, but the pixels in region 2 and 3 are interpolated to the adjacent 2 cells and 4 cells respectively. This operation was not performed in the HLS implementation.

#### 4. Output handling

The output of the OpenCV will be in the column major form. In the HLS implementation, output will be in the row major form. Also, the feature vector will be in the fixed point type Q0.16 in the HLS implementation, while in the OpenCV it will be in floating point.

### Limitations

1. The configurations are limited to [Dalal's implementation](#)
2. Image height and image width must be a multiple of cell height and cell width respectively.

## Houghlines

The `HoughLines` function here is equivalent to `HoughLines Standard` in OpenCV. The `Houghlines` function is used to detect straight lines in a binary image. To apply the Hough transform, edge detection preprocessing is required. The input to the Hough transform is an edge detected binary image. For each point  $(x_i, y_i)$  in a binary image, we define a family of lines that go through the point as:

$$\rho = x_i \cos(\theta) + y_i \sin(\theta)$$

<sup>1</sup> N. Dalal, B. Triggs: *Histograms of oriented gradients for human detection*, IEEE Computer Society Conference on Computer Vision and Pattern Recognition, 2005.

Each pair of (rho,theta) represents a line that passes through the point (xi,yi). These (rho,theta) pairs of this family of lines passing through the point form a sinusoidal curve in (rho,theta) plane. If the sinusoids of N different points intersect in the (rho,theta) plane, then that intersection (rho1, theta1) represents the line that passes through these N points. In the Houghlines function, an accumulator is used to keep the count (also called voting) of all the intersection points in the (rho,theta) plane. After voting, the function filters spurious lines by performing thinning, that is, checking if the center vote value is greater than the neighborhood votes and threshold, then making that center vote as valid and other wise making it zero. Finally, the function returns the desired maximum number of lines (LINESMAX) in (rho,theta) form as output.

The design assumes the origin at the center of the image i.e at (Floor(COLS/2), Floor(ROWS/2)). The ranges of rho and theta are:

```
theta = [0, pi)
```

```
rho=[-DIAG/2, DIAG/2), where DIAG = cvRound{SquareRoot( (COLS*COLS) + (ROWS*ROWS))}
```

For ease of use, the input angles THETA, MINTHETA and MAXTHETA are taken in degrees, while the output theta is in radians. The angle resolution THETA is declared as an integer, but treated as a value in Q6.1 format (that is, THETA=3 signifies that the resolution used in the function is 1.5 degrees). When the output (rho,  $\Theta$  theta) is used for drawing lines,you should be aware of the fact that origin is at the center of the image.

### API Syntax

```
template<unsigned int RHO,unsigned int THETA,int MAXLINES,int DIAG,int MINTHETA,int MAXTHETA,int SRC_T, int ROWS, int COLS,int NPC>
```

```
void HoughLines(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat,float outputrho[MAXLINES],float outputtheta[MAXLINES],short threshold,short linesmax)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 170: Houghlines Function Parameter Descriptions**

Parameter	Description
RHO	Distance resolution of the accumulator in pixels.
THETA	Angle resolution of the accumulator in degrees and Q6.1 format.
MAXLINES	Maximum number of lines to be detected
MINTHETA	Minimum angle in degrees to check lines.

Table 170: Houghlines Function Parameter Descriptions (cont'd)

Parameter	Description
MAXTHETA	Maximum angle in degrees to check lines
DIAG	Diagonal of the image. It should be $\text{cvRound}(\sqrt{\text{rows}*\text{rows} + \text{cols}*\text{cols}})/\text{RHO}$
SRC_T	Input Pixel Type. Only 8-bit, unsigned, 1-channel is supported (XF_8UC1).
ROWS	Maximum height of input image
COLS	Maximum width of input image
NPC	Number of Pixels to be processed per cycle; Only single pixel supported XF_NPPC1.
_src_mat	Input image should be 8-bit, single-channel binary image.
outputrho	Output array of rho values. rho is the distance from the coordinate origin (center of the image).
outputtheta	Output array of theta values. Theta is the line rotation angle in radians.
threshold	Accumulator threshold parameter. Only those lines are returned that get enough votes (>threshold).
linesmax	Maximum number of lines.

### Resource Utilization

The table below shows the resource utilization of the kernel for different configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 to process a grayscale HD (1080x1920) image for 512 lines.

Table 171: Houghlines Function Resource Utilization Summary

Name	Resource Utilization
	THETA=1, RHO=1
BRAM_18K	542
DSP48E	10
FF	60648
LUT	56131

### Performance Estimate

The following table shows the performance of kernel for different configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 to process a grayscale HD (1080x1920) image for 512 lines.

Table 172: Houghlines Function Performance Estimate Summary

Operating Mode	Operating Frequency (MHz)	Latency Estimate
		Max (ms)
THETA=1, RHO=1	300	12.5

## Pyramid Up

The `pyrUp` function is an image up-sampling algorithm. It first inserts zero rows and zero columns after every input row and column making up to the size of the output image. The output image size is always  $(2*rows \times 2*columns)$ . The zero padded image is then smoothed using Gaussian image filter. Gaussian filter for the pyramid-up function uses a fixed filter kernel as given below:

$$\frac{1}{256} \begin{bmatrix} 1 & 4 & 6 & 4 & 1 \\ 4 & 16 & 24 & 16 & 4 \\ 6 & 24 & 36 & 24 & 6 \\ 4 & 16 & 24 & 16 & 4 \\ 1 & 4 & 6 & 4 & 1 \end{bmatrix}$$

However, to make up for the pixel intensity that is reduced due to zero padding, each output pixel is multiplied by 4.

### API Syntax

```
template<int TYPE, int ROWS, int COLS, int NPC>
void pyrUp (xf::Mat<TYPE, ROWS, COLS, NPC> & _src, xf::Mat<TYPE, ROWS,
COLS, NPC> & _dst)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 173: pyrUp Function Parameter Descriptions*

Parameter	Description
TYPE	Pixel type. XF_8UC1 is the only supported pixel type.
ROWS	Maximum Height or number of output rows to build the hardware for this kernel
COLS	Maximum Width or number of output columns to build the hardware for this kernel
NPC	Number of pixels to process per cycle. Currently, the kernel supports only 1 pixel per cycle processing (XF_NPPC1).
_src	Input image stream
_dst	Output image stream

### Resource Utilization

The following table summarizes the resource utilization of `pyrUp` for 1 pixel per cycle implementation, for a maximum input image size of 1920x1080 pixels. The results are after synthesis in Vivado HLS 2018.2 for the Xilinx xczu9eg-ffvb1156-1-i-es1 FPGA at 300 MHz.



Table 174: **pyrUp Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate			
		LUTs	FFs	DSPs	BRAMs
1 Pixel	300	1124	1199	0	10

### Performance Estimate

The following table summarizes performance estimates of pyrUp function on Vivado HLS 2018.2 for the Xilinx xczu9eg-ffvb1156-1-i-es1 FPGA.

 Table 175: **pyrUp Function Performance Estimate Summary**

Operating Mode	Operating Frequency (MHz)	Input Image Size	Latency Estimate
			Max (ms)
1 pixel	300	1920x1080	27.82

## Pyramid Down

The `pyrDown` function is an image down-sampling algorithm which smoothens the image before down-scaling it. The image is smoothed using a Gaussian filter with the following kernel:

$$\frac{1}{256} \begin{bmatrix} 1 & 4 & 6 & 4 & 1 \\ 4 & 16 & 24 & 16 & 4 \\ 6 & 24 & 36 & 24 & 6 \\ 4 & 16 & 24 & 16 & 4 \\ 1 & 4 & 6 & 4 & 1 \end{bmatrix}$$

Down-scaling is performed by dropping pixels in the even rows and the even columns. The

resulting image size is  $\left( \frac{rows + 1}{2} \quad \frac{columns + 1}{2} \right)$ .

### API Syntax

```
template<int TYPE, int ROWS, int COLS, int NPC>
void pyrDown (xf::Mat<TYPE, ROWS, COLS, NPC> & _src, xf::Mat<TYPE, ROWS, COLS, NPC> & _dst)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 176: pyrDown Function Parameter Descriptions**

Parameter	Description
TYPE	Pixel type. XF_8UC1 is the only supported pixel type.
ROWS	Maximum Height or number of input rows to build the hardware for this kernel
COLS	Maximum Width or number of input columns to build the hardware for this kernel
NPC	Number of pixels to process per cycle. Currently, the kernel supports only 1 pixel per cycle processing (XF_NPPC1).
_src	Input image stream
_dst	Output image stream

## Resource Utilization

The following table summarizes the resource utilization of pyrDown for 1 pixel per cycle implementation, for a maximum input image size of 1920x1080 pixels. The results are after synthesis in Vivado HLS 2018.2 for the Xilinx xczu9eg-ffvb1156-1-i-es1 FPGA at 300 MHz.

**Table 177: pyrDown Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate			
		LUTs	FFs	DSPs	BRAMs
1 Pixel	300	1171	1238	1	5

## Performance Estimate

The following table summarizes performance estimates of pyrDown function in Vivado HLS 2018.2 for the Xilinx xczu9eg-ffvb1156-1-i-es1 FPGA.

**Table 178: pyrDown Function Performance Estimate Summary**

Operating Mode	Operating Frequency (MHz)	Input Image Size	Latency Estimate
			Max (ms)
1 pixel	300	1920x1080	6.99

## InitUndistortRectifyMapInverse

The `InitUndistortRectifyMapInverse` function generates `mapx` and `mapy`, based on a set of camera parameters, where `mapx` and `mapy` are inputs for the `xf::remap` function. That is, for each pixel in the location  $(u, v)$  in the destination (corrected and rectified) image, the function computes the corresponding coordinates in the source image (the original image from camera). The `InitUndistortRectifyMapInverse` module is optimized for hardware, so the inverse of rotation matrix is computed outside the synthesizable logic. Note that the inputs are fixed point, so the floating point camera parameters must be type casted to Q12.20 format.

### API Syntax

```
template< int CM_SIZE, int DC_SIZE, int MAP_T, int ROWS, int COLS, int NPC
>
void InitUndistortRectifyMapInverse ( ap_fixed<32,12> *cameraMatrix,
ap_fixed<32,12> *distCoeffs, ap_fixed<32,12> *ir, xf::Mat<MAP_T, ROWS,
COLS, NPC> &_mapx_mat, xf::Mat<MAP_T, ROWS, COLS, NPC> &_mapy_mat, int
_cm_size, int _dc_size)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 179: InitUndistortRectifyMapInverse Function Parameter Descriptions*

Parameter	Description
CM_SIZE	It must be set at the compile time, 9 for 3x3 matrix
DC_SIZE	It must be set at the compile time, must be 4,5 or 8
MAP_T	It is the type of output maps, and must be XF_32FC1
ROWS	Maximum image height, necessary to generate the output maps
COLS	Maximum image width, necessary to generate the output maps
NPC	Number of pixels per cycle. This function supports only one pixel per cycle, so set to XF_NPPC1
cameraMatrix	The input matrix representing the camera in the old coordinate system
distCoeffs	The input distortion coefficients (k1,k2,p1,p2[,k3[,k4,k5,k6]])
ir	The input transformation matrix is equal to $\text{Invert}(\text{newCameraMatrix} * R)$ , where <code>newCameraMatrix</code> represents the camera in the new coordinate system and <code>R</code> is the rotation matrix.. This processing will be done outside the synthesizable block
_mapx_mat	Output mat objects containing the <code>mapx</code>
_mapy_mat	Output mat objects containing the <code>mapy</code>
_cm_size	9 for 3x3 matrix
_dc_size	4, 5 or 8. If this is 0, then it means there is no distortion

## Integral Image

The `integral` function computes an integral image of the input. Each output pixel is the sum of all pixels above and to the left of itself.

$$dst(x, y) = sum(x, y) = sum(x, y) + sum(x - 1, y) + sum(x, y - 1) - sum(x - 1, y - 1)$$

### API Syntax

```
template<int SRC_TYPE, int DST_TYPE, int ROWS, int COLS, int NPC=1>
void integral(xf::Mat<SRC_TYPE, ROWS, COLS, NPC> & _src_mat,
             xf::Mat<DST_TYPE, ROWS, COLS, NPC> & _dst_mat)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 180: integral Function Parameter Descriptions**

Parameter	Description
SRC_TYPE	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
DST_TYPE	Output pixel type. Only 32-bit, unsigned, 1 channel is supported (XF_32UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; this function supports only XF_NPPC1 or 1 pixel per cycle operations.
_src_mat	Input image
_dst_mat	Output image

### Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

**Table 181: integral Function Resource Utilization Summary**

Name	Resource Utilization	
	1 pixel	
	300 MHz	
BRAM_18K	4	
DSP48E	0	
FF	613	
LUT	378	
CLB	102	

## Performance Estimate

The following table summarizes the performance of the kernel in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 182: integral Function Performance Estimate Summary

Operating Mode	Latency Estimate	
	Operating Frequency (MHz)	Latency(in ms)
1pixel	300	7.2

## Dense Pyramidal LK Optical Flow

Optical flow is the pattern of apparent motion of image objects between two consecutive frames, caused by the movement of object or camera. It is a 2D vector field, where each vector is a displacement vector showing the movement of points from first frame to second.

Optical Flow works on the following assumptions:

- Pixel intensities of an object do not have too many variations in consecutive frames
- Neighboring pixels have similar motion

Consider a pixel  $I(x, y, t)$  in first frame. (Note that a new dimension, time, is added here. When working with images only, there is no need of time). The pixel moves by distance  $(dx, dy)$  in the next frame taken after time  $dt$ . Thus, since those pixels are the same and the intensity does not change, the following is true:

$$I(x, y, t) = I(x + dx, y + dy, t + dt)$$

Taking the Taylor series approximation on the right-hand side, removing common terms, and dividing by  $dt$  gives the following equation:

$$f_x u + f_y v + f_t = 0$$

Where  $f_x = \frac{\delta f}{\delta x}$ ,  $f_y = \frac{\delta f}{\delta y}$ ,  $u = \frac{dx}{dt}$  and  $v = \frac{dy}{dt}$ .

The above equation is called the Optical Flow equation, where,  $f_x$  and  $f_y$  are the image gradients and  $f_t$  is the gradient along time. However,  $(u, v)$  is unknown. It is not possible to solve this equation with two unknown variables. Thus, several methods are provided to solve this problem. One method is Lucas-Kanade. Previously it was assumed that all neighboring pixels have similar motion. The Lucas-Kanade method takes a patch around the point, whose size can

be defined through the 'WINDOW\_SIZE' template parameter. Thus, all the points in that patch have the same motion. It is possible to find  $(f_x, f_y, f_t)$  for these points. Thus, the problem now becomes solving 'WINDOW\_SIZE \* WINDOW\_SIZE' equations with two unknown variables, which is over-determined. A better solution is obtained with the "least square fit" method. Below is the final solution, which is a problem with two equations and two unknowns:

$$\begin{bmatrix} u \\ v \end{bmatrix} = \begin{bmatrix} \sum f_{x_i}^2 & \sum f_{x_i}f_{y_i} \\ \sum f_{x_i}f_{y_i} & \sum f_{y_i}^2 \end{bmatrix}^{-1} \begin{bmatrix} -\sum f_{x_i}f_{t_i} \\ -\sum f_{y_i}f_{t_i} \end{bmatrix}$$

This solution fails when a large motion is involved and so pyramids are used. Going up in the pyramid, small motions are removed and large motions become small motions and so by applying Lucas-Kanade, the optical flow along with the scale is obtained.

### API Syntax

```
template< int NUM_PYR_LEVELS, int NUM_LINES, int WINSIZE, int FLOW_WIDTH,
int FLOW_INT, int TYPE, int ROWS, int COLS, int NPC>
void densePyrOpticalFlow(
xf::Mat<TYPE,ROWS,COLS,NPC> & _current_img,
xf::Mat<TYPE,ROWS,COLS,NPC> & _next_image,
xf::Mat<XF_32UC1,ROWS,COLS,NPC> & _streamFlowin,
xf::Mat<XF_32UC1,ROWS,COLS,NPC> & _streamFlowout,
const int level, const unsigned char scale_up_flag, float scale_in,
ap_uint<1> init_flag)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 183: densePyrOpticalFlow Function Parameter Descriptions**

Parameter	Description
NUM_PYR_LEVELS	Number of Image Pyramid levels used for the optical flow computation
NUM_LINES	Number of lines to buffer for the remap algorithm - used to find the temporal gradient
WINSIZE	Window Size over which Optical Flow is computed
FLOW_WIDTH, FLOW_INT	Data width and number of integer bits to define the signed flow vector data type. Integer bit includes the signed bit. The default type is 16-bit signed word with 10 integer bits and 6 decimal bits.
TYPE	Pixel type of the input image. XF_8UC1 is only the supported value.
ROWS	Maximum Height or number of rows to build the hardware for this kernel
COLS	Maximum Width or number of columns to build the hardware for this kernel
NPC	Number of pixels the hardware kernel must process per clock cycle. Only XF_NPPC1, 1 pixel per cycle, is supported.
_curr_img	First input image stream
_next_img	Second input image to which the optical flow is computed with respect to the first image

Table 183: **densePyrOpticalFlow Function Parameter Descriptions (cont'd)**

Parameter	Description
_streamFlowin	32-bit Packed U and V flow vectors input for optical flow. The bits from 31-16 represent the flow vector U while the bits from 15-0 represent the flow vector V.
_streamFlowout	32-bit Packed U and V flow vectors output after optical flow computation. The bits from 31-16 represent the flow vector U while the bits from 15-0 represent the flow vector V.
level	Image pyramid level at which the algorithm is currently computing the optical flow.
scale_up_flag	Flag to enable the scaling-up of the flow vectors. This flag is set at the host when switching from one image pyramid level to the other.
scale_in	Floating point scale up factor for the scaling-up the flow vectors. The value is $(\text{previous\_rows}-1)/(\text{current\_rows}-1)$ . This is not 1 when switching from one image pyramid level to the other.
init_flag	Flag to initialize flow vectors to 0 in the first iteration of the highest pyramid level. This flag must be set in the first iteration of the highest pyramid level (smallest image in the pyramid). The flag must be unset for all the other iterations.

### Resource Utilization

The following table summarizes the resource utilization of densePyrOpticalFlow for 1 pixel per cycle implementation, with the optical flow computed for a window size of 11 over an image size of 1920x1080 pixels. The results are after implementation in Vivado HLS 2018.2 for the Xilinx xczu9eg-ffvb1156-2L-e FPGA at 300 MHz.

 Table 184: **densePyrOpticalFlow Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate			
		LUTs	FFs	DSPs	BRAMs
1 Pixel	300	32231	16596	52	215

### Performance Estimate

The following table summarizes performance figures on hardware for the densePyrOpticalFlow function for 5 iterations over 5 pyramid levels scaled down by a factor of two at each level. This has been tested on the zcu102 evaluation board.

 Table 185: **densePyrOpticalFlow Function Performance Estimate Summary**

Operating Mode	Operating Frequency (MHz)	Image Size	Latency Estimate
			Max (ms)
1 pixel	300	1920x1080	49.7
1 pixel	300	1280x720	22.9
1 pixel	300	1226x370	12.02

## Dense Non-Pyramidal LK Optical Flow

Optical flow is the pattern of apparent motion of image objects between two consecutive frames, caused by the movement of object or camera. It is a 2D vector field, where each vector is a displacement vector showing the movement of points from first frame to second.

Optical Flow works on the following assumptions:

- Pixel intensities of an object do not have too many variations in consecutive frames
- Neighboring pixels have similar motion

Consider a pixel  $I(x, y, t)$  in first frame. (Note that a new dimension, time, is added here. When working with images only, there is no need of time). The pixel moves by distance  $(dx, dy)$  in the next frame taken after time  $dt$ . Thus, since those pixels are the same and the intensity does not change, the following is true:

$$I(x, y, t) = I(x + dx, y + dy, t + dt)$$

Taking the Taylor series approximation on the right-hand side, removing common terms, and dividing by  $dt$  gives the following equation:

$$f_x u + f_y v + f_t = 0$$

Where  $f_x = \frac{\delta f}{\delta x}$ ,  $f_y = \frac{\delta f}{\delta y}$ ,  $u = \frac{dx}{dt}$  and  $v = \frac{dy}{dt}$ .

The above equation is called the Optical Flow equation, where,  $f_x$  and  $f_y$  are the image gradients and  $f_t$  is the gradient along time. However,  $(u, v)$  is unknown. It is not possible to solve this equation with two unknown variables. Thus, several methods are provided to solve this problem. One method is Lucas-Kanade. Previously it was assumed that all neighboring pixels have similar motion. The Lucas-Kanade method takes a patch around the point, whose size can be defined through the 'WINDOW\_SIZE' template parameter. Thus, all the points in that patch have the same motion. It is possible to find  $(f_x, f_y, f_t)$  for these points. Thus, the problem now becomes solving 'WINDOW\_SIZE \* WINDOW\_SIZE' equations with two unknown variables, which is over-determined. A better solution is obtained with the "least square fit" method. Below is the final solution, which is a problem with two equations and two unknowns:

$$\begin{bmatrix} u \\ v \end{bmatrix} = \begin{bmatrix} \sum f_{x_i}^2 & \sum f_{x_i} f_{y_i} \\ \sum f_{x_i} f_{y_i} & \sum f_{y_i}^2 \end{bmatrix}^{-1} \begin{bmatrix} -\sum f_{x_i} f_{t_i} \\ -\sum f_{y_i} f_{t_i} \end{bmatrix}$$



## API Syntax

```
template<int TYPE, int ROWS, int COLS, int NPC, int WINDOW_SIZE>
void DenseNonPyrLKOpticalFlow (xf::Mat<TYPE, ROWS, COLS, NPC> & frame0,
xf::Mat<TYPE, ROWS, COLS, NPC> & frame1, xf::Mat<XF_32FC1, ROWS, COLS,
NPC> & flowx, xf::Mat<XF_32FC1, ROWS, COLS, NPC> & flowy)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 186: DenseNonPyrLKOpticalFlow Function Parameter Descriptions**

Parameter	Description
Type	pixel type. The current supported pixel value is XF_8UC1, unsigned 8 bit.
ROWS	Maximum number of rows of the input image that the hardware kernel must be built for.
COLS	Maximum number of columns of the input image that the hardware kernel must be built for.
NPC	Number of pixels to process per cycle. Supported values are XF_NPPC1 (=1) and XF_NPPC2(=2).
WINDOW_SIZE	Window size over which optical flow will be computed. This can be any odd positive integer.
frame0	First input images.
frame1	Second input image. Optical flow is computed between frame0 and frame1.
flowx	Horizontal component of the flow vectors. The format of the flow vectors is XF_32FC1 or single precision.
flowy	Vertical component of the flow vectors. The format of the flow vectors is XF_32FC1 or single precision.

## Resource Utilization

The following table summarizes the resource utilization of DenseNonPyrLKOpticalFlow for a 4K image, as generated in the Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA at 300 MHz.

**Table 187: DenseNonPyrLKOpticalFlow Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate			
		BRAM_18K	DSP_48Es	FF	LUTs
1 pixel	300	178	42	11984	7730
2 pixel	300	258	82	22747	15126

## Performance Estimate

The following table summarizes performance estimates of the DenseNonPyrLKOpticalFlow function for a 4K image, generated using Vivado HLS 2018.2 version tool for the Xilinx xczu9eg-ffvb1156-1-i-es1 FPGA.

Table 188: DenseNonPyrLKOpticalFlow Function Performance Estimate Summary

Operating Mode	Operating Frequency (MHz)	Latency Estimate
		Max (ms)
1 pixel	300	28.01
2 pixel	300	14.01

## Mean and Standard Deviation

The `meanStdDev` function computes the mean and standard deviation of input image. The output Mean value is in fixed point Q8.8 format, and the Standard Deviation value is in Q8.8 format. Mean and standard deviation are calculated as follows:

$$\mu = \frac{\sum_{y=0}^{height} \sum_{x=0}^{width} src(x, y)}{(width * height)}$$

$$\sigma = \sqrt{\frac{\sum_{y=0}^{height} \sum_{x=0}^{width} (\mu - src(x, y))^2}{(width * height)}}$$

### API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1>
void meanStdDev(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, unsigned short*
_mean, unsigned short* _stddev)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 189: meanStdDev Function Parameter Descriptions

Parameter	Description
SRC_T	Input pixel type. 8-bit, unsigned, 1 channel (XF_8UC1) is supported.
ROWS	Number of rows in the image being processed.
COLS	Number of columns in the image being processed.
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input image

Table 189: meanStdDev Function Parameter Descriptions (cont'd)

Parameter	Description
_mean	16-bit data pointer through which the computed mean of the image is returned.
_stddev	16-bit data pointer through which the computed standard deviation of the image is returned.

## Resource Utilization

The following table summarizes the resource utilization of the meanStdDev function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

Table 190: meanStdDev Function Resource Utilization Summary

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	6	896	461	121
8 pixel	150	0	13	1180	985	208

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 191: meanStdDev Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency
1 pixel operation (300 MHz)	6.9 ms
8 pixel operation (150 MHz)	1.69 ms

## Median Blur Filter

The function medianBlur performs a median filter operation on the input image. The median filter acts as a non-linear digital filter which improves noise reduction. A filter size of N would output the median value of the NxN neighborhood pixel values, for each pixel.

### API Syntax

```
template<int FILTER_SIZE, int BORDER_TYPE, int TYPE, int ROWS, int COLS,
int NPC>
void medianBlur (xf::Mat<TYPE, ROWS, COLS, NPC> & _src, xf::Mat<TYPE,
ROWS, COLS, NPC> & _dst)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

*Table 192: medianBlur Function Parameter Descriptions*

Parameter	Description
FILTER_SIZE	Window size of the hardware filter for which the hardware kernel will be built. This can be any odd positive integer greater than 1.
BORDER_TYPE	The way in which borders will be processed in the hardware kernel. Currently, only XF_BORDER_REPLICATE is supported.
TYPE	Type of input pixel. XF_8UC1 is supported.
ROWS	Number of rows in the image being processed.
COLS	Number of columns in the image being processed.
NPC	Number of pixels to be processed in parallel. Options are XF_NPPC1 (for 1 pixel processing per clock), XF_NPPC8 (for 8 pixel processing per clock)
_src	Input image.
_dst	Output image.

## Resource Utilization

The following table summarizes the resource utilization of the medianBlur function for XF\_NPPC1 and XF\_NPPC8 configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xc7z020c1g484-1 FPGA.

*Table 193: medianBlur Function Resource Utilization Summary*

Operating Mode	FILTER_SIZE	Operating Frequency (MHz)	Utilization Estimate			
			LUTs	FFs	DSPs	BRAMs
1 pixel	3	300	1197	771	0	3
8 pixel	3	150	6559	1595	0	6
1 pixel	5	300	5860	1886	0	5

## Performance Estimate

The following table summarizes performance estimates of medianBlur function on Vivado HLS 2018.2 version tool for the Xilinx xczu9eg-ffvb1156-1-i-es1 FPGA.

Table 194: medianBlur Function Performance Estimate Summary

Operating Mode	FILTER_SIZE	Operating Frequency (MHz)	Input Image Size	Latency Estimate
				Max (ms)
1 pixel	3	300	1920x1080	6.99
8 pixel	3	150	1920x1080	1.75
1 pixel	5	300	1920x1080	7.00

## MinMax Location

The `minMaxLoc` function finds the minimum and maximum values in an image and location of those values.

$$minVal = \min_{\substack{0 \leq x' \leq width \\ 0 \leq y' \leq height}} src(x', y')$$

$$maxVal = \max_{\substack{0 \leq x' \leq width \\ 0 \leq y' \leq height}} src(x', y')$$

### API Syntax

```
template<int SRC_T,int ROWS,int COLS,int NPC>
void minMaxLoc(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src,int32_t *max_value,
int32_t *min_value,uint16_t *_minlocx, uint16_t *_minlocy, uint16_t
*_maxlocx, uint16_t *_maxlocy )
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 195: minMaxLoc Function Parameter Descriptions

Parameter	Description
SRC_T	Input pixel type. 8-bit, unsigned, 1 channel (XF_8UC1), 16-bit, unsigned, 1 channel (XF_16UC1), 16-bit, signed, 1 channel (XF_16SC1), 32-bit, signed, 1 channel (XF_32SC1) are supported.
ROWS	Number of rows in the image being processed.
COLS	Number of columns in the image being processed.
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input image

Table 195: minMaxLoc Function Parameter Descriptions (cont'd)

Parameter	Description
max_val	Maximum value in the image, of type int.
min_val	Minimum value in the image, of type int.
_minlocx	x-coordinate location of the first minimum value.
_minlocy	y-coordinate location of the first maximum value.
_maxlocx	x-coordinate location of the first minimum value.
_maxlocy	y-coordinate location of the first maximum value.

### Resource Utilization

The following table summarizes the resource utilization of the minMaxLoc function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

Table 196: minMaxLoc Function Resource Utilization Summary

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	3	451	398	86
8 pixel	150	0	3	1049	1025	220

### Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 197: minMaxLoc Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency
1 pixel operation (300 MHz)	6.9 ms
8 pixel operation (150 MHz)	1.69 ms

## Mean Shift Tracking

Mean shift tracking is one of the basic object tracking algorithms. Mean-shift tracking tries to find the area of a video frame that is locally most similar to a previously initialized model. The object to be tracked is represented by a histogram. In object tracking algorithms target representation is mainly rectangular or elliptical region. It contains target model and target candidate. Color histogram is used to characterize the object. Target model is generally represented by its probability density function (pdf). Weighted RGB histogram is used to give more importance to object pixels.

Mean-shift algorithm is an iterative technique for locating the maxima of a density function. For object tracking, the density function used is the weight image formed using color histograms of the object to be tracked and the frame to be tested. By using the weighted histogram we are taking spatial position into consideration unlike the normal histogram calculation. This function will take input image pointer, top left and bottom right coordinates of the rectangular object, frame number and tracking status as inputs and returns the centroid using recursive mean shift approach.

### API Syntax

```
template <int MAXOBJ, int MAXITERS, int OBJ_ROWS, int OBJ_COLS, int SRC_T,
int ROWS, int COLS, int NPC>
void MeanShift(xf::Mat<SRC_T, ROWS, COLS, NPC> &_in_mat, uint16_t* x1,
uint16_t* y1, uint16_t* obj_height, uint16_t* obj_width, uint16_t* dx,
uint16_t* dy, uint16_t* status, uint8_t frame_status, uint8_t no_objects,
uint8_t no_iters );
```

### Template Parameter Descriptions

The following table describes the template parameters.

*Table 198: MeanShift Template Parameters*

Parameter	Description
MAXOBJ	Maximum number of objects to be tracked
MAXITERS	Maximum iterations for convergence
OBJ_ROWS	Maximum Height of the object to be tracked
OBJ_COLS	Maximum width of the object to be tracked
SRC_T	Type of the input xf::Mat, must be XF_8UC4, 8-bit data with 4 channels
ROWS	Maximum height of the image
COLS	Maximum width of the image
NPC	Number of pixels to be processed per cycle; this function supports only XF_NPPC1 or 1 pixel per cycle operations.

## Function Parameter Description

The following table describes the function parameters.

*Table 199: MeanShift Function Parameters*

Parameter	Description
_in_mat	Input xF Mat
x1	Top Left corner x-coordinate of all the objects
y1	Top Left corner y-coordinate of all the objects
obj_height	Height of all the objects
obj_width	Width of all the objects
dx	Centers x-coordinate of all the objects returned by the kernel function
dy	Centers y-coordinate of all the objects returned by the kernel function
status	Track the object only if the status of the object is true (i.e.) if the object goes out of the frame, status is made zero
frame_status	Set as zero for the first frame and one for other frames
no_objects	Number of objects tracked
no_iters	Number of iterations for convergence

## Resource Utilization and Performance Estimate

The following table summarizes the resource utilization of the MeanShift function for normal (1 pixel) configuration as generated in Vivado HLS 2018.2 release tool for the part xczu9eg-ffvb1156-i-es1 at 300 MHz to process a RGB image of resolution,1920x1080, and for 10 objects of size of 250x250 and 4 iterations.

*Table 200: MeanShift Function Resource Utilization and Performance Estimate Summary*

Configuration	Max. Latency	BRAMs	DSPs	FFs	LUTs
1 pixel	19.28	76	14	13198	10064

## Limitations

The maximum number of objects that can be tracked is 10.

## Otsu Threshold

Otsu threshold is used to automatically perform clustering-based image thresholding or the reduction of a gray-level image to a binary image. The algorithm assumes that the image contains two classes of pixels following bi-modal histogram (foreground pixels and background pixels), it then calculates the optimum threshold separating the two classes.



Otsu method is used to find the threshold which can minimize the intra class variance which separates two classes defined by weighted sum of variances of two classes.

$$\sigma_w^2(t) = w_1 \sigma_1^2(t) + w_2 \sigma_2^2(t)$$

Where,  $w_1$  is the class probability computed from the histogram.

$$w_1 = \sum_1^t p(i) \qquad w_2 = \sum_{t+1}^I p(i)$$

Otsu shows that minimizing the intra-class variance is the same as maximizing inter-class variance

$$\sigma_b^2 = \sigma - \sigma_w^2$$

$$\sigma_b^2 = w_1 w_2 (\mu_b - \mu_f)^2$$

Where,  $\mu_b = \left[ \sum_1^t p(i)x(i) \right] / w_1$  ,  $\mu_f = \left[ \sum_{t+1}^I p(i)x(i) \right] / w_2$  is the class mean.

### API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1> void
OtsuThreshold(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat, uint8_t & _thresh)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 201: OtsuThreshold Function Parameter Descriptions*

Parameter	Description
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_mat	Input image
_thresh	Output threshold value after the computation

## Resource Utilization

The following table summarizes the resource utilization of the OtsuThreshold function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

Table 202: OtsuThreshold Function Resource Utilization Summary

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	8	49	2239	3353	653
8 pixel	150	22	49	1106	3615	704

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 203: OtsuThreshold Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.92 ms
8 pixel operation (150 MHz)	1.76 ms

## Pixel-Wise Addition

The `add` function performs the pixel-wise addition between two input images and returns the output image.

$$I_{out}(x, y) = I_{in1}(x, y) + I_{in2}(x, y)$$

Where:

- $I_{out}(x, y)$  is the intensity of the output image at (x, y) position
- $I_{in1}(x, y)$  is the intensity of the first input image at (x, y) position
- $I_{in2}(x, y)$  is the intensity of the second input image at (x, y) position.

XF\_CONVERT\_POLICY\_TRUNCATE: Results are the least significant bits of the output operand, as if stored in two's complement binary format in the size of its bit-depth.

XF\_CONVERT\_POLICY\_SATURATE: Results are saturated to the bit depth of the output operand.

### API Syntax

```
template<int POLICY_TYPE, int SRC_T, int ROWS, int COLS, int NPC=1>
void add (
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src1,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src2,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> dst )
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 204: add Function Parameter Descriptions*

Parameter	Description
POLICY_TYPE	Type of overflow handling. It can be either, XF_CONVERT_POLICY_SATURATE or XF_CONVERT_POLICY_TRUNCATE.
SRC_T	pixel type. Options are XF_8UC1 and XF_16SC1.
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src1	Input image
src2	Input image
dst	Output image

### Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

*Table 205: add Function Resource Utilization Summary*

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	62	55	11
8 pixel	150	0	0	65	138	24

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 206: **add Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150MHz)	1.7

## Pixel-Wise Multiplication

The `multiply` function performs the pixel-wise multiplication between two input images and returns the output image.

$$I_{out}(x, y) = I_{in1}(x, y) * I_{in2}(x, y) * scale\_val$$

Where:

- $I_{out}(x, y)$  is the intensity of the output image at (x, y) position
- $I_{in1}(x, y)$  is the intensity of the first input image at (x, y) position
- $I_{in2}(x, y)$  is the intensity of the second input image at (x, y) position
- `scale_val` is the scale value.

`XF_CONVERT_POLICY_TRUNCATE`: Results are the least significant bits of the output operand, as if stored in two's complement binary format in the size of its bit-depth.

`XF_CONVERT_POLICY_SATURATE`: Results are saturated to the bit depth of the output operand.

## API Syntax

```
template<int POLICY_TYPE, int SRC_T, int ROWS, int COLS, int NPC=1>
void multiply (
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src1,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src2,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> dst,
    float scale)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 207: multiply Function Parameter Descriptions**

Parameter	Description
POLICY_TYPE	Type of overflow handling. It can be either, XF_CONVERT_POLICY_SATURATE or XF_CONVERT_POLICY_TRUNCATE.
SRC_T	pixel type. Options are XF_8UC1 and XF_16SC1.
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src1	Input image
src2	Input image
dst	Output image
scale_val	Weighing factor within the range of 0 and 1

### Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

**Table 208: multiply Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	2	124	59	18
8 pixel	150	0	16	285	108	43

### Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

**Table 209: multiply Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (in ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.6

## Pixel-Wise Subtraction

The `subtract` function performs the pixel-wise subtraction between two input images and returns the output image.

$$I_{\text{out}}(x, y) = I_{\text{in1}}(x, y) - I_{\text{in2}}(x, y)$$

Where:

- $I_{\text{out}}(x, y)$  is the intensity of the output image at  $(x, y)$  position
- $I_{\text{in1}}(x, y)$  is the intensity of the first input image at  $(x, y)$  position
- $I_{\text{in2}}(x, y)$  is the intensity of the second input image at  $(x, y)$  position.

**XF\_CONVERT\_POLICY\_TRUNCATE:** Results are the least significant bits of the output operand, as if stored in two's complement binary format in the size of its bit-depth.

**XF\_CONVERT\_POLICY\_SATURATE:** Results are saturated to the bit depth of the output operand.

### API Syntax

```
template<int POLICY_TYPE int SRC_T, int ROWS, int COLS, int NPC=1>
void subtract (
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src1,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> src2,
    xf::Mat<int SRC_T, int ROWS, int COLS, int NPC> dst )
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 210: subtract Function Parameter Descriptions*

Parameter	Description
POLICY_TYPE	Type of overflow handling. It can be either, XF_CONVERT_POLICY_SATURATE or XF_CONVERT_POLICY_TRUNCATE.
SRC_T	pixel type. Options are XF_8UC1 and XF_16SC1.
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
src1	Input image
src2	Input image
dst	Output image

## Resource Utilization

The following table summarizes the resource utilization in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

Table 211: **subtract Function Resource Utilization Summary**

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	0	0	62	53	11
8 pixel	150	0	0	59	13	21

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 212: **subtract Function Performance Estimate Summary**

Operating Mode	Latency Estimate
	Max Latency (ms)
1 pixel operation (300 MHz)	6.9
8 pixel operation (150 MHz)	1.7

## Remap

The `remap` function takes pixels from one place in the image and relocates them to another position in another image. Two types of interpolation methods are used here for mapping the image from source to destination image.

$$dst = src(map_x(x, y), map_y(x, y))$$

## API Syntax

```
template<int WIN_ROWS, int INTERPOLATION_TYPE, int SRC_T, int MAP_T, int
DST_T, int ROWS, int COLS, int NPC = 1>

void remap (xf::Mat<SRC_T, ROWS, COLS, NPC> &_src_mat,
            xf::Mat<DST_T, ROWS, COLS, NPC> &_remapped_mat,
            xf::Mat<MAP_T, ROWS, COLS, NPC> &_mapx_mat,
            xf::Mat<MAP_T, ROWS, COLS, NPC> &_mapy_mat);
```

## Parameter Descriptions

The following table describes the template parameters.

**Table 213: remap template Parameter Descriptions**

Parameter	Description
WIN_ROWS	Number of input image rows to be buffered inside. Must be set based on the map data. For instance, for left right flip, 2 rows are sufficient.
INTERPOLATION_TYPE	Type of interpolation, either XF_INTERPOLATION_NN (nearest neighbor) or XF_INTERPOLATION_BILINEAR (linear interpolation)
SRC_T	Input image type. Grayscale image of type 8-bits and single channel. XF_8UC1.
MAP_T	Map type. Single channel float type. XF_32FC1.
DST_T	Output image type. Grayscale image of type 8-bits and single channel. XF_8UC1.
ROWS	Height of input and output images
COLS	Width of input and output images
NPC	Number of pixels to be processed per cycle; this function supports only XF_NPPC1 or 1 pixel per cycle operations.

The following table describes the function parameters.

**Table 214: remap Function Parameter Descriptions**

PARAMETERS	DESCRIPTION
_src_mat	Input xF Mat
_remapped_mat	Output xF Mat
_mapx_mat	mapX Mat of float type
_mapy_mat	mapY Mat of float type

## Resource Utilization

The following table summarizes the resource utilization of remap, for HD (1080x1920) images generated in the Vivado HLS 2018.2 version tool for the Xilinx xczu9eg-ffvb1156-i-es1 FPGA at 300 MHz, with WIN\_ROWS as 64 for the XF\_INTERPOLATION\_BILINEAR mode.

**Table 215: remap Function Resource Utilization Summary**

Name	Resource Utilization
BRAM_18K	64
DSP48E	17
FF	1738
LUT	1593
CLB	360



## Performance Estimate

The following table summarizes the performance of `remap()`, for HD (1080x1920) images generated in the Vivado HLS 2018.2 version tool for the Xilinx xczu9eg-ffvb1156-i-es1 FPGA at 300 MHz, with `WIN_ROWS` as 64 for `XF_INTERPOLATION_BILINEAR` mode.

Table 216: **remap Function Performance Estimate Summary**

Operating Mode	Operating Frequency (MHz)	Latency Estimate Max latency (ms)
1 pixel mode	300	7.2

## Resolution Conversion (Resize)

Resolution Conversion is the method used to resize the source image to the size of the destination image. Different types of interpolation techniques can be used in resize function, namely: Nearest-neighbor, Bilinear, and Area interpolation. The type of interpolation can be passed as a template parameter to the API. The following enumeration types can be used to specify the interpolation type:

- `XF_INTERPOLATION_NN` - For Nearest-neighbor interpolation
- `XF_INTERPOLATION_BILINEAR` - For Bilinear interpolation
- `XF_INTERPOLATION_AREA` - For Area interpolation

**Note:** Scaling factors greater than or equal to 0.25 are supported in down-scaling and values less than or equal to 8 are supported for up-scaling.

### API Syntax

```
template<int INTERPOLATION_TYPE, int TYPE, int SRC_ROWS, int SRC_COLS, int
DST_ROWS, int DST_COLS, int NPC>
void resize (xf::Mat<TYPE, SRC_ROWS, SRC_COLS, NPC> & _src, xf::Mat<TYPE,
DST_ROWS, DST_COLS, NPC> & _dst)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 217: **resize Function Parameter Descriptions**

Parameter	Description
INTERPOLATION_TYPE	Interpolation type. The different options possible are <ul style="list-style-type: none"> <li>XF_INTERPOLATION_NN - Nearest Neighbor Interpolation</li> <li>XF_INTERPOLATION_BILINEAR - Bilinear interpolation</li> <li>XF_INTERPOLATION_AREA - Area Interpolation</li> </ul>
TYPE	Number of bits per pixel. Only XF_8UC1 is supported.
SRC_ROWS	Maximum Height of input image for which the hardware kernel would be built.
SRC_COLS	Maximum Width of input image for which the hardware kernel would be built (must be a multiple of 8).
DST_ROWS	Maximum Height of output image for which the hardware kernel would be built.
DST_COLS	Maximum Width of output image for which the hardware kernel would be built (must be a multiple of 8).
NPC	Number of pixels to be processed per cycle. Possible options are XF_NPPC1 (1 pixel per cycle) and XF_NPPC8 (8 pixel per cycle).
_src	Input Image
_dst	Output Image

## Resource Utilization

The following table summarizes the resource utilization of Resize function in Resource Optimized (8 pixel) mode and Normal mode, as generated in the Vivado HLS 2018.2 tool for the Xilinx xczu9eg-ffvb1156-2-i-es2 FPGA.

 Table 218: **resize Function Resource Utilization Summary**

Operating Mode	Utilization Estimate							
	1 Pixel (at 300 MHz)				8 Pixel (at 150MHz)			
	LUTs	FFs	DSPs	BRAMs	LUTs	FFs	DSPs	BRAMs
Downscale Nearest Neighbor	1215	1625	4	3	2533	2454	4	24
Downscale Bilinear	1473	1821	8	3	5647	3714	36	24
Downscale Area	2558	2995	42	30	Configuration not supported			
Upscale Nearest Neighbor	1215	1625	4	3	1599	1636	8	20
Upscale Bilinear	1473	1821	8	3	4116	3423	36	12
Upscale Area	1461	2107	16	25	Configuration not supported			

## Performance Estimate

The following table summarizes the performance estimation of Resize for various configurations, as generated in the Vivado HLS 2018.2 tool for the xczu9eg-ffvb1156-2-i-es2 FPGA at 300 MHz to resize a grayscale image from 1080x1920 to 480x640 (downscale); and to resize a grayscale image from 1080x1920 to 2160x3840 (upscale). This table also shows the latencies obtained for different interpolation types.

Table 219: **resize Function Performance Estimate Summary**

Operating Mode	Operating Frequency (MHz)	Latency Estimate (ms)					
		Downscale NN	Downscale Bilinear	Downscale Area	Upscale NN	Upscale Bilinear	Upscale Area
1 pixel	300	6.94	6.97	7.09	27.71	27.75	27.74

## RGB2HSV

The `RGB2HSV` function converts the input image color space to HSV color space and returns the HSV image as the output.

### API Syntax

```
template<int SRC_T, int ROWS, int COLS, int NPC=1>
    void RGB2HSV(xf::Mat<SRC_T, ROWS, COLS, NPC> &
        _src_mat, xf::Mat<SRC_T, ROWS, COLS, NPC> & _dst_mat)
```

### Parameter Descriptions

The table below describes the template and the function parameters.

Parameter	Description
SRC_T	Input pixel type should be XF_8UC4
DST_T	Output pixel type should be XF_8UC4
ROWS	Maximum height of input and output image
COLS	Maximum width of input and output image
NPC	Number of pixels to be processed per cycle. Only XF_NPPC1 is supported.
_src_mat	Input image
_dst_mat	Output image

## Scharr Filter

The `Scharr` function computes the gradients of input image in both x and y direction by convolving the kernel with input image being processed.

For Kernel size 3x3:

- GradientX:

$$G_x = \begin{bmatrix} -3 & 0 & 3 \\ -10 & 0 & 10 \\ -3 & 0 & 3 \end{bmatrix} * I$$

- GradientY:

$$G_y = \begin{bmatrix} -3 & -10 & -3 \\ 0 & 0 & 0 \\ 3 & 10 & 3 \end{bmatrix} * I$$

### API Syntax

```
template<int BORDER_TYPE, int SRC_T,int DST_T, int ROWS, int COLS,int
NPC=1>
void Scharr(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat,xf::Mat<DST_T,
ROWS, COLS, NPC> & _dst_matx,xf::Mat<DST_T, ROWS, COLS, NPC> & _dst_maty)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 220: Scharr Function Parameter Descriptions*

Parameter	Description
BORDER_TYPE	Border Type supported is XF_BORDER_CONSTANT
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
DST_T	Output pixel type. Only 8-bit unsigned, 16-bit signed, 1 channel is supported (XF_8UC1, XF_16SC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_mat	Input image
_dst_matx	X gradient output image.
_dst_maty	Y gradient output image.

## Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

*Table 221: Scharr Function Resource Utilization Summary*

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150MHz
BRAM_18K	3	6
DSP48E	0	0
FF	728	1434
LUT	812	2481
CLB	171	461

## Performance Estimate

The following table summarizes the performance of the kernel in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

*Table 222: Scharr Function Performance Estimate Summary*

Operating Mode	Operating Frequency (MHz)	Latency Estimate (ms)
1 pixel	300	7.2
8 pixel	150	1.7

## Sobel Filter

The `Sobel` function Computes the gradients of input image in both x and y direction by convolving the kernel with input image being processed.

- For Kernel size 3x3

- GradientX:

$$G_y = \begin{bmatrix} -3 & -10 & -3 \\ 0 & 0 & 0 \\ 3 & 10 & 3 \end{bmatrix} * I$$

- GradientY:

$$G_y = \begin{bmatrix} -1 & -2 & -1 \\ 0 & 0 & 0 \\ 1 & 2 & 1 \end{bmatrix} * I$$

- For Kernel size 5x5

- GradientX:

$$G_x = \begin{bmatrix} -1 & -2 & 0 & 2 & 1 \\ -4 & -8 & 0 & 8 & 4 \\ -6 & -12 & 0 & 12 & 6 \\ -4 & -8 & 0 & 8 & 4 \\ -1 & -2 & 0 & 2 & 1 \end{bmatrix} * I$$

- GradientY:

$$G_y = \begin{bmatrix} -1 & -4 & -6 & -4 & -1 \\ -2 & -8 & -12 & -8 & -2 \\ 0 & 0 & 0 & 0 & 0 \\ 2 & 8 & 12 & 8 & 2 \\ 1 & 4 & 6 & 4 & 1 \end{bmatrix} * I$$

- For Kernel size 7x7

- GradientX:

$$G_x = \begin{bmatrix} -1 & -4 & -5 & 0 & 5 & 4 & 1 \\ -6 & -24 & -30 & 0 & 30 & 24 & 6 \\ -15 & -60 & 75 & 0 & 75 & 60 & 15 \\ -20 & -80 & -100 & 0 & 75 & 60 & 15 \\ -15 & -60 & -75 & 0 & 75 & 60 & 15 \\ -6 & -24 & -30 & 0 & 30 & 24 & 6 \\ -1 & -4 & -5 & 0 & 5 & 4 & 1 \end{bmatrix} * I$$

- GradientY:

$$G_y = \begin{bmatrix} -1 & -6 & -15 & -20 & -15 & -6 & -1 \\ -4 & -24 & -60 & -80 & -60 & -24 & -4 \\ -5 & -30 & -75 & -100 & -75 & -30 & -5 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 5 & 30 & 75 & 100 & 75 & 30 & 5 \\ 4 & 24 & 60 & 80 & 60 & 24 & 4 \\ 1 & 6 & 15 & 20 & 15 & 6 & 1 \end{bmatrix} * I$$

## API Syntax

```
template<int BORDER_TYPE,int FILTER_TYPE, int SRC_T,int DST_T, int ROWS,
int COLS,int NPC=1>
void Sobel(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat,xf::Mat<DST_T, ROWS,
COLS, NPC> & _dst_matx,xf::Mat<DST_T, ROWS, COLS, NPC> & _dst_maty)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 223: Sobel Function Parameter Descriptions**

Parameter	Description
FILTER_TYPE	Filter size. Filter size of 3(XF_FILTER_3X3), 5(XF_FILTER_5X5) and 7(XF_FILTER_7X7) are supported
BORDER_TYPE	Border Type supported is XF_BORDER_CONSTANT
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
DST_T	Output pixel type. Only 8-bit unsigned, 16-bit signed, 1 channel is supported (XF_8UC1, XF_16SC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_mat	Input image
_dst_matx	X gradient output image.
_dst_maty	Y gradient output image.

1. Sobel 7x7 8-pixel is not supported.

## Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

**Table 224: Sobel Function Resource Utilization Summary**

Operating Mode	Filter Size	Operating Frequency (MHz)	Utilization Estimate				
			BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	3x3	300	3	0	609	616	135
	5x5	300	5	0	1133	1499	308
	7x7	300	7	0	2658	3334	632

Table 224: Sobel Function Resource Utilization Summary (cont'd)

Operating Mode	Filter Size	Operating Frequency (MHz)	Utilization Estimate				
			BRAM_18K	DSP_48Es	FF	LUT	CLB
8 pixel	3x3	150	6	0	1159	1892	341
	5x5	150	10	0	3024	5801	999

### Performance Estimate

The following table summarizes the performance of the kernel in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 225: Sobel Function Performance Estimate Summary

Operating Mode	Operating Frequency (MHz)	Filter Size	Latency Estimate (in ms)
1 pixel	300	3x3	7.5
	300	5x5	7.5
	300	7x7	7.5
8 pixel	150	3x3	1.7
	150	5x5	1.71

## Stereo Local Block Matching

Stereo block matching is a method to estimate the motion of the blocks between the consecutive frames, called stereo pair. The postulate behind this idea is that, considering a stereo pair, the foreground objects will have disparities higher than the background. Local block matching uses the information in the neighboring patch based on the window size, for identifying the conjugate point in its stereo pair. While, the techniques under global method, used the information from the whole image for computing the matching pixel, providing much better accuracy than local methods. But, the efficiency in the global methods are obtained with the cost of resources, which is where local methods stands out.

Local block matching algorithm consists of preprocessing and disparity estimation stages. The preprocessing consists of Sobel gradient computation followed by image clipping. And the disparity estimation consists of SAD (Sum of Absolute Difference) computation and obtaining the disparity using winner takes all method (least SAD will be the disparity). Invalidity of the pixel relies upon its uniqueness from the other possible disparities. And the invalid pixels are indicated with the disparity value of zero.



## API Syntax

```
template <int WSIZE, int NDISP, int NDISP_UNIT, int SRC_T, int DST_T, int
ROWS, int COLS, int NPC = XF_NPPC1>
void StereoBM(xf::Mat<SRC_T, ROWS, COLS, NPC> &_left_mat, xf::Mat<SRC_T,
ROWS, COLS, NPC> &_right_mat, xf::Mat<DST_T, ROWS, COLS, NPC> &_disp_mat,
xf::xFSBMState<WSIZE, NDISP, NDISP_UNIT> &sbmstate);
```

## Parameter Descriptions

The following table describes the template and the function parameters.

*Table 226: StereoBM Function Parameter Descriptions*

Parameter	Description
WSIZE	Size of the window used for disparity computation
NDISP	Number of disparities
NDISP_UNITS	Number of disparities to be computed in parallel.
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
DST_T	Output type. This is XF_16UC1, where the disparities are arranged in Q12.4 format.
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 only.
left_image	Image from the left camera
right_image	Image from the right camera
disparity_image	Disparities output in the form of an image.
sbmstate	Class object consisting of various parameters regarding the stereo block matching algorithm. <ol style="list-style-type: none"> <li>preFilterCap: default value is 31, can be altered by the user, value ranges from 1 to 63</li> <li>minDisparity: default value is 0, can be altered by the user, value ranges from 0 to (imgWidth-NDISP)</li> <li>uniquenessRatio: default set to 15, but can be altered to any non-negative integer.</li> <li>textureThreshold: default set to 10, but can be modified to any non-negative integer.</li> </ol>

## Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to progress a grayscale HD (1080x1920) image.

The configurations are in the format: imageSize\_WSIZE\_NDisp\_NDispUnits.

Table 227: StereoBM Function Resource Utilization Summary

Configurations	Frequency ( MHz)	Resource Utilization			
		BRAM_18k	DSP48E	FF	LUT
HD_5_16_2	300	37	20	6856	7181
HD_9_32_4	300	45	20	9700	10396
HD_11_32_32	300	49	20	34519	31978
HD_15_128_32	300	57	20	41017	35176
HD_21_64_16	300	69	20	29853	30706

### Performance Estimate

The following table summarizes a performance estimate of the Stereo local block matching in different configurations, as generated using Vivado HLS 2018.2 tool for Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

The configurations are in the format: imageSize\_WSIZE\_NDisp\_NDispUnits.

Table 228: StereoBM Function Performance Estimate Summary

Configurations	Frequency ( MHz)	Latency ( ms)	
		Min	Max
HD_5_16_2	300	55.296	55.296
HD_9_32_4	300	55.296	55.296
HD_11_32_32	300	6.912	6.912
HD_15_48_16	300	20.736	20.736
HD_15_128_32	300	27.648	27.648
HD_21_64_16	300	27.648	27.648

## Semi Global Method for Stereo Disparity Estimation

Stereo matching algorithms are used for finding relative depth from a pair of rectified stereo images. The resultant disparity information can be used for 3D reconstruction by triangulation, using the known intrinsic and extrinsic parameters of the stereo camera. The Semi global method for stereo disparity estimation aggregates the cost in terms of dissimilarity across multiple paths leading to a smoother estimate of the disparity map.

For the semi-global method in xfOpenCV, census transform in conjunction with Hamming distance is used for cost computation. The semiglobal optimization block is based on the implementation by Hirschmuller, but approximates the cost aggregation by considering only four directions.

Parallelism is achieved by computing and aggregating cost for multiple disparities in parallel, and this parameter is included as a compile-time input.

### API Syntax

```
template<int BORDER_TYPE, int WINDOW_SIZE, int NDISP, int PU, int R, int SRC_T, int DST_T, int ROWS, int COLS, int NPC>
```

```
void SemiGlobalBM(xf::Mat<SRC_T,ROWS,COLS,NPC> & _src_mat_l,
xf::Mat<SRC_T,ROWS,COLS,NPC> & _src_mat_r, xf::Mat<DST_T,ROWS,COLS,NPC> &
_dst_mat, uint8_t p1, uint8_t p2)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 229: StereoSGM Function Parameter Descriptions*

Parameter	Description
BORDER_TYPE	The border pixels are processed in Census transform function based on this parameter. Only XF_BORDER_CONSTANT is supported.
WINDOW_SIZE	Size of the window used for Census transform computation. Only '5' (5x5) is supported.
NDISP	Number of disparities
PU	Number of disparity units to be computed in parallel
R	Number of directions for cost aggregation. It must be 2, 3, or 4.
SRC_T	Type of input image Mat object. It must be XF_8UC1.
DST_T	Type of output disparity image Mat object. It must be XF_8UC1.
ROWS	Maximum height of the input image.
COLS	Maximum width of the input image.
NPC	Number of pixels to be computed in parallel. It must be XF_NPPC1.
_src_mat_l	Left input image Mat
_src_mat_r	Right input image Mat
_dst_mat	Output disparity image Mat
p1	Small penalty for cost aggregation
p2	Large penalty for cost aggregation. The maximum value is 100.

### Resource Utilization

The following table summarizes the resource utilization for a 1920 x 1080 image, with 64 number of disparities, and 16 parallel units.

**Table 230: StereoSGM Function Resource Utilization Summary**

Operating Mode	Filter Size	Operating Frequency (MHz)	Resource Utilization			
			BRAM_18k	DSP48E	FF	LUT
1 pixel	5x5	300	205	78	10847	12498

### Performance Estimate

The following table summarizes a performance estimate for a 1920x1080 image.

**Table 231: StereoSGM Function Performance Estimate Summary**

Operating Mode	Operating Frequency	Number of Disparities	Parallel Units	Latency
1 pixel/clock	300 MHz	64	16	50 ms

## SVM

The `SVM` function is the SVM core operation, which performs dot product between the input arrays. The function returns the resultant dot product value with its fixed point type.

### API Syntax

```
template<int SRC1_T, int SRC2_T, int DST_T, int ROWS1, int COLS1, int
ROWS2, int COLS2, int NPC=1, int N>
void SVM(xf::Mat<SRC1_T, ROWS1, COLS1, NPC> &in_1, xf::Mat<SRC2_T, ROWS2,
COLS2, NPC> &in_2, uint16_t idx1, uint16_t idx2, uchar_t frac1, uchar_t
frac2, uint16_t n, uchar_t *out_frac, ap_int<XF_PIXELDEPTH(DST_T)> *result)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

**Table 232: SVM Function Parameter Descriptions**

Parameters	Description
SRC1_T	Input pixel type. 16-bit, signed, 1 channel (XF_16SC1) is supported.
SRC2_T	Input pixel type. 16-bit, signed, 1 channel (XF_16SC1) is supported.
DST_T	Output data Type. 32-bit, signed, 1 channel (XF_32SC1) is supported.
ROWS1	Number of rows in the first image being processed.
COLS1	Number of columns in the first image being processed.
ROWS2	Number of rows in the second image being processed.
COLS2	Number of columns in the second image being processed.

Table 232: SVM Function Parameter Descriptions (cont'd)

Parameters	Description
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1.
N	Max number of kernel operations
in_1	First Input Array.
in_2	Second Input Array.
idx1	Starting index of the first array.
idx2	Starting index of the second array.
frac1	Number of fractional bits in the first array data.
frac2	Number of fractional bits in the second array data.
n	Number of kernel operations.
out_frac	Number of fractional bits in the resultant value.
result	Resultant value

## Resource Utilization

The following table summarizes the resource utilization of the SVM function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

Table 233: SVM Function Resource Utilization Summary

Operating Frequency (MHz)	Utilization Estimate (ms)				
	BRAM_18K	DSP_48Es	FF	LUT	CLB
300	0	1	27	34	12

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

Table 234: SVM Function Performance Estimate Summary

Operating Frequency (MHz)	Latency Estimate	
	Min (cycles)	Max (cycles)
300	204	204

## Thresholding

The `Threshold` function performs thresholding operation on the input image. Thresholding are of two types, binary and range.

In the Binary thresholding, the threshold value will be set and the depending upon the threshold value the output is set to either 0 or 255. The `_binary_thresh_val` has to be set to the threshold value when the binary thresholding is selected, as well as the `_upper_range` and `_lower_range` has to be set to 0.

$$dst(x, y) = \begin{cases} 255, & \text{if } src(x, y) > \text{threshold} \\ 0, & \text{Otherwise} \end{cases}$$

In the Range thresholding, the upper and the lower threshold values are set and depending upon those values the output is set either 0 or 255. The `_upper_range` and `_lower_range` values has to be set to the upper and the lower threshold values respectively, when the range thresholding is selected, as well as in this case the `_binary_thresh_val` has to be set to 0.

$$dst(x, y) = \begin{cases} 0, & \text{if } src(x, y) > \text{upper} \\ 0, & \text{if } src(x, y) < \text{lower} \\ 255, & \text{otherwise} \end{cases}$$

## API Syntax

```
template<int THRESHOLD_TYPE, int SRC_T, int ROWS, int COLS, int NPC=1>
void Threshold(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src_mat, xf::Mat<SRC_T,
ROWS, COLS, NPC> & _dst_mat, short thresh_val, short thresh_upper, short
thresh_lower)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 235: Threshold Function Parameter Descriptions**

Parameter	Description
THRESHOLD_TYPE	Type of thresholding. It can be either binary thresholding or range thresholding. Options are XF_THRESHOLD_TYPE_BINARY or XF_THRESHOLD_TYPE_RANGE.
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle.
_src_mat	Input image
_dst_mat	Output image

## Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

Table 236: Threshold Function Resource Utilization Summary

Configurations	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150MHz
BRAM_18K	0	0
DSP48E	3	3
FF	410	469
LUT	277	443
CLB	72	103

### Performance Estimate

The following table summarizes the performance of the kernel in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 237: Threshold Function Performance Estimate Summary

Operating Mode	Operating Frequency (MHz)	Latency Estimate (ms)
1 pixel	300	7.2
8 pixel	150	1.7

## WarpAffine

Affine Transformation is used to express rotation, scaling and translation operations.

`warpAffine` takes inverse transformation as input and transforms the input image by matrix multiplication with 2x3 matrix. Calculate the input position corresponding to every output pixel in the following way.

$$\begin{bmatrix} x_{input} \\ y_{input} \end{bmatrix} = \begin{bmatrix} M_{0,0} & M_{0,1} & M_{0,2} \\ M_{1,0} & M_{1,1} & M_{1,2} \end{bmatrix} \begin{bmatrix} x_{output} \\ y_{output} \\ 1 \end{bmatrix}$$

$$x_{input} = M_{0,0} * x_{output} + M_{0,1} * y_{output} + M_{0,2}$$

$$y_{input} = M_{1,0} * x_{output} + M_{1,1} * y_{output} + M_{1,2}$$

$$output(x_{output}, y_{output}) = input(x_{input}, y_{input})$$

**Note:** Prior scaling of greater than or equal to 0.25 and less than or equal to 8 are supported and throws an assertion if the transformation matrix passed is having unsupported scaling factors.

## API Syntax

```
template<int INTERPOLATION_TYPE, int SRC_T, int ROWS, int COLS, int NPC=1>
void warpAffine(xf::Mat<SRC_T, ROWS, COLS, XF_NPPC8> & _src,
xf::Mat<SRC_T, ROWS, COLS, XF_NPPC8> & _dst, float* transformation_matrix)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

*Table 238: warpAffine Function Parameter Descriptions*

Parameter	Description
INTERPOLATION_TYPE	Interpolation technique to be used XF_INTERPOLATION_NN - Nearest Neighbor XF_INTERPOLATION_BILINEAR - Bilinear
SRC_T	Input pixel type.
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input Image pointer
_dst	Output Image pointer
transformation_matrix	Inverse Affine Transformation matrix

## Resource Utilization

The following table shows the resource utilization of warpAffine in different configurations as generated in Vivado HLS 2018.2 version tool for the part Xilinx Xczu9eg-ffvb1156-1-i-es1.

*Table 239: warpAffine Function Resource Utilization Summary*

Name	Utilization (at 250 MHz)			
	Normal Operation (1 pixel) Mode		Resource Optimized (8 pixel) Mode	
	Nearest Neighbour	Bilinear Interpolation	Nearest Neighbour	Bilinear Interpolation
BRAM	200	194	200	200
DSP48E	121	125	139	155
FF	9523	10004	8070	9570
LUT	9928	10592	13296	13894



Table 239: warpAffine Function Resource Utilization Summary (cont'd)

Name	Utilization (at 250 MHz)			
	Normal Operation (1 pixel) Mode		Resource Optimized (8 pixel) Mode	
	Nearest Neighbour	Bilinear Interpolation	Nearest Neighbour	Bilinear Interpolation
CLB	2390	2435	2932	2829

**Note:** NO is single pixel processing and RO is 4-pixel processing.

### Performance Estimate

The following table shows the performance of Affine Transformation in different configurations, as generated in Vivado HLS 2018.2 version tool for the part Xilinx Xczu9eg-ffvb1156-1-i-es1.

Table 240: warpAffine Function Performance Estimate Summary

Latency Estimate			
1 pixel (300 MHz)		8 pixel (150 MHz)	
Nearest Neighbour	Bilinear Interpolation	Nearest Neighbour	Bilinear Interpolation
Max(in ms)	Max(in ms)	Max(in ms)	Max(in ms)
10.4	19.3	10.7	10.4

## WarpPerspective

The `warpPerspective` function performs the perspective transformation on the image. It takes inverse transformation as input and applies perspective transformation with a 3x3 matrix.

Calculate the input position corresponding to every output pixel as following:

$$\begin{bmatrix} x \\ y \\ z \end{bmatrix} = \begin{bmatrix} M_{0,0} & M_{0,1} & M_{0,2} \\ M_{1,0} & M_{1,1} & M_{1,2} \\ M_{2,0} & M_{2,1} & M_{2,2} \end{bmatrix} \begin{bmatrix} x_{output} \\ y_{output} \\ 1 \end{bmatrix}$$

$$x = M_{0,0} * x_{output} + M_{0,1} * y_{output} + M_{0,2}$$

$$y = M_{1,0} * x_{output} + M_{1,1} * y_{output} + M_{1,2}$$

$$z = M_{2,0} * x_{output} + M_{2,1} * y_{output} + M_{2,2}$$

$$output(x_{output}, y_{output}) = input(x/z, y/z)$$

**Note:** Prior scaling of greater than or equal to 0.25 and less than or equal to 8 are supported and throws an assertion if the transformation matrix passed is having unsupported scaling factors.

## API Syntax

```
template< int INTERPOLATION_TYPE ,int SRC_T, int ROWS, int COLS,int NPC>
void warpPerspective(xf::Mat<SRC_T, ROWS, COLS, XF_NPPC8> &
_src_mat,xf::Mat<SRC_T, ROWS, COLS, XF_NPPC8> & _dst_mat,float
*transformation_matrix)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 241: warpPerspective Function Parameter Descriptions**

Parameter	Description
INTERPOLATION_TYPE	Interpolation technique to be used XF_INTERPOLATION_NN - Nearest Neighbour XF_INTERPOLATION_BILINEAR - Bilinear
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (must be a multiple of 8)
COLS	Maximum width of input and output image (must be a multiple of 8)
NPC	Number of pixels to be processed per cycle; possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src_mat	Input image
_dst_mat	Output image
transformation_matrix	Inverse Perspective Transformation matrix

## Resource Utilization

The following table summarizes the resource utilization of the kernel in different configurations, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image for Bilinear interpolation.

**Table 242: warpPerspective Function Resource Utilization Summary**

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
BRAM_18K	223	233

Table 242: **warpPerspective** Function Resource Utilization Summary (cont'd)

Name	Resource Utilization	
	1 pixel	8 pixel
	300 MHz	150 MHz
DSP48E	191	293
FF	17208	14330
LUT	14458	18969
CLB	3230	3876

### Performance Estimate

The following table summarizes the performance of kernel for different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image for Bilinear interpolation.

 Table 243: **warpPerspective** Function Performance Estimate Summary

Operating Mode	Operating Frequency (MHz)	Latency Estimate
		Max (ms)
1 pixel	300	19.3
8 pixel	150	15.5

## Atan2

The `Atan2LookupFP` function finds the arctangent of  $y/x$ . It returns the angle made by the vector  $\begin{bmatrix} x \\ y \end{bmatrix}$  with respect to origin. The angle returned by `atan2` will also contain the quadrant information.

`Atan2LookupFP` is a fixed point version of the standard `atan2` function. This function implements the `atan2` using a lookup table approach. The values in the look up table are represented in Q4.12 format and so the values returned by this function are in Q4.12. A maximum error of 0.2 degrees is present in the range of 89 to 90 degrees when compared to the standard `atan2` function available in `glibc`. For the other angles (0 to 89) the maximum error is in the order of 10<sup>-3</sup>. This function returns 0 when both `xs` and `ys` are zeroes.

### API Syntax

```
short Atan2LookupFP(short xs, short ys, int M1,int N1,int M2, int N2)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 244: Atan2LookupFP Function Parameter Descriptions**

Parameter	Description
xs	16-bit signed value x in fixed point format of QM1.N1
ys	16-bit signed value y in fixed point format of QM2.N2
M1	Number of bits to represent integer part of x.
N1	Number of bits to represent fractional part of y. Must be equal to 16-M1.
M2	Number of bits to represent integer part of y.
N2	Number of bits to represent fractional part of y. Must be equal to 16-N1.
Return	Return value is in radians. Its range varies from -pi to +pi in fixed point format of Q4.12

## Resource Utilization

The following table summarizes the resource utilization of the `Atan2LookupFP` function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

**Table 245: Atan2LookupFP Function Resource Utilization Summary**

Operating Frequency (MHz)	Utilization Estimate				
	BRAM_18K	DSP_48Es	FF	LUT	CLB
300	4	2	275	75	139

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

**Table 246: Atan2LookupFP Function Performance Estimate Summary**

Operating Frequency (MHz)	Latency Estimate	
	Min (cycles)	Max (cycles)
300	1	15

## Inverse (Reciprocal)

The `Inverse` function computes the reciprocal of a number  $x$ . The values of  $1/x$  are stored in a look up table of 2048 size. The index for picking the  $1/x$  value is computed using the fixed point format of  $x$ . Once this index is computed, the corresponding  $1/x$  value is fetched from the look up table and returned along with the number of fractional bits needed to represent this value in fixed point format.

### API Syntax

```
unsigned int Inverse(unsigned short x,int M,char *N)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 247: Inverse Function Parameter Descriptions*

Parameter	Description
x	16-bit unsigned value x in fixed point format of QM.(16-M)
M	Number of bits to represent integer part of x.
N	Pointer to a char variable which stores the number of bits to represent fractional part of $1/x$ . This value is returned from the function.
Return	$1/x$ value is returned in 32-bit format represented by a fixed point format of Q(32-N).N

### Resource Utilization

The following table summarizes the resource utilization of the Inverse function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

*Table 248: Inverse Function Resource Utilization Summary*

Operating Frequency (MHz)	Utilization Estimate (ms)				
	BRAM_18K	DSP_48Es	FF	LUT	CLB
300	4	0	68	128	22

### Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

Table 249: Inverse Function Performance Estimate Summary

Operating Frequency (MHz)	Latency Estimate	
	Min (cycles)	Max (cycles)
300	1	8

## Look Up Table

The LUT function performs the table lookup operation. Transforms the source image into the destination image using the given look-up table. The input image must be of depth AU\_8UP and the output image of same type as input image.

$$I_{out}(x, y) = LUT [I_{in1}(x, y)]$$

Where:

- $I_{out}(x, y)$  is the intensity of output image at (x, y) position
- $I_{in}(x, y)$  is the intensity of first input image at (x, y) position
- LUT is the lookup table of size 256 and type unsigned char.

### API Syntax

```
template <int SRC_T, int ROWS, int COLS, int NPC=1>
void LUT(xf::Mat<SRC_T, ROWS, COLS, NPC> & _src, xf::Mat<SRC_T, ROWS,
COLS, NPC> & _dst, unsigned char* _lut)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

Table 250: LUT Function Parameter Descriptions

Parameter	Description
SRC_T	Input pixel type. 8-bit, unsigned, 1 channel (XF_8UC1) is supported.
ROWS	Number of rows in the image being processed.
COLS	Number of columns in the image being processed.
NPC	Number of pixels to be processed in parallel. Possible options are XF_NPPC1 and XF_NPPC8 for 1 pixel and 8 pixel operations respectively.
_src	Input image of size (ROWS, COLS) and type 8U.
_dst	Output image of size (ROWS, COLS) and same type as input.
_lut	Input lookup Table of size 256 and type unsigned char.

## Resource Utilization

The following table summarizes the resource utilization of the LUT function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

Table 251: LUT Function Resource Utilization Summary

Operating Mode	Operating Frequency (MHz)	Utilization Estimate				
		BRAM_18K	DSP_48Es	FF	LUT	CLB
1 pixel	300	1	0	937	565	137
8 pixel	150	9	0	1109	679	162

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1, to process a grayscale HD (1080x1920) image.

Table 252: LUT Function Performance Estimate Summary

Operating Mode	Latency Estimate
	Max Latency
1 pixel operation (300 MHz)	6.92 ms
8 pixel operation (150 MHz)	1.66 ms

## Square Root

The `Sqrt` function computes the square root of a 16-bit fixed point number using the non-restoring square root algorithm. The non-restoring square root algorithm uses the two's complement representation for the square root result. At each iteration the algorithm can generate exact result value even in the last bit.

Input argument `D` must be 16-bit number, though it is declared as 32-bit. The output `sqrt(D)` is 16-bit type. If format of `D` is `QM.N` (where  $M+N = 16$ ) then format of output is `Q(M/2).N`

To get a precision of 'n' bits in fractional part, you can simply left shift the radicand (`D`) by '2n' before the function call and shift the solution right by 'n' to get the correct answer. For example, to find the square root of 35 (011000112) with one bit after the decimal point, that is,  $N=1$ :

1. Shift the number (01100011002) left by 2
2. Shift the answer (10112) right by 1. The correct answer is 101.1, which is 5.5.

## API Syntax

```
int Sqrt(unsigned int D)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 253: Sqrt Function Parameter Descriptions**

Parameter	Description
D	Input data in a 16-bit fixed-point format.
Return	Output value in short int format.

## Resource Utilization

The following table summarizes the resource utilization of the Sqrt function, generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

**Table 254: Sqrt Function Resource Utilization Summary**

Operating Frequency (MHz)	Utilization Estimate				
	BRAM_18K	DSP_48Es	FF	LUT	CLB
300	0	0	8	6	1

## Performance Estimate

The following table summarizes the performance in different configurations, as generated using Vivado HLS 2018.2 tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA.

**Table 255: Sqrt Function Performance Estimate Summary**

Operating Frequency (MHz)	Latency Estimate	
	Min (cycles)	Max (cycles)
300	18	18

## WarpTransform

The `warpTransform` function is designed to perform the perspective and affine geometric transformations on an image. The type of transform is a compile time parameter to the function.



The function uses a streaming interface to perform the transformation. Due to this and due to the fact that geometric transformations need access to many different rows of input data to compute one output row, the function stores some rows of the input data in BRAMs. The number of rows the function stores can be configured by the user by modifying a template parameter. Based on the transformation matrix, you can decide on the number of rows to be stored. You can also choose when to start transforming the input image in terms of the number of rows of stored image.

### Affine Transformation

The transformation matrix consists of size parameters, and is as shown:

$$M = \begin{bmatrix} M_{11} & M_{12} & M_{13} \\ M_{21} & M_{22} & M_{23} \end{bmatrix}$$

Affine transformation is applied in the warpTransform function following the equation:

$$dst \begin{pmatrix} x \\ y \end{pmatrix} = M * src \begin{pmatrix} x \\ y \\ 1 \end{pmatrix}$$

### Perspective Transformation

The transformation matrix is a 3x3 matrix as shown below:

$$M = \begin{bmatrix} M_{11} & M_{12} & M_{13} \\ M_{21} & M_{22} & M_{23} \\ M_{31} & M_{32} & M_{33} \end{bmatrix}$$

Perspective transformation is applied in warpTransform following the equation:

$$dst^1 \begin{pmatrix} x \\ y \\ n \end{pmatrix} = M * src \begin{pmatrix} x \\ y \\ 1 \end{pmatrix}$$

The destination pixel is then computed by dividing the first two dimensions of the dst1 by the third dimension

$$dst^1 \begin{pmatrix} x \\ y \\ n \end{pmatrix} = M * src \begin{pmatrix} x \\ y \\ 1 \end{pmatrix}$$

## API Syntax

```
template<int STORE_LINES, int START_ROW, int TRANSFORMATION_TYPE, int
INTERPOLATION_TYPE, int SRC_T, int ROWS, int COLS, int NPC=1>
void warpTransform(xf::Mat<SRC_T, ROWS, COLS, NPC> & src, xf::Mat<SRC_T,
ROWS, COLS, NPC> & dst, float *transformation_matrix)
```

## Parameter Descriptions

The following table describes the template and the function parameters.

**Table 256: warpTransform Function Parameter Descriptions**

Parameter	Description
STORE_LINES	Number of lines of the image that need to be buffered locally on FPGA.
START_ROW	Number of the input rows to store before starting the image transformation. This must be less than or equal to STORE_LINES.
TRANSFORMATION_TYPE	Affine and perspective transformations are supported. Set this flag to '0' for affine and '1' for perspective transformation.
INTERPOLATION_TYPE	Set flag to '1' for bilinear interpolation and '0' for nearest neighbor interpolation.
SRC_T	Input pixel type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image.
COLS	Maximum width of input and output image.
NPC	Number of pixels to be processed per cycle; only one-pixel operation supported (XF_NPPC1).
src	Input image
dst	Output image
transformation_matrix	Transformation matrix that is applied to the input image.

## Resource Utilization

The following table summarizes the resource utilization of the Warp transform, generated using Vivado HLS 2018.2 version tool for the Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to progress a grayscale HD (1080x1920) image.

**Table 257: warpTransform Function Resource Utilization Summary**

Transformation	INTERPOLATION_TYPE	STORE_LINES	START_ROW	Operating Frequency (MHz)	Utilization Estimate			
					LUTs	FFs	DSPs	BRAMs
Perspective	Bilinear	100	50	300	7468	9804	61	112
Perspective	Nearest Neighbor	100	50	300	4514	6761	35	104
Affine	Bilinear	100	50	300	6139	5606	40	124
Affine	Nearest Neighbor	100	50	300	4611	4589	18	112

## Performance Estimate

The following table summarizes a performance estimate of the Warp transform, as generated using Vivado HLS 2018.2 tool for Xilinx Xczu9eg-ffvb1156-1-i-es1 FPGA, to process a grayscale HD (1080x1920) image.

*Table 258: warpTransform Function Performance Estimate Summary*

Transformation	INTERPOLATION _TYPE	STORE _LINES	START _ROW	Operating Frequency (MHz)	Latency Estimate Max (ms)
Perspective	Bilinear	100	50	300	7.46
Perspective	Nearest Neighbor	100	50	300	7.31
Affine	Bilinear	100	50	300	7.31
Affine	Nearest Neighbor	100	50	300	7.24

# Design Examples Using xfOpenCV Library

All the hardware functions in the library have their own respective examples that are available in the github. This section provides details of image processing functions and pipelines implemented using a combination of various functions in xfOpenCV. They illustrate how to best implement various functionalities using the capabilities of both the processor and the programmable logic. These examples also illustrate different ways to implement complex dataflow paths. The following examples are described in this section:

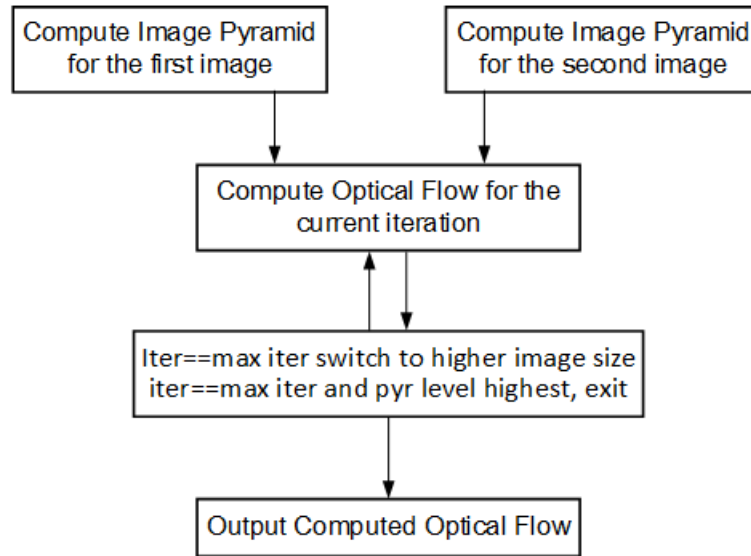
- [Iterative Pyramidal Dense Optical Flow](#)
- [Corner Tracking Using Sparse Optical Flow](#)
- [Color Detection](#)
- [Difference of Gaussian Filter](#)
- [Stereo Vision Pipeline](#)

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## Iterative Pyramidal Dense Optical Flow

The Dense Pyramidal Optical Flow example uses the `xf::pyrDown` and `xf::densePyrOpticalFlow` hardware functions from the xfOpenCV library, to create an image pyramid, iterate over it and compute the Optical Flow between two input images. The example uses two hardware instances of the `xf::pyrDown` function to compute the image pyramids of the two input images in parallel. The two image pyramids are processed by one hardware instance of the `xf::densePyrOpticalFlow` function, starting from the smallest image size going up to the largest image size. The output flow vectors of each iteration are fed back to the hardware kernel as input to the hardware function. The output of the last iteration on the largest image size is treated as the output of the dense pyramidal optical flow example.

Figure 9: Iterative Pyramidal Dense Optical Flow



Specific details of the implementation of the example on the host follow to help understand the process in which the claimed throughput is achieved.

## pyrof\_hw()

The `pyrof_hw()` is the host function that computes the dense optical flow.

### API Syntax

```

void pyrof_hw(cv::Mat im0, cv::Mat im1, cv::Mat flowUmat, cv::Mat
flowVmat, xf::Mat<XF_32UC1,HEIGHT,WIDTH,XF_NPPC1> & flow,
xf::Mat<XF_32UC1,HEIGHT,WIDTH,XF_NPPC1> & flow_iter,
xf::Mat<XF_8UC1,HEIGHT,WIDTH,XF_NPPC1> mat_imagepyr1[ NUM_LEVELS ] ,
xf::Mat<XF_8UC1,HEIGHT,WIDTH,XF_NPPC1> mat_imagepyr2[ NUM_LEVELS ] , int
pyr_h[ NUM_LEVELS ], int pyr_w[ NUM_LEVELS ])
    
```

### Parameter Descriptions

The table below describes the template and the function parameters.

Parameter	Description
im0	First input image in cv::Mat
im1	Second input image in cv::Mat
flowUmat	Allocated cv::Mat to store the horizontal component of the output flow vector
flowVmat	Allocated cv::Mat to store the vertical component of the output flow vector
flow	Allocated xf::Mat to temporarily store the packed flow vectors, during the iterative computation using the hardware function

Parameter	Description
flow_iter	Allocated xf::Mat to temporarily store the packed flow vectors, during the iterative computation using the hardware function
mat_imagepyr1	An array, of size equal to the number of image pyramid levels, of xf::Mat to store the image pyramid of the first image
mat_imagepyr2	An array, of size equal to the number of image pyramid levels, of xf::Mat to store the image pyramid of the second image
pyr_h	An array of integers which includes the size of number of image pyramid levels, to store the height of the image at each pyramid level
pyr_w	An array of integers which includes the size of the number of image pyramid levels, to store the width of the image at each pyramid level

## Dataflow

The `pyrof_hw()` function performs the following:

1. Set the sizes of the images in various levels of the image pyramid
2. Copy input images from `cv::Mat` format to the `xf::Mat` object allocated to contain the largest image pyramid level
3. Create the image pyramid calling the `pyr_dense_optical_flow_pyr_down_accel()` function
4. Use the `pyr_dense_optical_flow_accel()` function to compute the optical flow output by iterating over the pyramid levels as input by the user
5. Unpack the flow vectors and convert them to the floating point, and return

The important steps 3 and 4 in the above processes will be explained in detail.

## pyr\_dense\_optical\_flow\_pyr\_down\_accel()

### API Syntax

```
void
pyr_dense_optical_flow_pyr_down_accel(xf::Mat<XF_8UC1,HEIGHT,WIDTH,XF_NPPC1
> mat_imagepyr1[ NUM_LEVELS], xf::Mat<XF_8UC1,HEIGHT,WIDTH,XF_NPPC1>
mat_imagepyr2[ NUM_LEVELS])
```

### Parameter Descriptions

The table below describes the template and the function parameters.

Parameter	Description
mat_imagepyr1	An array, of size equal to the number of image pyramid levels, of <code>xf::Mat</code> to store the image pyramid of the first image. The memory location corresponding to the highest pyramid level [0] in this allocated memory must contain the first input image.

Parameter	Description
mat_imagepyr2	An array, of size equal to the number of image pyramid levels, of xf::Mat to store the image pyramid of the second image. The memory location corresponding to the highest pyramid level [0] in this allocated memory must contain the second input image.

The `pyr_dense_optical_flow_pyr_down_accel()` just runs one for loop calling the `xf::pyrDown` hardware function as follows:

```

for(int pyr_comp=0;pyr_comp<NUM_LEVELS-1; pyr_comp++)
{
    #pragma SDS async(1)
    #pragma SDS resource(1)

    xf::pyrDown<XF_8UC1,HEIGHT,WIDTH,XF_NPPC1>(mat_imagepyr1[pyr_comp],
    mat_imagepyr1[pyr_comp+1]);
    #pragma SDS async(2)
    #pragma SDS resource(2)

    xf::pyrDown<XF_8UC1,HEIGHT,WIDTH,XF_NPPC1>(mat_imagepyr2[pyr_comp],
    mat_imagepyr2[pyr_comp+1]);
    #pragma SDS wait(1)
    #pragma SDS wait(2)
}
    
```

The code is straightforward without the pragmas, and the `xf::pyrDown` function is being called twice every iteration. First with the first image and then with the second image. Note that the input to the next iteration is the output of the current iteration. The pragma `#pragma SDS async(ID)` makes the Arm® processor call the hardware function and not wait for the hardware function to return. The Arm processor takes some cycles to call the function, which includes programming the DMA. The pragma `#pragma SDS wait(ID)` makes the Arm processor wait for the hardware function called with the `async(ID)` pragma to finish processing. The pragma `#pragma SDS resource(ID)` creates a separate hardware instance each time the hardware function is called with a different ID. With this new information it is easy to assimilate that the loop in the above host function calls the two hardware instances of `xf::pyrDown` functions in parallel, waits until both the functions return and proceed to the next iteration.

## Dense Pyramidal Optical Flow Computation

```

for (int l=NUM_LEVELS-1; l>=0; l--) {
    //compute current level height
    int curr_height = pyr_h[l];
    int curr_width = pyr_w[l];

    //compute the flow vectors for the current pyramid level
    iteratively
    for(int iterations=0;iterations<NUM_ITERATIONS; iterations++)
    {
        bool scale_up_flag = (iterations==0)&&(l != NUM_LEVELS-1);
        int next_height = (scale_up_flag==1)?pyr_h[l+1]:pyr_h[l];
        int next_width = (scale_up_flag==1)?pyr_w[l+1]:pyr_w[l];
        float scale_in = (next_height - 1)*1.0/(curr_height - 1);
        ap_uint<1> init_flag = ((iterations==0) && (l==NUM_LEVELS-1))?
    
```

```

1 : 0;
        if(flag_flowin)
        {
            flow.rows = pyr_h[1];
            flow.cols = pyr_w[1];
            flow.size = pyr_h[1]*pyr_w[1];
            pyr_dense_optical_flow_accel(mat_imagepyr1[1],
mat_imagepyr2[1], flow_iter, flow, 1, scale_up_flag, scale_in, init_flag);
            flag_flowin = 0;
        }
        else
        {
            flow_iter.rows = pyr_h[1];
            flow_iter.cols = pyr_w[1];
            flow_iter.size = pyr_h[1]*pyr_w[1];
            pyr_dense_optical_flow_accel(mat_imagepyr1[1],
mat_imagepyr2[1], flow, flow_iter, 1, scale_up_flag, scale_in, init_flag);
            flag_flowin = 1;
        }
    } //end iterative optical flow computation
} // end pyramidal iterative optical flow HLS computation
    
```

The Iterative Pyramidal Dense Optical Flow is computed in a nested for loop which runs for iterations\*pyramid levels number of iterations. The main loop starts from the smallest image size and iterates up to the largest image size. Before the loop iterates in one pyramid level, it sets the current pyramid level's height and width, in curr\_height and current\_width variables. In the nested loop, the next\_height variable is set to the previous image height if scaling up is necessary, that is, in the first iterations. As divisions are costly and one time divisions can be avoided in hardware, the scale factor is computed in the host and passed as an argument to the hardware kernel. After each pyramid level, in the first iteration, the scale-up flag is set to let the hardware function know that the input flow vectors need to be scaled up to the next higher image size. Scaling up is done using bilinear interpolation in the hardware kernel.

After all the input data is prepared, and the flags are set, the host processor calls the hardware function. Please note that the host function swaps the flow vector inputs and outputs to the hardware function to iteratively solve the optimization problem. Also note that the `pyr_dense_optical_flow_accel()` function is just a wrapper to the hardware function `xf::densePyrOpticalFlow`. Template parameters to the hardware function are passed inside this wrapper function.



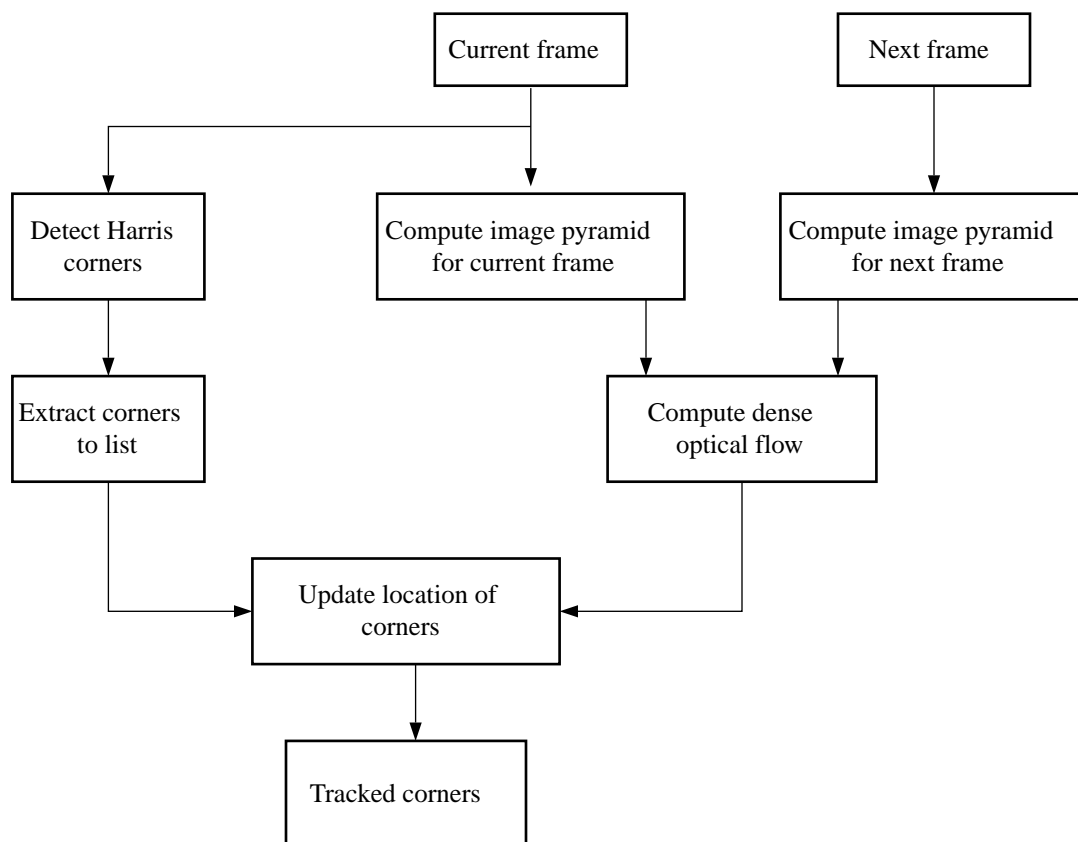
## Corner Tracking Using Sparse Optical Flow

This example illustrates how to detect and track the characteristic feature points in a set of successive frames of video. A Harris corner detector is used as the feature detector, and a modified version of Lucas Kanade optical flow is used for tracking. The core part of the algorithm takes in current and next frame as the inputs and outputs the list of tracked corners. If the current image is the first frame in the set, then corner detection is performed to detect the features to track. The number of frames in which the points need to be tracked is also provided as the input.

Corner tracking example uses five hardware functions from the xfOpenCV library

`xf::cornerHarris`, `xf::cornersImgToList`, `xf::cornerUpdate`, `xf::pyrDown`, and `xf::densePyrOpticalFlow`.

Figure 10: Corner Tracking Using Sparse Optical Flow



A new hardware function, `xf::cornerUpdate`, has been added to ensure that the dense flow vectors from the output of the `xf::densePyrOpticalFlow` function are sparsely picked and stored in a new memory location as a sparse array. This was done to ensure that the next function in the pipeline would not have to surf through the memory by random accesses. The function takes corners from Harris corner detector and dense optical flow vectors from the dense pyramidal optical flow function and outputs the updated corner locations, tracking the input corners using the dense flow vectors, thereby imitating the sparse optical flow behavior. This hardware function runs at 300 MHz for 10,000 corners on a 720p image, adding very minimal latency to the pipeline.

## cornerUpdate()

### API Syntax

```
template <unsigned int MAXCORNERSNO, unsigned int TYPE, unsigned int ROWS,
unsigned int COLS, unsigned int NPC>
void cornerUpdate(ap_uint<64> *list_fix, unsigned int *list, uint32_t
nCorners, xf::Mat<TYPE,ROWS,COLS,NPC> &flow_vectors, ap_uint<1>
harris_flag)
```

### Parameter Descriptions

The following table describes the template and the function parameters.

*Table 259: CornerUpdate Function Parameter Descriptions*

Parameter	Description
MAXCORNERSNO	Maximum number of corners that the function needs to work on
TYPE	Input Pixel Type. Only 8-bit, unsigned, 1 channel is supported (XF_8UC1)
ROWS	Maximum height of input and output image (Must be multiple of 8)
COLS	Maximum width of input and output image (Must be multiple of 8)
NPC	Number of pixels to be processed per cycle. This function supports only XF_NPPC1 or 1-pixel per cycle operations.
list_fix	A list of packed fixed point coordinates of the corner locations in 16, 5 (16 integer bits and 5 fractional bits) format. Bits from 20 to 0 represent the column number, while the bits 41 to 21 represent the row number. The rest of the bits are used for flag, this flag is set when the tracked corner is valid.
list	A list of packed positive short integer coordinates of the corner locations in unsigned short format. Bits from 15 to 0 represent the column number, while the bits 31 to 16 represent the row number. This list is same as the list output by Harris Corner Detector.
nCorners	Number of corners to track
flow_vectors	Packed flow vectors as in <code>xf::DensePyrOpticalFlow</code> function
harris_flag	If set to 1, the function takes input corners from list. if set to 0, the function takes input corners from list_fix.

The example codeworks on an input video which is read and processed using the xfOpenCV library. The core processing and tracking is done by the `xf_corner_tracker_accel()` function at the host.

## cornersImgToList()

### API Syntax

```
template <unsigned int MAXCORNERSNO, unsigned int TYPE, unsigned int ROWS,
unsigned int COLS, unsigned int NPC>
void cornersImgToList(xf::Mat<TYPE,ROWS,COLS,NPC> &_src, unsigned int
list[MAXCORNERSNO], unsigned int *ncorners)
```

### Parameter Descriptions

The following table describes the template and theKintex® UltraScale+™ function parameters.

*Table 260: CornerImgToList Function Parameter Descriptions*

Parameter	Description
<code>_src</code>	The output image of harris corner detector. The size of this <code>xf::Mat</code> object is the size of the input image to Harris corner detector. The value of each pixel is 255 if a corner is present in the location, 0 otherwise.
<code>list</code>	A 32 bit memory allocated, the size of MAXCORNERS, to store the corners detected by Harris Detector
<code>ncorners</code>	Total number of corners detected by Harris, that is, the number of corners in the list

## cornerTracker()

The `xf_corner_tracker_accel()` function does the core processing and tracking at the host.

### API Syntax

```
void cornerTracker(xf::Mat<XF_32UC1,HEIGHT,WIDTH,XF_NPPC1> & flow,
xf::Mat<XF_32UC1,HEIGHT,WIDTH,XF_NPPC1> & flow_iter,
xf::Mat<XF_8UC1,HEIGHT,WIDTH,XF_NPPC1> mat_imagepyr1[ NUM_LEVELS ] ,
xf::Mat<XF_8UC1,HEIGHT,WIDTH,XF_NPPC1> mat_imagepyr2[ NUM_LEVELS ] ,
xf::Mat<XF_8UC1, HEIGHT, WIDTH, XF_NPPC1> &inHarris, xf::Mat<XF_8UC1,
HEIGHT, WIDTH, XF_NPPC1> &outHarris, unsigned int *list, ap_uint<64>
*listfixed, int pyr_h[ NUM_LEVELS ], int pyr_w[ NUM_LEVELS ], unsigned int
*num_corners, unsigned int harrisThresh, bool *harris_flag)
```

### Parameter Descriptions

The table below describes the template and the function parameters.

Parameter	Description
flow	Allocated xf::Mat to temporarily store the packed flow vectors during the iterative computation using the hardware function
flow_iter	Allocated xf::Mat to temporarily store the packed flow vectors during the iterative computation using the hardware function
mat_imagepyr1	
mat_imagepyr2	An array, of size equal to the number of image pyramid levels, of xf::Mat to store the image pyramid of the second image An array, of size equal to the number of image pyramid levels, of xf::Mat to store the image pyramid of the first image
inHarris	Input image to Harris Corner Detector in xf::Mat
outHarris	Output image from Harris detector. Image has 255 if a corner is present in the location and 0 otherwise
list	A 32 bit memory allocated, the size of MAXCORNERS, to store the corners detected by Harris Detector
listfixed	A 64 bit memory allocated, the size of MAXCORNERS, to store the corners tracked by xf::cornerUpdate
pyr_h	An array of integers the size of number of image pyramid levels to store the height of the image at each pyramid level
pyr_w	An array of integers the size of number of image pyramid levels to store the width of the image at each pyramid level
num_corners	An array, of size equal to the number ofNumber of corners detected by Harris Corner Detector
harrisThresh	Threshold input to the Harris Corner Detector, xf::harris
harris_flag	Flag used by the caller of this function to use the corners detected by xf::harris for the set of input images

## Image Processing

The following steps demonstrate the Image Processing procedure in the hardware pipeline

1. `xf::cornerharris` is called to start processing the first input image
2. The output of `xf::cornerHarris` is pipelined by SDSoC on hardware to `xf::cornersImgToList`. This function takes in an image with corners marked as 255 and 0 elsewhere, and converts them to a list of corners.
3. Simultaneously, `xf::pyrDown` creates the two image pyramids and Dense Optical Flow is computed using the two image pyramids as described in the Iterative Pyramidal Dense Optical Flow example.
4. `xf::densePyrOpticalFlow` is called with the two image pyramids as inputs.
5. `xf::cornerUpdate` function is called to track the corner locations in the second image. If `harris_flag` is enabled, the `cornerUpdate` tracks corners from the output of the list, else it tracks the previously tracked corners.

```

if(*harris_flag == true)
{
    #pragma SDS async(1)

    xf::cornerHarris<FILTER_WIDTH, BLOCK_WIDTH, NMS_RADIUS, XF_8UC1, HEIGHT, WIDTH, XF_NPPC1>(inHarris, outHarris, Thresh, k);
    
```

```

#pragma SDS async(2)

xf::cornersImgToList<MAXCORNERS, XF_8UC1, HEIGHT, WIDTH, XF_NPPC1>(outHarris,
list, &nCorners);
}
//Code to compute Iterative Pyramidal Dense Optical Flow
if(*harris_flag == true)
{
#pragma SDS wait(1)
#pragma SDS wait(2)
*num_corners = nCorners;
}
if(flag_flowin)
{

xf::cornerUpdate<MAXCORNERS, XF_32UC1, HEIGHT, WIDTH, XF_NPPC1>(listfixed,
list, *num_corners, flow_iter, (ap_uint<1>)(*harris_flag));
}

else

{

xf::cornerUpdate<MAXCORNERS, XF_32UC1, HEIGHT, WIDTH, XF_NPPC1>(listfixed,
list, *num_corners, flow, (ap_uint<1>)(*harris_flag));
}
if(*harris_flag == true)
{
*num_corners = false;
}
}
    
```

The `xf_corner_tracker_accel()` function takes a flag called `harris_flag` which is set during the first frame or when the corners need to be redetected. The `xf::cornerUpdate` function outputs the updated corners to the same memory location as the output corners list of `xf::cornerImgToList`. This means that when `harris_flag` is unset, the corners input to the `xf::cornerUpdate` are the corners tracked in the previous cycle, that is, the corners in the first frame of the current input frames.

After the Dense Optical Flow is computed, if `harris_flag` is set, the number of corners that `xf::cornerharris` has detected and `xf::cornersImgToList` has updated is copied to `num_corners` variable which is one of the outputs of the `xf_corner_tracker_accel()` function. The other being the tracked corners list, `listfixed`. If `harris_flag` is set, `xf::cornerUpdate` tracks the corners in 'list' memory location, otherwise it tracks the corners in 'listfixed' memory location.

## Color Detection

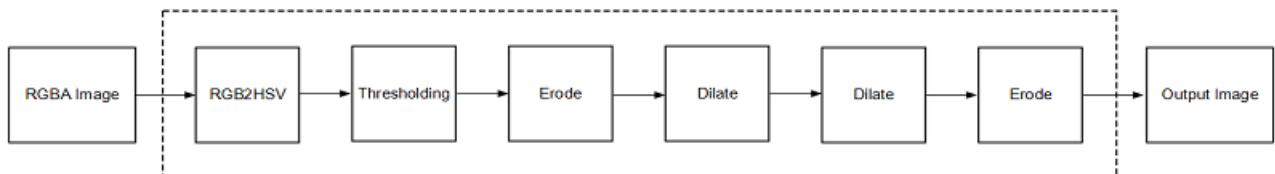
The Color Detection algorithm is basically used for color object tracking and object detection, based on the color of the object. The color based methods are very useful for object detection and segmentation, when the object and the background have a significant difference in color.

The Color Detection example uses four hardware functions from the xfOpenCV library. They are:

- xf::RGB2HSV
- xf::colorthresholding
- xf:: erode
- xf:: dilate

In the Color Detection example, the color space of the original BGR image is converted into an HSV color space. Because HSV color space is the most suitable color space for color based image segmentation. Later, based on the H (hue), S (saturation) and V (value) values, apply the thresholding operation on the HSV image and return either 255 or 0. After thresholding the image, apply erode (morphological opening) and dilate (morphological opening) functions to reduce unnecessary white patches (noise) in the image. Here, the example uses two hardware instances of erode and dilate functions. The erode followed by dilate and once again applying dilate followed by erode.

Figure 11: Color Detection



The following example demonstrates the Color Detection algorithm.

```

void colordetect_accel(xf::Mat<XF_8UC4, HEIGHT, WIDTH, XF_NPPC1> &_src,
    xf::Mat<XF_8UC4, HEIGHT, WIDTH, XF_NPPC1> &_rgb2hsv,
    xf::Mat<XF_8UC1, HEIGHT, WIDTH, XF_NPPC1> &_thresholdedimg,
    xf::Mat<XF_8UC1, HEIGHT, WIDTH, XF_NPPC1> &_erodeimage1,
    xf::Mat<XF_8UC1, HEIGHT, WIDTH, XF_NPPC1> &_dilateimage1,
    xf::Mat<XF_8UC1, HEIGHT, WIDTH, XF_NPPC1> &_dilateimage2,
    xf::Mat<XF_8UC1, HEIGHT, WIDTH, XF_NPPC1> &_dst,
    unsigned char *low_thresh, unsigned char *high_thresh){

    xf::RGB2HSV< XF_8UC4,HEIGHT, WIDTH, XF_NPPC1>(_src, _rgb2hsv);
    xf::colorthresholding<XF_8UC4,XF_8UC1,MAXCOLORS,HEIGHT,WIDTH,
    XF_NPPC1>(_rgb2hsv,_ thresholdedimage, low_thresh, high_thresh);
    xf::erode<XF_BORDER_CONSTANT,XF_8UC1,HEIGHT, WIDTH,
    XF_NPPC1>(_thresholdedimg, _ erodeimage1);
    xf::dilate<XF_BORDER_CONSTANT,XF_8UC1,HEIGHT, WIDTH, XF_NPPC1>(_
    erodeimage1, _ dilateimage1);
  
```

```

        xf::dilate<XF_BORDER_CONSTANT, XF_8UC1, HEIGHT, WIDTH, XF_NPPC1>(_
        dilateimage1, _ dilateimage2);
        xf::erode<XF_BORDER_CONSTANT, XF_8UC1, HEIGHT, WIDTH, XF_NPPC1>(_
        dilateimage2, _dst);
    }
    
```

In the given example, the source image is passed to the `xf::RGB2HSV` function, the output of that function is passed to the `xf::colorthresholding` module, the thresholded image is passed to the `xf::erode` function and, the `xf::dilate` functions and the final output image are returned.

---

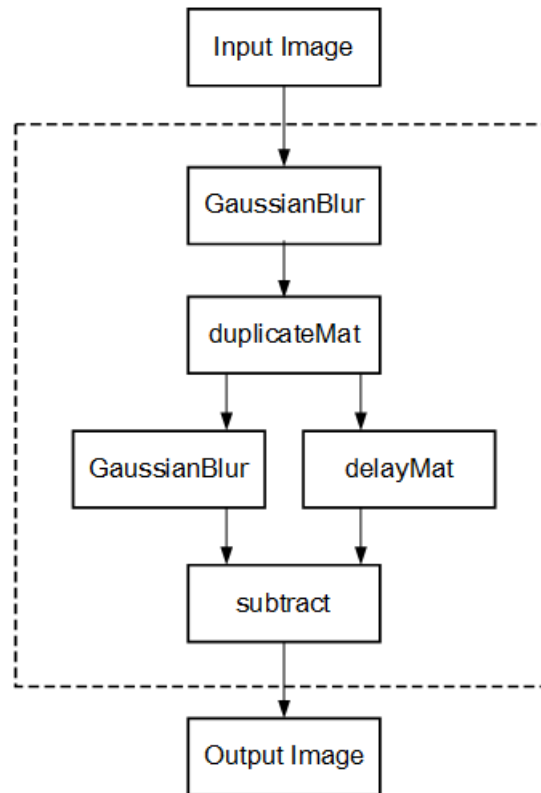
## Difference of Gaussian Filter

The Difference of Gaussian Filter example uses four hardware functions from the xfOpenCV library. They are:

- `xf::GaussianBlur`
- `xf::duplicateMat`
- `xf::delayMat`
- `xf::subtract`

The Difference of Gaussian Filter function can be implemented by applying Gaussian Filter on the original source image, and that Gaussian blurred image is duplicated as two images. The Gaussian blur function is applied to one of the duplicated images, whereas the other one is stored as it is. Later, perform the Subtraction function on, two times Gaussian applied image and one of the duplicated image. Here, the duplicated image has to wait until the Gaussian applied for other one generates at least for one pixel output. Therefore, here `xf::delayMat` function is used to add delay.

Figure 12: Difference of Gaussian Filter



The following example demonstrates the Difference of Gaussian Filter example.

```

void gaussian_diff_accel(xf::Mat<XF_8UC1,HEIGHT,WIDTH,NPC1> &imgInput,
    xf::Mat<XF_8UC1,HEIGHT,WIDTH, XF_NPPC1> &imgin1,
    xf::Mat<XF_8UC1,HEIGHT,WIDTH, XF_NPPC1> &imgin2,
    xf::Mat<XF_8UC1,HEIGHT,WIDTH, XF_NPPC1> &imgin3,
    xf::Mat<XF_8UC1,HEIGHT,WIDTH, XF_NPPC1> &imgin4,
    xf::Mat<XF_8UC1,HEIGHT,WIDTH, XF_NPPC1> &imgin5,
    xf::Mat<XF_8UC1,HEIGHT,WIDTH, XF_NPPC1>&imgOutput,
    float sigma)
{
    xf::GaussianBlur<FILTER_WIDTH, XF_BORDER_CONSTANT, XF_8UC1, HEIGHT,
    WIDTH, XF_NPPC1>
    (imgInput, imgin1, sigma);
    xf::duplicateMat<XF_8UC1, HEIGHT, WIDTH,
    XF_NPPC1>(imgin1, imgin2, imgin3);
    xf::delayMat<MAXDELAY, XF_8UC1, HEIGHT, WIDTH,
    XF_NPPC1>(imgin3, imgin5);
    xf::GaussianBlur<FILTER_WIDTH, XF_BORDER_CONSTANT, XF_8UC1, HEIGHT,
    WIDTH, XF_NPPC1>
    (imgin2, imgin4, sigma);
    xf::subtract<XF_CONVERT_POLICY_SATURATE, XF_8UC1, HEIGHT, WIDTH,
    XF_NPPC1>(imgin5, imgin4, imgOutput);
}
    
```



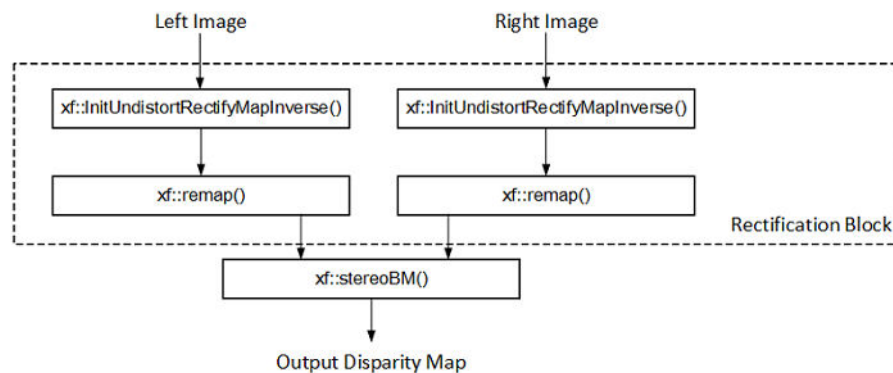
In the given example, the Gaussian Blur function is applied for source image `imginput`, and resultant image `imgin1` is passed to `xf::duplicateMat`. The `imgin2` and `imgin3` are the duplicate images of Gaussian applied image. Again gaussian blur is applied to `imgin2` and the result is stored in `imgin4`. Now, perform the subtraction between `imgin4` and `imgin3`, but here `imgin3` has to wait up to at least one pixel of `imgin4` generation. So, delay has applied for `imgin3` and stored in `imgin5`. Finally the subtraction performed on `imgin4` and `imgin5`.

## Stereo Vision Pipeline

Disparity map generation is one of the first steps in creating a three dimensional map of the environment. The xfOpenCV library has components to build an image processing pipeline to compute a disparity map given the camera parameters and inputs from a stereo camera setup.

The two main components involved in the pipeline are stereo rectification and disparity estimation using local block matching method. While disparity estimation using local block matching is a discrete component in xfOpenCV, rectification block can be constructed using `xf::InitUndistortRectifyMapInverse()` and `xf::Remap()`. The dataflow pipeline is shown below. The camera parameters are an additional input to the pipeline.

Figure 13: Stereo Vision Pipeline



The following code is for the pipeline.

```

void stereopipeline_accel(xf::Mat<XF_8UC1, XF_HEIGHT, XF_WIDTH, XF_NPPC1>
&leftMat, xf::Mat<XF_8UC1, XF_HEIGHT, XF_WIDTH, XF_NPPC1> &rightMat,
xf::Mat<XF_16UC1, XF_HEIGHT, XF_WIDTH, XF_NPPC1> &dispMat,
xf::Mat<XF_32FC1, XF_HEIGHT, XF_WIDTH, XF_NPPC1> &mapxLMat,
xf::Mat<XF_32FC1, XF_HEIGHT, XF_WIDTH, XF_NPPC1> &mapyLMat,
xf::Mat<XF_32FC1, XF_HEIGHT, XF_WIDTH, XF_NPPC1> &mapxRMat,
xf::Mat<XF_32FC1, XF_HEIGHT, XF_WIDTH, XF_NPPC1> &mapyRMat,
xf::Mat<XF_8UC1, XF_HEIGHT, XF_WIDTH, XF_NPPC1> &leftRemappedMat,
xf::Mat<XF_8UC1, XF_HEIGHT, XF_WIDTH, XF_NPPC1> &rightRemappedMat,
xf::xFSBMState<SAD_WINDOW_SIZE, NO_OF_DISPARTITIES, PARALLEL_UNITS>
&bm_state, ap_fixed<32,12> *cameraMA_l_fix, ap_fixed<32,12>
*cameraMA_r_fix, ap_fixed<32,12> *distC_l_fix, ap_fixed<32,12>
    
```

```

*distC_r_fix,
  ap_fixed<32,12> *irA_l_fix, ap_fixed<32,12> *irA_r_fix, int _cm_size,
  int _dc_size)
{
    xf::InitUndistortRectifyMapInverse<XF_HEIGHT, XF_WIDTH,
    XF_CAMERA_MATRIX_SIZE, XF_DIST_COEFF_SIZE,
    XF_32FC1, XF_NPPC1>(cameraMA_l_fix, distC_l_fix, irA_l_fix,
    mapxLMat, mapyLMat, _cm_size, _dc_size);
    xf::remap<XF_REMAP_BUFSIZE, XF_8UC1, XF_32FC1, XF_8UC1, XF_HEIGHT,
    XF_WIDTH, XF_NPPC1>(leftMat, leftRemappedMat, mapxLMat, mapyLMat,
    XF_INTERPOLATION_BILINEAR);

    xf::InitUndistortRectifyMapInverse<XF_HEIGHT, XF_WIDTH,
    XF_CAMERA_MATRIX_SIZE, XF_DIST_COEFF_SIZE, XF_32FC1,
    XF_NPPC1>(cameraMA_r_fix, distC_r_fix, irA_r_fix, mapxRMat, mapyRMat,
    _cm_size, _dc_size);
    xf::remap<XF_REMAP_BUFSIZE, XF_8UC1, XF_32FC1, XF_8UC1, XF_HEIGHT,
    XF_WIDTH, XF_NPPC1>(rightMat, rightRemappedMat, mapxRMat, mapyRMat,
    XF_INTERPOLATION_BILINEAR);
    xf::StereoBM<XF_HEIGHT, XF_WIDTH, XF_8UC1, XF_16UC1, XF_NPPC1,
    SAD_WINDOW_SIZE, NO_OF_DISPARITIES, PARALLEL_UNITS>(leftRemappedMat,
    rightRemappedMat, dispMat, bm_state);
}
    
```

# Additional Resources and Legal Notices

## Xilinx Resources

For support resources such as Answers, Documentation, Downloads, and Forums, see [Xilinx Support](#).

## Solution Centers

See the [Xilinx Solution Centers](#) for support on devices, software tools, and intellectual property at all stages of the design cycle. Topics include design assistance, advisories, and troubleshooting tips

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## Xilinx Resources

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- From the Vivado® IDE, select **Help** → **Documentation and Tutorials**.
- On Windows, select **Start** → **All Programs** → **Xilinx Design Tools** → **DocNav**.
- At the Linux command prompt, enter `docnav`.

Xilinx Design Hubs provide links to documentation organized by design tasks and other topics, which you can use to learn key concepts and address frequently asked questions. To access the Design Hubs:

- In the Xilinx Documentation Navigator, click the **Design Hubs View** tab.
- On the Xilinx website, see the [Design Hubs](#) page.

**Note:** For more information on Documentation Navigator, see the [Documentation Navigator](#) page on the Xilinx website.

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## References

These documents provide supplemental material useful with this guide:

1. *SDSoC Environments Release Notes, Installation, and Licensing Guide* ([UG1294](#))
2. *SDSoC Environment User Guide* ([UG1027](#))
3. *SDSoC Environment Getting Started Tutorial* ([UG1028](#))
4. *SDSoC Environment Platform Creation Tutorial* ([UG1236](#))
5. *SDSoC Environment Platform Development Guide* ([UG1146](#))
6. *SDSoC Environment Profiling and Optimization Guide* ([UG1235](#))
7. *SDx Command and Utility Reference Guide* ([UG1279](#))
8. *SDSoC Environment Programmers Guide* ([UG1278](#))
9. *SDSoC Environment Debugging Guide* ([UG1282](#))
10. *SDx Pragma Reference Guide* ([UG1253](#))
11. *UltraFast Embedded Design Methodology Guide* ([UG1046](#))
12. *Zynq-7000 SoC Software Developers Guide* ([UG821](#))
13. *Zynq UltraScale+ MPSoC: Software Developers Guide* ([UG1137](#))
14. *ZC702 Evaluation Board for the Zynq-7000 XC7Z020 SoC User Guide* ([UG850](#))
15. *ZCU102 Evaluation Board User Guide* ([UG1182](#))
16. *Vivado Design Suite User Guide: High-Level Synthesis* ([UG902](#))
17. *Vivado Design Suite: Creating and Packaging Custom IP* ([UG1118](#))
18. [SDSoC Development Environment web page](#)
19. [Vivado® Design Suite Documentation](#)

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