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SECTION I: SUMMARY

IP Facts
Overview
Product Specification
Designing with the Core
C Model Reference
Introduction

The Xilinx LogiCORE™ IP Defective Pixel Correction core performs real-time detection and correction of defective pixels in a camera image sensor array.

Features

- Real-time detection and correction of defective pixels from a camera image sensor array
- Spatial and temporal analysis without using an external frame buffer
- Programmable thresholds for detection/replacement:
  - Spatial variance
  - Temporal variance
  - Pixel age
- Optional AXI4-Lite control interface enables dynamic control of core
- Supports spatial resolutions from 32x32 up to 7680x7680
  - Supports 1080P60 in all supported device families (1)
  - Supports 4kx2k @24Hz in supported high performance devices
- Supports 8, 10 or 12 bits per pixel
- Built in, optional bypass and test pattern generator modes simplifies system debugging
- Built-in optional throughput monitors simplifies system throughput analysis

1. Performance on low power devices may be lower.

---

LogiCORE IP Facts Table

<table>
<thead>
<tr>
<th>Core Specifics</th>
</tr>
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<tbody>
<tr>
<td>Supported Device Family (1)</td>
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<td>Supported User Interfaces</td>
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<table>
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<tr>
<td>Documentation</td>
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<td>Design Files</td>
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<td>Example Design</td>
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<tr>
<td>Test Bench</td>
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<td>Constraints File</td>
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<td>Simulation Models</td>
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<td>Supported Software Drivers</td>
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<table>
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<th>Tested Design Flows (6)</th>
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<tr>
<td>Design Entry Tools</td>
</tr>
<tr>
<td>Simulation (5)</td>
</tr>
<tr>
<td>Synthesis Tools</td>
</tr>
</tbody>
</table>

Support

Provided by Xilinx, Inc.

1. For a complete listing of supported devices, see the release notes for this core.
2. Supported in ISE Design Suite implementations only.
3. Video protocol as defined in the Video IP: AXI Feature Adoption section of UG761 AXI Reference Guide.
5. For the supported versions of the tools, see the ISE Design Suite 14: Release Notes Guide.
6. For the supported versions of the tools, see the Xilinx Design Tools: Release Notes Guide.
7. Supports only 7 series devices.
Overview

An image sensor may have a certain number of defective pixels that may be the result of manufacturing faults, failures during normal operation, or variations in pixel voltage levels based on temperature or exposure. A wide class of pixel defects may be characterized as: dead (always low), hot (always high), or stuck (to a certain value). These anomalies can further be characterized as static (always present) or dynamic (as a function of exposure or temperature).

The Xilinx Defective Pixel Correction solution distinguishes between large stationary areas, which are likely to be non-changing parts of the image, and singular outliers, which are likely to be defective pixels. The Xilinx Defective Pixel Correction solution compares a pixel in the raw, Bayer sub-sampled domain to its neighboring, same color pixel values and keeps track of pixels that are sufficiently different from their neighbors. If the values of tracked outlier pixels stay in a predefined range for a predefined number of frames, then the tracked pixels are considered defective, and are replaced with values interpolated from neighboring pixels.

Spatial filtering first identifies potential defective pixels, and at the same time eliminates pixels that blend into their local neighborhoods, and therefore do not need to be substituted even if they are defective. Spatial filtering reduces the number of pixels, along with the amount of information, that needs to be stored for temporal filtering, therefore facilitating spatio-temporal filtering in embedded systems with limited or no access to external memory.

Feature Summary

The Defective Pixel Correction core performs real-time detection and correction of defective pixels in a camera image sensor array. The core is capable of removing defective pixels in real time, without the need to buffer, on a maximum resolution of 7620 columns by 7620 rows 8, 10, or 12 bits per pixel and supports the bandwidth necessary for High-definition (1080p60) resolutions.

You can configure and instantiate the core from Vivado tools, CORE Generator, or EDK tools. Core functionality may be controlled dynamically with an optional AXI4-Lite interface.
Applications

Detection and correction of noisy or defective pixels for applications utilizing an image sensor with a Bayer pattern Color Filter Array.

Licensing and Ordering Information

This Xilinx LogiCORE IP module is provided under the terms of the Xilinx Core License Agreement. The module is shipped as part of the Vivado Design Suite/ISE Design Suite. For full access to all core functionalities in simulation and in hardware, you must purchase a license for the core. Contact your local Xilinx sales representative for information about pricing and availability.

For more information, visit the Defective Pixel Correction product web page.

Information about other Xilinx LogiCORE IP modules is available at the Xilinx Intellectual Property page. For information on pricing and availability of other Xilinx LogiCORE IP modules and tools, contact your local Xilinx sales representative.
Product Specification

Standards Compliance

The Defective Pixel Correction core is compliant with the AXI4-Stream Video Protocol and AXI4-Lite interconnect standards. Refer to the Video IP: AXI Feature Adoption section of the UG761 AXI Reference Guide for additional information.

Performance

The following sections detail the performance characteristics of the Defective Pixel Correction core.

Maximum Frequencies

This section contains typical clock frequencies for the target devices. The maximum achievable clock frequency can vary. The maximum achievable clock frequency and all resource counts can be affected by other tool options, additional logic in the FPGA device, using a different version of Xilinx tools and other factors. Refer to in Table 2-1 through Table 2-5 for device-specific information.

Latency

The processing latency of the core is shown in the following equation:

\[
\text{Latency} = 2 \text{ scan lines} + 18 \text{ pixels}
\]

Throughput

The Defective Pixel Correction core produces one output pixel per input sample.

The core supports bidirectional data throttling between its AXI4-Stream Slave and Master interfaces. If the slave side data source is not providing valid data samples (s_axis_video_tvalid is not asserted), the core cannot produce valid output samples.
after its internal buffers are depleted. Similarly, if the master side interface is not ready to accept valid data samples (m_axis_video_tready is not asserted) the core cannot accept valid input samples once its buffers become full.

If the master interface is able to provide valid samples (s_axis_video_tvalid is high) and the slave interface is ready to accept valid samples (m_axis_video_tready is high), typically the core can process one sample and produce one pixel per ACLK cycle.

However, at the end of each scan line the core flushes internal pipelines for 2 clock cycles, during which the s_axis_video_tready is de-asserted signaling that the core is not ready to process samples. Also at the end of each frame the core flushes internal line buffers for 4 scan lines, during which the s_axis_video_tready is de-asserted signaling that the core is not ready to process samples.

When the core is processing timed streaming video (which is typical for image sensors), the flushing periods coincide with the blanking periods therefore do not reduce the throughput of the system.

Note: There are sections in a video stream that do not contain any video data so the burst rate will always contain video data and the average rate will include the video data and the non-video (blanking) data.

When the core is processing data from a video source which can always provide valid data, e.g. a frame buffer, the throughput of the core can be defined as follows:

\[
R_{\text{MAX}} = f_{\text{ACLK}} \times \frac{\text{ROWS}}{\text{ROWS} + 2} \times \frac{\text{COLS}}{\text{COLS} + 18}
\]

Equation 2-1

In numeric terms, 1080P/60 represents an average data rate of 124.4 MPixels/second (1080 rows x 1920 columns x 60 frames / second), and a burst data rate of 148.5 MPixels/sec.

To ensure that the core can process 124.4 MPixels/second, it needs to operate minimally at:

\[
f_{\text{ACLK}} = R_{\text{MAX}} \times \frac{\text{ROWS} + 2}{\text{ROWS}} \times \frac{\text{COLS} + 18}{\text{COLS}} = \frac{124.4 \times 1082}{1080} \times \frac{1938}{1920} = 125.8
\]

Equation 2-2

Resource Utilization

For an accurate measure of the usage of primitives, slices, and CLBs for a particular instance, check the Display Core Viewer after Generation check box in the CORE Generator interface.

The information presented in Table 2-1 through Table 2-8 is a guide to the resource utilization and maximum clock frequency of the Defective Pixel Correction core for all input/output width combinations for Virtex-7, Kintex-7, Artix-7, Zynq-7000, Virtex-6, and Spartan-6 FPGA families. The Xtreme DSP Slice count is always 1, regardless of parameterization, and this core does not use any dedicated I/O or CLK resources. Table 2-1 through Table 2-5 were generated using ISE® v14.2 tools with default tool options for
characterization data. The design was tested with the AXI4-Lite interface, INTC_IF and the Debug Features disabled. By default, the maximum number of pixels per scan line was set to 1920, active pixels per scan line was set to 1920.

Table 2-1:  Spartan-6

<table>
<thead>
<tr>
<th>Data Width</th>
<th>LUT-FF Pairs</th>
<th>LUTs</th>
<th>FFs</th>
<th>RAM 16 / 8</th>
<th>DSP48A1</th>
<th>Fmax (MHz)</th>
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<tbody>
<tr>
<td>8</td>
<td>1682</td>
<td>1441</td>
<td>1372</td>
<td>4 / 0</td>
<td>1</td>
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<tr>
<td>10</td>
<td>1896</td>
<td>1641</td>
<td>1562</td>
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<td>1</td>
<td>169</td>
</tr>
<tr>
<td>12</td>
<td>2074</td>
<td>1821</td>
<td>1754</td>
<td>4 / 1</td>
<td>1</td>
<td>175</td>
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</table>

1. Speedfile: XC6SLX25-2 FGG484 Production 1.21 2012-06-18

Table 2-2:  Virtex-7

<table>
<thead>
<tr>
<th>Data Width</th>
<th>LUT-FF Pairs</th>
<th>LUTs</th>
<th>FFs</th>
<th>RAM 36 / 18</th>
<th>DSP48E1</th>
<th>Fmax (MHz)</th>
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<tbody>
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<td>8</td>
<td>1629</td>
<td>1435</td>
<td>1319</td>
<td>2 / 1</td>
<td>1</td>
<td>262</td>
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<tr>
<td>10</td>
<td>1888</td>
<td>1619</td>
<td>1509</td>
<td>2 / 2</td>
<td>1</td>
<td>253</td>
</tr>
<tr>
<td>12</td>
<td>2042</td>
<td>1806</td>
<td>1699</td>
<td>2 / 2</td>
<td>1</td>
<td>243</td>
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</table>

1. Speedfile: XC7V585T-1 FFG1157 Advanced 1.05g 2012-06-18

Table 2-3:  Virtex-6

<table>
<thead>
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<th>Data Width</th>
<th>LUT-FF Pairs</th>
<th>LUTs</th>
<th>FFs</th>
<th>RAM 36 / 18</th>
<th>DSP48E1</th>
<th>Fmax (MHz)</th>
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<tbody>
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<td>1703</td>
<td>1443</td>
<td>1319</td>
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<td>1</td>
<td>285</td>
</tr>
<tr>
<td>10</td>
<td>1919</td>
<td>1580</td>
<td>1509</td>
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<td>1</td>
<td>262</td>
</tr>
<tr>
<td>12</td>
<td>2152</td>
<td>1782</td>
<td>1699</td>
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<td>1</td>
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1. Speedfile: XC6VLX75T-1 FF484 Production 1.17 2012-06-18

Table 2-4:  Kintex-7 (and Zynq 7030, 7045 Devices with Kintex Based Fabric)

<table>
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<th>LUTs</th>
<th>FFs</th>
<th>RAM 36 / 18</th>
<th>DSP48E1</th>
<th>Fmax (MHz)</th>
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<td>10</td>
<td>1955</td>
<td>1591</td>
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<td>1</td>
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<tr>
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<td>2158</td>
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1. Speedfile: XC7K70T-1 FBG484 Advanced 1.05b 2012-06-18

Table 2-5:  Artix-7 (and Zynq 7010, 7020 Devices with Artix Based Fabric)

<table>
<thead>
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<th>Data Width</th>
<th>LUT-FF Pairs</th>
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<th>FFs</th>
<th>RAM 36 / 18</th>
<th>DSP48E1</th>
<th>Fmax (MHz)</th>
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<td>1</td>
<td>206</td>
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<tr>
<td>10</td>
<td>1929</td>
<td>1614</td>
<td>1509</td>
<td>2 / 2</td>
<td>1</td>
<td>182</td>
</tr>
<tr>
<td>12</td>
<td>2185</td>
<td>1816</td>
<td>1699</td>
<td>2 / 2</td>
<td>1</td>
<td>190</td>
</tr>
</tbody>
</table>

1. Speedfile: XC7A100T-1 FGG484 Advanced 1.04d 2012-06-18
Table 2-6 through Table 2-8 were generated using Vivado Design Suite 2012.2 with default tool options for characterization data.

**Table 2-6: Virtex-7**

<table>
<thead>
<tr>
<th>Data Width</th>
<th>LUT-FF Pairs</th>
<th>LUTs</th>
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<th>Fmax (MHz)</th>
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<tbody>
<tr>
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<td>1592</td>
<td>2 / 1</td>
<td>2</td>
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<tr>
<td>10</td>
<td>2310</td>
<td>1912</td>
<td>1827</td>
<td>2 / 2</td>
<td>2</td>
<td>274</td>
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<td>2758</td>
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<td>2 / 2</td>
<td>2</td>
<td>284</td>
</tr>
</tbody>
</table>

1. Speedfile: XC7V585T-1 FFG1157 Advanced 1.05g 2012-06-18

**Table 2-7: Kintex-7**

<table>
<thead>
<tr>
<th>Data Width</th>
<th>LUT-FF Pairs</th>
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<td>2433</td>
<td>1913</td>
<td>1827</td>
<td>2 / 2</td>
<td>2</td>
<td>272</td>
</tr>
<tr>
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<td>2697</td>
<td>2135</td>
<td>2065</td>
<td>2 / 2</td>
<td>2</td>
<td>272</td>
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1. Speedfile: XC7K70T-1 FBG484 Advanced 1.05b 2012-06-18

**Table 2-8: Artix-7**

<table>
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<tr>
<th>Data Width</th>
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<th>RAM 36 / 18</th>
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<td>2513</td>
<td>1915</td>
<td>1827</td>
<td>2 / 2</td>
<td>2</td>
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<td>2065</td>
<td>2 / 2</td>
<td>2</td>
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</tr>
</tbody>
</table>

1. Speedfile: XC7A100T-1 FGG484 Advanced 1.04d 2012-06-18

---

Core Interfaces and Register Space

Port Descriptions

The Defective Pixel Correction (DPC) core uses industry standard control and data interfaces to connect to other system components. The following sections describe the various interfaces available with the core. Figure 2-1 illustrates an I/O diagram of the DPC core. Some signals are optional and not present for all configurations of the core. The AXI4-Lite interface and the IRQ pin are present only when the core is configured via the GUI with an AXI4-Lite control interface. The INTC_IF interface is present only when the core is configured via the GUI with the INTC interface enabled.
Common Interface Signals

Table 2-9 summarizes the signals which are either shared by, or not part of the dedicated AXI4-Stream data or AXI4-Lite control interfaces.

<table>
<thead>
<tr>
<th>Signal Name</th>
<th>Direction</th>
<th>Width</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ACLK</td>
<td>In</td>
<td>1</td>
<td>Video Core Clock</td>
</tr>
<tr>
<td>ACLKEN</td>
<td>In</td>
<td>1</td>
<td>Video Core Active High Clock Enable</td>
</tr>
<tr>
<td>ARESETn</td>
<td>In</td>
<td>1</td>
<td>Video Core Active Low Synchronous Reset</td>
</tr>
<tr>
<td>INTC_IF</td>
<td>Out</td>
<td>6</td>
<td>Optional External Interrupt Controller Interface. Available only when INTC_IF is selected on GUI.</td>
</tr>
<tr>
<td>IRQ</td>
<td>Out</td>
<td>1</td>
<td>Optional Interrupt Request Pin. Available only when AXI4-Liter interface is selected on GUI.</td>
</tr>
</tbody>
</table>

The ACLK, ACLKEN and ARESETn signals are shared between the core and the AXI4-Stream data interfaces. The AXI4-Lite control interface has its own set of clock, clock enable and
reset pins: S_AXI_ACLK, S_AXI_ACLKEN and S_AXI_ARESETn. Refer to The Interrupt Subsystem for a description of the INTC_IF and IRQ pins.

ACLK

The AXI4-Stream interface must be synchronous to the core clock signal ACLK. All AXI4-Stream interface input signals are sampled on the rising edge of ACLK. All AXI4-Stream output signal changes occur after the rising edge of ACLK. The AXI4-Lite interface is unaffected by the ACLK signal.

ACLKEN

The ACLKEN pin is an active-high, synchronous clock-enable input pertaining to AXI4-Stream interfaces. Setting ACLKEN low (de-asserted) halts the operation of the core despite rising edges on the ACLK pin. Internal states are maintained, and output signal levels are held until ACLKEN is asserted again. When ACLKEN is de-asserted, core inputs are not sampled, except ARESETn, which supersedes ACLKEN. The AXI4-Lite interface is unaffected by the ACLKEN signal.

ARESETn

The ARESETn pin is an active-low, synchronous reset input pertaining to only AXI4-Stream interfaces. ARESETn supersedes ACLKEN, and when set to 0, the core resets at the next rising edge of ACLK even if ACLKEN is de-asserted. The ARESETn signal must be synchronous to the ACLK and must be held low for a minimum of 32 clock cycles of the slowest clock. The AXI4-Lite interface is unaffected by the ARESETn signal.

Data Interface

The DPC core receives and transmits data using AXI4-Stream interfaces that implement a video protocol as defined in the Video IP: AXI Feature Adoption section of the UG761 AXI Reference Guide.

AXI4-Stream Signal Names and Descriptions

Table 2-10 describes the AXI4-Stream signal names and descriptions.

<table>
<thead>
<tr>
<th>Signal Name</th>
<th>Direction</th>
<th>Width</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s_axis_video_tdata</td>
<td>In</td>
<td>8,16</td>
<td>Input Video Data</td>
</tr>
<tr>
<td>s_axis_video_tvalid</td>
<td>In</td>
<td>1</td>
<td>Input Video Valid Signal</td>
</tr>
<tr>
<td>s_axis_video_tready</td>
<td>Out</td>
<td>1</td>
<td>Input Ready</td>
</tr>
<tr>
<td>s_axis_video_tuser</td>
<td>In</td>
<td>1</td>
<td>Input Video Start Of Frame</td>
</tr>
</tbody>
</table>
Video Data

The AXI4-Stream interface specification restricts TDATA widths to integer multiples of 8 bits. Therefore, 10 and 12 bit sensor data must be padded with zeros on the MSB to form a 16 bit wide vector before connecting to $s_{\text{axis}}_{\text{video}}_{\text{tdata}}$. Padding does not affect the size of the core.

Similarly, RGB data on the DPC output $m_{\text{axis}}_{\text{video}}_{\text{tdata}}$ is packed and padded to multiples of 8 bits as necessary. Zero padding the most significant bits is only necessary for 10 and 12 bit wide data.

READY/VALID Handshake

A valid transfer occurs whenever READY, VALID, ACLKEN, and ARESETn are high at the rising edge of ACLK, as seen in Figure 2-11. During valid transfers, DATA only carries active video data. Blank periods and ancillary data packets are not transferred via the AXI4-Stream video protocol.

Guidelines on Driving $s_{\text{axis}}_{\text{video}}_{\text{tvalid}}$

Once $s_{\text{axis}}_{\text{video}}_{\text{tvalid}}$ is asserted, no interface signals (except the DPC core driving $s_{\text{axis}}_{\text{video}}_{\text{tready}}$) may change value until the transaction completes ($s_{\text{axis}}_{\text{video}}_{\text{tready}}, s_{\text{axis}}_{\text{video}}_{\text{tvalid}}$ ACLKEN high on the rising edge of ACLK). Once asserted, $s_{\text{axis}}_{\text{video}}_{\text{tvalid}}$ may only be de-asserted after a transaction has completed. Transactions may not be retracted or aborted. In any cycle following a transaction, $s_{\text{axis}}_{\text{video}}_{\text{tvalid}}$ can either be de-asserted or remain asserted to initiate a new transfer.

<table>
<thead>
<tr>
<th>Signal Name</th>
<th>Direction</th>
<th>Width</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>$s_{\text{axis}}<em>{\text{video}}</em>{\text{tlast}}$</td>
<td>In</td>
<td>1</td>
<td>Input Video End Of Line</td>
</tr>
<tr>
<td>$m_{\text{axis}}<em>{\text{video}}</em>{\text{tdata}}$</td>
<td>Out</td>
<td>24,32,40</td>
<td>Output Video Data</td>
</tr>
<tr>
<td>$m_{\text{axis}}<em>{\text{video}}</em>{\text{tvalid}}$</td>
<td>Out</td>
<td>1</td>
<td>Output Valid</td>
</tr>
<tr>
<td>$m_{\text{axis}}<em>{\text{video}}</em>{\text{tready}}$</td>
<td>In</td>
<td>1</td>
<td>Output Ready</td>
</tr>
<tr>
<td>$m_{\text{axis}}<em>{\text{video}}</em>{\text{tuser}}$</td>
<td>Out</td>
<td>1</td>
<td>Output Video Start Of Frame</td>
</tr>
<tr>
<td>$m_{\text{axis}}<em>{\text{video}}</em>{\text{tlast}}$</td>
<td>Out</td>
<td>1</td>
<td>Output Video End Of Line</td>
</tr>
</tbody>
</table>

Table 2-10: AXI4-Stream Data Interface Signal Descriptions
Guidelines on Driving `m_axis_video_tready`

The `m_axis_video_tready` signal may be asserted before, during or after the cycle in which the DPC core asserted `m_axis_video_tvalid`. The assertion of `m_axis_video_tready` may be dependent on the value of `m_axis_video_tvalid`. A slave that can immediately accept data qualified by `m_axis_video_tvalid`, should pre-assert its `m_axis_video_tready` signal until data is received. Alternatively, `m_axis_video_tready` can be registered and driven the cycle following `VALID` assertion. It is recommended that the AXI4-Stream slave should drive `READY` independently, or pre-assert `READY` to minimize latency.

Start of Frame Signals - `m_axis_video_tuser`, `s_axis_video_tuser`

The Start-Of-Frame (SOF) signal, physically transmitted over the AXI4-Stream TUSER signal, marks the first pixel of a video frame. The SOF pulse is 1 valid transaction wide, and must coincide with the first pixel of the frame, as seen in Figure 2-2. SOF serves as a frame synchronization signal, which allows downstream cores to re-initialize, and detect the first pixel of a frame. The SOF signal may be asserted an arbitrary number of ACLK cycles before the first pixel value is presented on DATA, as long as a VALID is not asserted.

End of Line Signals - `m_axis_video_tlast`, `s_axis_video_tlast`

The End-Of-Line signal, physically transmitted over the AXI4-Stream TLAST signal, marks the last pixel of a line. The EOL pulse is 1 valid transaction wide, and must coincide with the last pixel of a scan-line, as seen in Figure 2-3.
Core Interfaces and Register Space

Control Interface

When configuring the core, the user has the option to add an AXI4-Lite register interface to dynamically control the behavior of the core. The AXI4-Lite slave interface facilitates integrating the core into a processor system, or along with other video or AXI4-Lite compliant IP, connected via AXI4-Lite interface to an AXI4-Lite master. In a static configuration with a fixed set of parameters (constant configuration), the core can be instantiated without the AXI4-Lite control interface, which reduces the core Slice footprint.

Constant Configuration

The constant configuration caters to users who will use the DPC core in a single setup that will not need to change. In constant configuration, the image resolution, Spatial Variance Threshold, Temporal Variance Threshold, and Pixel Resolution are hard coded into the core via the DPC core GUI. Since there is no AXI4-Lite interface, the core is not programmable, but can be reset, enabled, or disabled using the ARESETn and ACLKEN ports.

AXI4-Lite Interface

The AXI4-Lite interface allows a user to dynamically control parameters within the core. Core configuration can be accomplished using an AXI4-Stream master state machine, or an embedded ARM or soft system processor such as MicroBlaze.

The DPC core can be controlled via the AXI4-Lite interface using read and write transactions to the DPC register space.

Table 2-11: AXI4-Lite Interface Signals

<table>
<thead>
<tr>
<th>Signal Name</th>
<th>Direction</th>
<th>Width</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s_axi_aclk</td>
<td>In</td>
<td>1</td>
<td>AXI4-Lite clock</td>
</tr>
<tr>
<td>s_axi_aclken</td>
<td>In</td>
<td>1</td>
<td>AXI4-Lite clock enable</td>
</tr>
<tr>
<td>s_axi_aresetn</td>
<td>In</td>
<td>1</td>
<td>AXI4-Lite synchronous Active Low reset</td>
</tr>
<tr>
<td>s_axi_awvalid</td>
<td>In</td>
<td>1</td>
<td>AXI4-Lite Write Address Channel Write Address Valid.</td>
</tr>
</tbody>
</table>
Table 2-11: AXI4-Lite Interface Signals (Cont’d)

<table>
<thead>
<tr>
<th>Signal Name</th>
<th>Direction</th>
<th>Width</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s_axi_awread</td>
<td>Out</td>
<td>1</td>
<td>AXI4-Lite Write Address Channel Write Address Ready. Indicates DMA ready to accept the write address.</td>
</tr>
<tr>
<td>s_axi_awaddr</td>
<td>In</td>
<td>32</td>
<td>AXI4-Lite Write Address Bus</td>
</tr>
<tr>
<td>s_axi_wvalid</td>
<td>In</td>
<td>1</td>
<td>AXI4-Lite Write Data Channel Write Data Valid.</td>
</tr>
<tr>
<td>s_axi_wready</td>
<td>Out</td>
<td>1</td>
<td>AXI4-Lite Write Data Channel Write Data Ready. Indicates DMA is ready to accept the write data.</td>
</tr>
<tr>
<td>s_axi_wdata</td>
<td>In</td>
<td>32</td>
<td>AXI4-Lite Write Data Bus</td>
</tr>
<tr>
<td>s_axi_bresp</td>
<td>Out</td>
<td>2</td>
<td>AXI4-Lite Write Response Channel. Indicates results of the write transfer.</td>
</tr>
<tr>
<td>s_axi_bvalid</td>
<td>Out</td>
<td>1</td>
<td>AXI4-Lite Write Response Channel Response Valid. Indicates response is valid.</td>
</tr>
<tr>
<td>s_axi_bready</td>
<td>In</td>
<td>1</td>
<td>AXI4-Lite Write Response Channel Ready. Indicates target is ready to receive response.</td>
</tr>
<tr>
<td>s_axi_arvalid</td>
<td>In</td>
<td>1</td>
<td>AXI4-Lite Read Address Channel Read Address Valid</td>
</tr>
<tr>
<td>s_axi_arready</td>
<td>Out</td>
<td>1</td>
<td>Ready. Indicates DMA is ready to accept the read address.</td>
</tr>
<tr>
<td>s_axi_araddr</td>
<td>In</td>
<td>32</td>
<td>AXI4-Lite Read Address Bus</td>
</tr>
<tr>
<td>s_axi_rvalid</td>
<td>Out</td>
<td>1</td>
<td>AXI4-Lite Read Data Channel Read Data Valid</td>
</tr>
<tr>
<td>s_axi_rready</td>
<td>In</td>
<td>1</td>
<td>AXI4-Lite Read Data Channel Read Data Ready. Indicates target is ready to accept the read data.</td>
</tr>
<tr>
<td>s_axi_rdata</td>
<td>Out</td>
<td>32</td>
<td>AXI4-Lite Read Data Bus</td>
</tr>
<tr>
<td>s_axi_rresp</td>
<td>Out</td>
<td>2</td>
<td>AXI4-Lite Read Response Channel Response. Indicates results of the read transfer.</td>
</tr>
</tbody>
</table>

S_AXI_ACLK

The AXI4-Lite interface must be synchronous to the S_AXI_ACLK clock signal. The AXI4-Lite interface input signals are sampled on the rising edge of ACLK. The AXI4-Lite output signal changes occur after the rising edge of ACLK. The AXI4-Stream interfaces signals are not affected by the S_AXI_ACLK.

S_AXI_ACLKEN

The S_AXI_ACLKEN pin is an active-high, synchronous clock-enable input for the AXI4-Lite interface. Setting S_AXI_ACLKEN low (de-asserted) halts the operation of the AXI4-Lite interface despite rising edges on the S_AXI_ACLK pin. AXI4-Lite interface states are maintained, and AXI4-Lite interface output signal levels are held until S_AXI_ACLKEN is asserted again. When S_AXI_ACLKEN is de-asserted, AXI4-Lite interface inputs are not sampled, except S_AXI_ARESETn, which supersedes S_AXI_ACLKEN. The AXI4-Stream interfaces signals are not affected by the S_AXI_ACLKEN.
**S_AXI_ARESETn**

The S_AXI_ARESETn pin is an active-low, synchronous reset input for the AXI4-Lite interface. S_AXI_ARESETn supersedes S_AXI_ACLKEN, and when set to 0, the core resets at the next rising edge of S_AXI_ACLK even if S_AXI_ACLKEN is de-asserted. The S_AXI_ARESETn signal must be synchronous to the S_AXI_ACLK and must be held low for a minimum of 32 clock cycles of the slowest clock. The S_AXI_ARESETn input is resynchronized to the ACLK clock domain. The AXI4-Stream interfaces and core signals are also reset by S_AXI_ARESETn.

**Register Space**

The standardized Xilinx Video IP register space is partitioned to control-, timing-, and core specific registers. The DPC core uses only one timing related register, ACTIVE_SIZE (0x0020), which allows specifying the input frame dimensions. Also, the core has the following core-specific registers, THRESH_TEMPORAL_VAR (0x0100), THRESH_SPATIAL_VAR (0x0104), THRESH_PIXEL_AGE (0x0108) which allows specifying the characteristics of the defective pixels from the image sensor, as described in THRESH TEMPORAL_VAR (0x0100), THRESH_SPATIAL_VAR (0x0104), THRESH_PIXEL_AGE (0x0108) registers.

<table>
<thead>
<tr>
<th>Address (hex)</th>
<th>Register Name</th>
<th>Access Type</th>
<th>Double Buffered</th>
<th>Default Value</th>
<th>Register Description</th>
</tr>
</thead>
</table>
| BASEADDR      |               | R/W         | N               | Power-on-Reset: 0x0 | Bit 0: SW_ENABLE  
|               |               |             |                 |               | Bit 1: REG_UPDATE  
|               |               |             |                 |               | Bit 4: BYPASS¹  
|               |               |             |                 |               | Bit 5: TEST_PATTERN¹  
|               |               |             |                 |               | Bit 30: FRAME_SYNC_RESET (1: reset)  
|               |               |             |                 |               | Bit 31: SW_RESET (1: reset)  
| 0x0000        | CONTROL       | R/W         | No              | 0             | Bit 0: PROC_STARTED  
|               |               |             |                 |               | Bit 1: EOF  
|               |               |             |                 |               | Bit 16: SLAVE_ERROR  
| 0x0004        | STATUS        | R/W         | No              | 0             | Bit 0: SLAVE_EOL_EARLY  
|               |               |             |                 |               | Bit 1: SLAVE_EOL_LATE  
|               |               |             |                 |               | Bit 2: SLAVE_SOFTWARE  
|               |               |             |                 |               | Bit 3: SLAVE_SOFTWARE  
| 0x0008        | ERROR         | R/W         | No              | 0             | Bit 0: INTERRUPT_ENABLE  
|               |               |             |                 |               | Bit 1: INTERRUPT_ENABLE  
|               |               |             |                 |               | Bit 16: INTERRUPT_ENABLE  
| 0x000C        | IRQ_ENABLE    | R/W         | No              | 0             | 16-0: Interrupt enable bits corresponding to STATUS bits  
| 0x0010        | VERSION       | R           | N/A             | 0x0600a000    | 7-0: REVISION_NUMBER  
|               |               |             |                 |               | 11-8: PATCH_ID  
|               |               |             |                 |               | 15-12: VERSION_REVISION  
|               |               |             |                 |               | 23-16: VERSION_MINOR  
|               |               |             |                 |               | 31-24: VERSION_MAJOR  

¹The register type is defined by the software.
1. Only available when the debugging features option is enabled in the GUI at the time the core is instantiated.

**CONTROL (0x0000) Register**

Bit 0 of the **CONTROL** register, **SW_ENABLE**, facilitates enabling and disabling the core from software. Writing ‘0’ to this bit effectively disables the core halting further operations, which blocks the propagation of all video signals. The default value of **SW_enable** is 1 (enabled) for the Constant configuration. After Power up, or Global Reset, the **SW_ENABLE** defaults to 0 for the AXI4-Lite interface. Similar to the **ACLKEN** pin, the **SW_ENABLE** flag is not synchronized with the AXI4-Stream interfaces: Enabling or Disabling the core takes effect immediately, irrespective of the core processing status. Disabling the core for extended periods may lead to image tearing.

Bit 1 of the **CONTROL** register, **REG_UPDATE** is a write done semaphore for the host processor, which facilitates committing all user and timing register updates simultaneously. The DPC core **ACTIVE_SIZE** and **BAYER_PHASE** registers are double buffered. One set of registers (the processor registers) is directly accessed by the processor interface, while the other set (the active set) is actively used by the core. New values written to the processor registers will get copied over to the active set at the end of the AXI4-Stream frame, if and
only if `REG_UPDATE` is set. Setting `REG_UPDATE` to 0 before updating multiple register values, then setting `REG_UPDATE` to 1 when updates are completed ensures all registers are updated simultaneously at the frame boundary without causing image tearing.

Bit 4 of the `CONTROL` register, `BYPASS`, switches the core to bypass mode if debug features are enabled. In bypass mode the DPC core processing function is bypassed, and the core repeats AXI4-Stream input samples on its output. Refer to Debugging Features in Appendix C for more information. If debug features were not included at instantiation, this flag has no effect on the operation of the core. Switching bypass mode on or off is not synchronized to frame processing, therefore can lead to image tearing.

Bit 5 of the `CONTROL` register, `TEST_PATTERN`, switches the core to test-pattern generator mode if debug features are enabled. Refer to Debugging Features in Appendix C for more information. If debug features were not included at instantiation, this flag has no effect on the operation of the core. Switching test-pattern generator mode on or off is not synchronized to frame processing, therefore can lead to image tearing.

Bits 30 and 31 of the `CONTROL` register, `FRAME_SYNC_RESET` and `SW_RESET` facilitate software reset. Setting `SW_RESET` reinitializes the core to GUI default values, all internal registers and outputs are cleared and held at initial values until `SW_RESET` is set to 0. The `SW_RESET` flag is not synchronized with the AXI4-Stream interfaces. Resetting the core while frame processing is in progress will cause image tearing. For applications where the software reset functionality is desirable, but image tearing has to be avoided a frame synchronized software reset (`FRAME_SYNC_RESET`) is available. Setting `FRAME_SYNC_RESET` to 1 will reset the core at the end of the frame being processed, or immediately if the core is between frames when the `FRAME_SYNC_RESET` was asserted. After reset, the `FRAME_SYNC_RESET` bit is automatically cleared, so the core can get ready to process the next frame of video as soon as possible. The default value of both `RESET` bits is 0. Core instances with no AXI4-Lite control interface can only be reset via the `ARESETn` pin.

**STATUS (0x0004) Register**

All bits of the `STATUS` register can be used to request an interrupt from the host processor. To facilitate identification of the interrupt source, bits of the `STATUS` register remain set after an event associated with the particular `STATUS` register bit, even if the event condition is not present at the time the interrupt is serviced.

Bits of the `STATUS` register can be cleared individually by writing '1' to the bit position to be cleared.

Bit 0 of the `STATUS` register, `PROC_STARTED`, indicates that processing of a frame has commenced via the AXI4-Stream interface.

Bit 1 of the `STATUS` register, End-of-frame (`EOF`), indicates that the processing of a frame has completed.
Bit 16 of the STATUS register, SLAVE_ERROR, indicates that one of the conditions monitored by the ERROR register has occurred.

**ERROR (0x0008) Register**

Bit 16 of the STATUS register, SLAVE_ERROR, indicates that one of the conditions monitored by the ERROR register has occurred. This bit can be used to request an interrupt from the host processor. To facilitate identification of the interrupt source, bits of the STATUS and ERROR registers remain set after an event associated with the particular ERROR register bit, even if the event condition is not present at the time the interrupt is serviced.

Bits of the ERROR register can be cleared individually by writing '1' to the bit position to be cleared.

Bit 0 of the ERROR register, EOL_EARLY, indicates an error during processing a video frame via the AXI4-Stream slave port. The number of pixels received between the latest and the preceding End-Of-Line (EOL) signal was less than the value programmed into the ACTIVE_SIZE register.

Bit 1 of the ERROR register, EOL_LATE, indicates an error during processing a video frame via the AXI4-Stream slave port. The number of pixels received between the last EOL signal surpassed the value programmed into the ACTIVE_SIZE register.

Bit 2 of the ERROR register, SOF_EARLY, indicates an error during processing a video frame via the AXI4-Stream slave port. The number of pixels received between the latest and the preceding Start-Of-Frame (SOF) signal was less than the value programmed into the ACTIVE_SIZE register.

Bit 3 of the ERROR register, SOF_LATE, indicates an error during processing a video frame via the AXI4-Stream slave port. The number of pixels received between the last SOF signal surpassed the value programmed into the ACTIVE_SIZE register.

**IRQ_ENABLE (0x000C) Register**

Any bits of the STATUS register can generate a host-processor interrupt request via the IRQ pin. The Interrupt Enable register facilitates selecting which bits of STATUS register will assert IRQ. Bits of the STATUS registers are masked by (AND) corresponding bits of the IRQ_ENABLE register and the resulting terms are combined (OR) together to generate IRQ.

**Version (0x0010) Register**

Bit fields of the Version Register facilitate software identification of the exact version of the hardware peripheral incorporated into a system. The core driver can take advantage of this Read-Only value to verify that the software is matched to the correct version of the hardware.
SYSDEBUG0 (0x0014) Register

The SYSDEBUG0, or Frame Throughput Monitor, register indicates the number of frames processed since power-up or the last time the core was reset. The SYSDEBUG registers can be useful to identify external memory / Frame buffer / or throughput bottlenecks in a video system. Refer to Debugging Features in Appendix C for more information.

SYSDEBUG1 (0x0018) Register

The SYSDEBUG1, or Line Throughput Monitor, register indicates the number of lines processed since power-up or the last time the core was reset. The SYSDEBUG registers can be useful to identify external memory / Frame buffer / or throughput bottlenecks in a video system. Refer to Debugging Features in Appendix C for more information.

SYSDEBUG2 (0x001C) Register

The SYSDEBUG2, or Pixel Throughput Monitor, register indicates the number of pixels processed since power-up or the last time the core was reset. The SYSDEBUG registers can be useful to identify external memory / Frame buffer / or throughput bottlenecks in a video system. Refer to Debugging Features in Appendix C for more information.

ACTIVE_SIZE (0x0020) Register

The ACTIVE_SIZE register encodes the number of active pixels per scan line and the number of active scan lines per frame. The lower half-word (bits 12:0) encodes the number of active pixels per scan line. Supported values are between 32 and the value provided in the Maximum number of pixels per scan line field in the GUI. The upper half-word (bits 28:16) encodes the number of active lines per frame. Supported values are 32 to 7680. To avoid processing errors, the user should restrict values written to ACTIVE_SIZE to the range supported by the core instance.

THRESH_TEMPORAL_VAR (0x0100) Register

Threshold value THRESH_TEMPORAL_VAR defines the range a pixel value needs to stay in to be classified as stuck. The lower the value, the lower the chance that slowly varying pixels get characterized as stuck. However, if the sensor image is loaded with noise, or blooming may modify the readout values of dead pixels, THRESH_TEMPORAL_VAR may need to be increased to identify all stuck pixels. As a practical value for THRESH_TEMPORAL_VAR, the square root of the maximum pixel value is suggested.

THRESH_SPATIAL_VAR (0x0104) Register

Threshold value THRESH_SPATIAL_VAR defines how different a pixel needs to be from the surrounding pixels to be classified as an outlier. A practical value of $2^{\text{DATA_WIDTH}-5}$ identifies pixels that visually stand out from their surroundings. A higher threshold value for THRESH_SPATIAL_VAR results in a lower number of outlier candidates and slower
convergence time for identifying all outliers, but at the same time returns fewer false positives. If heuristics for the total number of outliers (M) are known, a feedback mechanism can be implemented that tunes `THRESH_SPATIAL_VAR` so that the number of outlier pixels identified, `num_candidates`, approximates M.

**THRESH_PIXEL_AGE (0x0108) Register**

Threshold value, `THRESH_PIXEL_AGE`, defines the number of frames presumed outliers have to hold their values within `THRESH_TEMPORAL_VAR` range before an outlier pixel is considered defective, and replacement (interpolation) of the pixels begin. The higher the value of `THRESH_PIXEL_AGE`, the less flickering due to incorrect defective pixel correction the algorithm produces, but also the longer it takes for the algorithm to converge and start replacing defective pixels. Values in the range of several thousands allow virtually no flickering while identifying outliers within minutes.

**NUM_CANDIDATES (0x010C) Register**

This read only register returns the number of potential defective pixel candidates stored in memory from the previous frame.

**NUM_DEFECTIVE (0x0120) Register**

This read only register returns the number of pixels actively being interpolated from the previous frame.

**The Interrupt Subsystem**

`STATUS` register bits can trigger interrupts so embedded application developers can quickly identify faulty interfaces or incorrectly parameterized cores in a video system. Irrespective of whether the AXI4-Lite control interface is present or not, the DPC core detects AXI4-Stream framing errors, as well as the beginning and the end of frame processing.

When the core is instantiated with an AXI4-Lite Control interface, the optional interrupt request pin (IRQ) is present. Events associated with bits of the `STATUS` register can generate a (level triggered) interrupt, if the corresponding bits of the interrupt enable register (IRQ_ENABLE) are set. Once set by the corresponding event, bits of the `STATUS` register stay set until the user application clears them by writing '1' to the desired bit positions. Using this mechanism the system processor can identify and clear the interrupt source.

Without the AXI4-Lite interface the user can still benefit from the core signaling error and status events. By selecting the Enable INTC Port check-box on the GUI, the core generates the optional INTC_IF port. This vector of signals gives parallel access to the individual interrupt sources, as seen in Table 2-13.
Unlike STATUS and ERROR flags, INTC_IF signals are not held, rather stay asserted only while the corresponding event persists.

Table 2-13: INTC_IF Signal Functions

<table>
<thead>
<tr>
<th>INTC_IF signal</th>
<th>Function</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Frame processing start</td>
</tr>
<tr>
<td>1</td>
<td>Frame processing complete</td>
</tr>
<tr>
<td>2</td>
<td>Reserved</td>
</tr>
<tr>
<td>3</td>
<td>Reserved</td>
</tr>
<tr>
<td>4</td>
<td>Video over AXI4-Stream Error</td>
</tr>
<tr>
<td>5</td>
<td>EOL Early</td>
</tr>
<tr>
<td>6</td>
<td>EOL Late</td>
</tr>
<tr>
<td>7</td>
<td>SOF Early</td>
</tr>
<tr>
<td>8</td>
<td>SOF Late</td>
</tr>
</tbody>
</table>

In a system integration tool, such as EDK, the interrupt controller INTC IP can be used to register the selected INTC_IF signals as edge triggered interrupt sources. The INTC IP provides functionality to mask (enable or disable), as well as identify individual interrupt sources from software. Alternatively, for an external processor or MCU the user can custom build a priority interrupt controller to aggregate interrupt requests and identify interrupt sources.
Chapter 3

Designing with the Core

General Design Guidelines

The DPC core corrects defective pixels from a Bayer sub-sampled image sensor data to downstream processing modules. The resulting video stream remains Bayer sub-sampled.

The core processes samples provided via an AXI4-Stream slave interface, outputs pixels via an AXI4-Stream master interface, and can be controlled via an optional AXI4-Lite interface. It is recommended that the DPC core is used in conjunction with the Video In to AXI4-Stream and Video Timing Controller cores. The Video Timing Controller core measures the timing parameters, such as number of active scan lines, number of active pixels per scan line of the image sensor. The Video In to AXI4-Stream core formats the input video to the AXI4-Stream interface.

Typically, the DPC core is part of an Image Sensor Pipeline (ISP) System, as shown in Figure 3-1.
Clock, Enable, and Reset Considerations

ACLK

The master and slave AXI4-Stream video interfaces use the ACLK clock signal as their shared clock reference, as shown in Figure 3-2.

**WRITER NOTE:** Update graphic

---

**Figure 3-2:** Example of ACLK Routing in an ISP Processing Pipeline

S_AXI_ACLK

The AXI4-Lite interface uses the S_AXI_ACLK pin as its clock source. The ACLK pin is not shared between the AXI4-Lite and AXI4-Stream interfaces. The DPC core contains clock-domain crossing logic between the ACLK (AXI4-Stream and Video Processing) and S_AXI_ACLK (AXI4-Lite) clock domains. The core automatically ensures that the AXI4-Lite transactions will complete even if the video processing is stalled with ARESETn, ACLKEN or with the video clock not running.

ACLKEN

The DPC core has two enable options: the ACLKEN pin (hardware clock enable), and the software reset option provided via the AXI4-Lite control interface (when present).

ACLKEN is by no means synchronized internally to AXI4-Stream frame processing therefore de-asserting ACLKEN for extended periods of time may lead to image tearing.

The ACLKEN pin facilitates:
Clock, Enable, and Reset Considerations

- Multi-cycle path designs (high speed clock division without clock gating),
- Standby operation of subsystems to save on power
- Hardware controlled bring-up of system components

**Note:** When ACLKEN (clock enable) pins are used (toggled) in conjunction with a common clock source driving the master and slave sides of an AXI4-Stream interface, to prevent transaction errors the ACLKEN pins associated with the master and slave component interfaces must also be driven by the same signal (Figure 2-2).

**Note:** When two cores connected via AXI4-Stream interfaces, where only the master or the slave interface has an ACLKEN port, which is not permanently tied high, the two interfaces should be connected via the AXI4-Stream Interconnect or AXI-FIFO cores to avoid data corruption (Figure 2-3).

**S_AXI_ACLKEN**

The S_AXI_ACLKEN is the clock enable signal for the AXI4-Lite interface only. Driving this signal low will only affect the AXI4-Lite interface and will not halt the video processing in the ACLK clock domain.

**ARESETn**

The DPC core has two reset source: the ARESETn pin (hardware reset), and the software reset option provided via the AXI4-Lite control interface (when present).

**Note:** ARESETn is by no means synchronized internally to AXI4-Stream frame processing, therefore de-asserting ARESETn while a frame is being process will lead to image tearing.

The external reset pulse needs to be held for 32 ACLK cycles to reset the core. The ARESETn signal will only reset the AXI4-Stream interfaces. The AXI4-Lite interface is unaffected by the ARESETn signal to allow the video processing core to be reset without halting the AXI4-Lite interface.

**Note:** When a system with multiple-clocks and corresponding reset signals are being reset, the reset generator has to ensure all reset signals are asserted/de-asserted long enough that all interfaces and clock-domains in all IP cores are correctly reinitialized.

**S_AXI_ARESETn**

The S_AXI_ARESETn signal is synchronous to the S_AXI_ACLK clock domain, but is internally synchronized to the ACLK clock domain. The S_AXI_ARESETn signal will reset the entire core including the AXI4-Lite and AXI4-Stream interfaces.
System Considerations

When using the DPC, it needs to be configured for the actual video frame-size to operate properly. To gather the frame size information from the video, it can be connected to the Video In to AXI4-Stream input and the Video Timing Controller. The timing detector logic in the Video Timing Controller will gather the video timing signals. The AXI4-Lite control interface on the Video Timing Controller allows the system processor to read out the measured frame dimensions, and program all downstream cores, such as the DPC, with the appropriate image dimensions.

If the target system will use only one setup of the DPC, the user may choose to create a constant configuration by removing the AXI4-Lite interface. This option allows reducing the core Slice footprint.

Clock Domain Interaction

The ARESETn and ACLKEN input signals will not reset or halt the AXI4-Lite interface. This allows the video processing to be reset or halted separately from the AXI4-Lite interface without disrupting AXI4-Lite transactions.

The AXI4-Lite interface will respond with an error if the core registers cannot be read or written within 128 S_AXI_ACLK clock cycles. The core registers cannot be read or written if the ARESETn signal is held low, if the ACLKEN signal is held low or if the ACLK signal is not connected or not running. If core register read does not complete, the AXI4-Lite read transaction will respond with 10 on the S_AXI_RRESP bus. Similarly, if a core register write does not complete, the AXI4-Lite write transaction will respond with 10 on the S_AXI_BRESP bus. The S_AXI_ARESETn input signal resets the entire core.

Programming Sequence

If processing parameters such as the image size needs to be changed on the fly, or the system needs to be reinitialized, it is recommended that pipelined Xilinx IP video cores are disabled/reset from system output towards the system input, and programmed/enabled from system input to system output. STATUS register bits allow system processors to identify the processing states of individual constituent cores, and successively disable a pipeline as one core after another is finished processing the last frame of data.

Error Propagation and Recovery

Parameterization and/or configuration registers define the dimensions of video frames video IP should process. Starting from a known state, based on these configuration settings the IP can predict when the beginning of the next frame is expected. Similarly, the IP can predict when the last pixel of each scan line is expected. SOF detected before it was expected (early), or SOF not present when it is expected (late), EOL detected before
expected (early), or EOL not present when expected (late), signals error conditions indicative of either upstream communication errors or incorrect core configuration.

When SOF is detected early, the output SOF signal is generated early, terminating the previous frame immediately. When SOF is detected late, the output SOF signal is generated according to the programmed values. Extra lines / pixels from the previous frame are dropped until the input SOF is captured.

Similarly, when EOL is detected early, the output EOL signal is generated early, terminating the previous line immediately. When EOL is detected late, the output EOL signal is generated according to the programmed values. Extra pixels from the previous line are dropped until the input EOL is captured.
C Model Reference

Installation and Directory Structure

This chapter contains information for installing the Defective Pixel Correction C-Model, and describes the file contents and directory structure.

Software Requirements

The Defective Pixel Correction v6.00.a C-models were compiled and tested with the following software versions.

Table 4-1: Supported Systems and Software Requirements

<table>
<thead>
<tr>
<th>Platform</th>
<th>C-Compiler</th>
</tr>
</thead>
<tbody>
<tr>
<td>Linux 32-bit and 64-bit</td>
<td>GCC 4.1.1</td>
</tr>
</tbody>
</table>

Installation

The installation of the C-Model requires updates to the PATH variable, as described below.

Linux

Ensure that the directory in which the libIp_v_spc_v6_00_a_bitacc_cmodel.so and libstlport.so.5.1 files are located is in your $LD_LIBRARY_PATH environment variable.
Unzipping the `v_spc_v6_00_a_bitacc_model.zip` file creates the following directory structures and files which are described in Table 4-2.

<table>
<thead>
<tr>
<th>File</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>/lin Pre-compiled bit accurate ANSI C reference model for simulation on 32-bit Linux Platforms</td>
<td></td>
</tr>
<tr>
<td>libIp_v_spc_v6_00_a_bitacc_cmodel.lib Defective Pixel Correction v6.00.a model shared object library (Linux platforms only)</td>
<td></td>
</tr>
<tr>
<td>libstlport.so.5.1 STL library, referenced by the Defective Pixel Correction and RGB to YCrCb object libraries (Linux platforms only)</td>
<td></td>
</tr>
<tr>
<td>run_bitacc_cmodel Pre-compiled bit accurate executable for simulation on 32-bit Linux Platforms</td>
<td></td>
</tr>
<tr>
<td>/lin64 Pre-compiled bit accurate ANSI C reference model for simulation on 64-bit Linux Platforms</td>
<td></td>
</tr>
<tr>
<td>libIp_v_spc_v6_00_a_bitacc_cmodel.lib Defective Pixel Correction v6.00.a model shared object library (Linux platforms only)</td>
<td></td>
</tr>
<tr>
<td>libstlport.so.5.1 STL library, referenced by the Defective Pixel Correction and RGB to YCrCb object libraries (Linux platforms only)</td>
<td></td>
</tr>
<tr>
<td>run_bitacc_cmodel Pre-compiled bit accurate executable for simulation on 32-bit Linux Platforms</td>
<td></td>
</tr>
<tr>
<td>/nt Pre-compiled bit accurate ANSI C reference model for simulation on 32-bit Windows Platforms</td>
<td></td>
</tr>
<tr>
<td>libIp_v_spc_v6_00_a_bitacc_cmodel.lib Pre-compiled library file for win32 compilation</td>
<td></td>
</tr>
<tr>
<td>run_bitacc_cmodel.exe Pre-compiled bit accurate executable for simulation on 32-bit Windows Platforms</td>
<td></td>
</tr>
<tr>
<td>/nt64 Pre-compiled bit accurate ANSI C reference model for simulation on 64-bit Windows Platforms</td>
<td></td>
</tr>
<tr>
<td>libIp_v_spc_v6_00_a_bitacc_cmodel.lib Pre-compiled library file for win32 compilation</td>
<td></td>
</tr>
<tr>
<td>run_bitacc_cmodel.exe Pre-compiled bit accurate executable for simulation on 64-bit Windows Platforms</td>
<td></td>
</tr>
<tr>
<td>README.txt Release notes</td>
<td></td>
</tr>
<tr>
<td>pg002_v_spc.pdf Defective Pixel Correction Interpolation Core Product Guide</td>
<td></td>
</tr>
<tr>
<td>v_spc_v6_00_a_bitacc_cmodel.h Model header file</td>
<td></td>
</tr>
<tr>
<td>rgb_utils.h Header file declaring the RGB image / video container type and support functions</td>
<td></td>
</tr>
<tr>
<td>bmp_utils.h Header file declaring the bitmap (.bmp) image file I/O functions</td>
<td></td>
</tr>
<tr>
<td>video_utils.h Header file declaring the generalized image / video container type, I/O and support functions.</td>
<td></td>
</tr>
</tbody>
</table>
Using the C-Model

The bit accurate C model is accessed through a set of functions and data structures that are declared in the `v_spc_v6_00_a_bitacc_cmodel.h` file.

Before using the model, the structures holding the inputs, generics and output of the DPC instance must be defined:

```c
struct xilinx_ip_v_spc_v6_00_a_generics spc_generics;
struct xilinx_ip_v_spc_v6_00_a_inputs   spc_inputs;
struct xilinx_ip_v_spc_v6_00_a_outputs  spc_outputs;
```

The declaration of these structures is in the `v_spc_v6_00_a_bitacc_cmodel.h` file.

Table 4-3 lists the generic parameters taken by the DPC v6.00.a IP core bit accurate model, as well as the default values. For an actual instance of the core, these parameters can only be set in generation time through the GUI.

<table>
<thead>
<tr>
<th>Generic Variable</th>
<th>Type</th>
<th>Default Value</th>
<th>Range</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>DATA_WIDTH</td>
<td>int</td>
<td>8</td>
<td>8,10,12</td>
<td>Input / output data width</td>
</tr>
<tr>
<td>STATUS_WIDTH</td>
<td>int</td>
<td>10</td>
<td>9 - 13</td>
<td>$2^{\text{STATUS_WIDTH}}$ number of defective pixels tracked</td>
</tr>
<tr>
<td>MAX_COLS</td>
<td>int</td>
<td>1920</td>
<td>32 - 7680</td>
<td>Maximum number of columns that the input video will have. Must be greater than ACTIVE_COLS</td>
</tr>
<tr>
<td>ACTIVE_COLS</td>
<td>int</td>
<td>1920</td>
<td>32 - 7680</td>
<td>Maximum number of columns in the active video</td>
</tr>
<tr>
<td>ACTIVE_ROWS</td>
<td>int</td>
<td>1080</td>
<td>32 - 7680</td>
<td>Maximum number of rows in the active video</td>
</tr>
<tr>
<td>THRESH_PIXEL_AGE</td>
<td>int</td>
<td>1200</td>
<td>0 - 65535</td>
<td>The number of frames a potential defective pixel will be tracked</td>
</tr>
<tr>
<td>THRESH_SPATIAL_VAR</td>
<td>int</td>
<td>6554</td>
<td>0 - 65535</td>
<td>The variance of the potential defective pixel against the neighboring pixels. Outside of the variance, the pixel will be considered defective.</td>
</tr>
<tr>
<td>THRESH_TEMPORAL_VAR</td>
<td>int</td>
<td>2</td>
<td>0 - 65535</td>
<td>The variance of the potential defective pixel between frames. Outside of the variance, the pixel will be considered defective.</td>
</tr>
</tbody>
</table>
Calling `xilinx_ip_v_spc_v6_00_a_get_default_generics(&spc Generics)` initializes the generics structure with the DPC GUI defaults, listed in Table 4-3.

The structure `spc_inputs` defines the values of run time parameters and the actual input image. Calling `xilinx_ip_v_spc_v6_00_a_get_default_inputs(&spc Generics, &spc_inputs)` initializes the input structure with the DPC GUI default values (see Table 4-3).

**Note:** The `video_in` variable is not initialized because the initialization depends on the actual test image to be simulated. Initializing the DPC Input Video Structure describes the initialization of the `video_in` structure.

After the inputs are defined, the model can be simulated by calling this function:

```
int xilinx_ip_v_spc_v6_00_a_bitacc_simulate(
    struct xilinx_ip_v_spc_v6_00_a Generics* generics,
    struct xilinx_ip_v_spc_v6_00_a_inputs* inputs,
    struct xilinx_ip_v_spc_v6_00_a_outputs* outputs).
```

Results are included in the outputs structure, which contains only one member, type `video_struct`. After the outputs are evaluated and saved, dynamically allocated memory for input and output video structures must be released by calling this function:

```
void xilinx_ip_v_spc_v6_00_a_destroy(
    struct xilinx_ip_v_spc_v6_00_a_inputs *input,
    struct xilinx_ip_v_spc_v6_00_a_outputs *output).
```

Successful execution of all provided functions, except for the destroy function, return value 0. A non-zero error code indicates that problems occurred during function calls.

### DPC Input and Output Video Structure

Input images or video streams can be provided to the DPC v6.00.a reference model using the `video_struct` structure, defined in `video_utils.h`:

```
struct video_struct{
    int frames, rows, cols, bits_per_component, mode;
    uint16*** data[5];
};
```

<table>
<thead>
<tr>
<th>Member Variable</th>
<th>Designation</th>
</tr>
</thead>
<tbody>
<tr>
<td>frames</td>
<td>Number of video/image frames in the data structure.</td>
</tr>
<tr>
<td>rows</td>
<td>Number of rows per frame. Pertaining to the image plane with the most rows and columns, such as the luminance channel for YUV data. Frame dimensions are assumed constant through all frames of the video stream. However different planes, such as y, u and v can have different dimensions.</td>
</tr>
</tbody>
</table>
Initializing the DPC Input Video Structure

The easiest way to assign stimuli values to the input video structure is to initialize it with an image or video. The `bmp_util.h` and `video_util.h` header files packaged with the bit accurate C models contain functions to facilitate file I/O.

### Table 4-4: Member Variables of the Video Structure (Cont’d)

<table>
<thead>
<tr>
<th>Variable</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>cols</td>
<td>Number of columns per frame. Pertaining to the image plane with the most rows and columns, such as the luminance channel for YUV data. Frame dimensions are assumed constant through all frames of the video stream. However different planes, such as y, u and v can have different dimensions.</td>
</tr>
<tr>
<td>bits_per_component</td>
<td>Number of bits per color channel/component. All image planes are assumed to have the same color/component representation. Maximum number of bits per component is 16.</td>
</tr>
<tr>
<td>mode</td>
<td>Contains information about the designation of data planes. Named constants to be assigned to mode are listed in Table 4-5.</td>
</tr>
<tr>
<td>data</td>
<td>Set of five pointers to three dimensional arrays containing data for image planes. Data is in 16-bit unsigned integer format accessed as <code>data[plane][frame][row][col]</code>.</td>
</tr>
</tbody>
</table>

### Table 4-5: Named Video Modes with Corresponding Planes and Representations

<table>
<thead>
<tr>
<th>Mode(1)</th>
<th>Planes</th>
<th>Video Representation</th>
</tr>
</thead>
<tbody>
<tr>
<td>FORMAT_MONO</td>
<td>1</td>
<td>Monochrome – Luminance only</td>
</tr>
<tr>
<td>FORMAT_RGB</td>
<td>3</td>
<td>RGB image/video data</td>
</tr>
<tr>
<td>FORMAT_C444</td>
<td>3</td>
<td>444 YUV, or YCrCb image/video data</td>
</tr>
<tr>
<td>FORMAT_C422</td>
<td>3</td>
<td>422 format YUV video, (u, v chrominance channels horizontally sub-sampled)</td>
</tr>
<tr>
<td>FORMAT_C420</td>
<td>3</td>
<td>420 format YUV video, (u, v sub-sampled both horizontally and vertically)</td>
</tr>
<tr>
<td>FORMAT_MONO_M</td>
<td>3</td>
<td>Monochrome (Luminance) video with Motion</td>
</tr>
<tr>
<td>FORMAT_RGBA</td>
<td>4</td>
<td>RGB image/video data with alpha (transparency) channel</td>
</tr>
<tr>
<td>FORMAT_C420_M</td>
<td>5</td>
<td>420 YUV video with Motion</td>
</tr>
<tr>
<td>FORMAT_C422_M</td>
<td>5</td>
<td>422 YUV video with Motion</td>
</tr>
<tr>
<td>FORMAT_C444_M</td>
<td>5</td>
<td>444 YUV video with Motion</td>
</tr>
<tr>
<td>FORMAT_RGBM</td>
<td>5</td>
<td>RGB video with Motion</td>
</tr>
</tbody>
</table>

1. The Defective Pixel Correction core supports Modes FORMAT_RGB and FORMAT_C444.
Defective Pixel Correction v6.00.a
www.xilinx.com

Using the C-Model

Bitmap Image Files

The header `bmp_utils.h` declares functions that help access files in Windows Bitmap format ([http://en.wikipedia.org/wiki/BMP_file_format](http://en.wikipedia.org/wiki/BMP_file_format)). However, this format limits color depth to a maximum of 8-bits per pixel, and operates on images with three planes (R,G,B). Consequently, the following functions operate on arguments type `rgb8_video_struct`, which is defined in `rgb_utils.h`. Also, both functions support only true-color, non-indexed formats with 24-bits per pixel.

```c
int write_bmp(FILE *outfile, struct rgb8_video_struct *rgb8_video);
int read_bmp(FILE *infile, struct rgb8_video_struct *rgb8_video);
```

Exchanging data between `rgb8_video_struct` and general `video_struct` type frames/videos is facilitated by these functions:

```c
int copy_rgb8_to_video(struct rgb8_video_struct* rgb8_in,
                        struct video_struct* video_out);
int copy_video_to_rgb8(struct video_struct* video_in,
                        struct rgb8_video_struct* rgb8_out);
```

**Note:** All image/video manipulation utility functions expect both input and output structures initialized; for example, pointing to a structure that has been allocated in memory, either as static or dynamic variables. Moreover, the input structure must have the dynamically allocated container (data or r, g, b) structures already allocated and initialized with the input frame(s). If the output container structure is pre-allocated at the time of the function call, the utility functions verify and issue an error if the output container size does not match the size of the expected output. If the output container structure is not pre-allocated, the utility functions create the appropriate container to hold results.

Binary Image/Video Files

The `video_utils.h` header file declares functions that help load and save generalized video files in raw, uncompressed format.

```c
int read_video(FILE* infile, struct video_struct* in_video);
int write_video(FILE* outfile, struct video_struct* out_video);
```

These functions serialize the `video_struct` structure. The corresponding file contains a small, plain text header defining, "Mode", "Frames", "Rows", "Columns", and "Bits per Pixel". The plain text header is followed by binary data, 16-bits per component in scan line continuous format. Subsequent frames contain as many component planes as defined by the video mode value selected. Also, the size (rows, columns) of component planes can differ within each frame as defined by the actual video mode selected.

Working with Video_struct Containers

The `video_utils.h` header file defines functions to simplify access to video data in `video_struct`.

```c
int video_planes_per_mode(int mode);
int video_rows_per_plane(struct video_struct* video, int plane);
```
Using the C-Model

```c
int video_cols_per_plane(struct video_struct* video, int plane);
```

The `video_planes_per_mode` function returns the number of component planes defined by the mode variable, as described in Table 4-5. The `video_rows_per_plane` and `video_cols_per_plane` functions return the number of rows and columns in a given plane of the selected video structure. The following example demonstrates using these functions in conjunction to process all pixels within a video stream stored in the `in_video` variable:

```c
for (int frame = 0; frame < in_video->frames; frame++) {
    for (int plane = 0; plane < video_planes_per_mode(in_video->mode); plane++) {
        for (int row = 0; row < rows_per_plane(in_video, plane); row++) {
            for (int col = 0; col < cols_per_plane(in_video, plane); col++) {
                // User defined pixel operations on
                // in_video->data[plane][frame][row][col]
            }
        }
    }
}
```

### C Model Example Code

An example C file, `run_bitacc_cmodel.c`, is provided to demonstrate the steps required to run the model. After following the compilation instructions, run the example executable. The executable takes the path/name of the input file and the path/name of the output file as parameters. If invoked with insufficient parameters, this help message is issued:

```
Usage: run_bitacc_cmodel in_file out_file
in_file : path/name of the input BMP file
out_file : path/name of the output BMP file
```

During successful execution, two files with a .bin extension are created. The first file corresponds to the input BMP image, with the same path and name as the input file, and a .bin extension. The other file similarly corresponds to the output file. These files contain the inputs and outputs of the DPC algorithm in full precision, as the BMP format does not support color resolutions beyond 8-bits per component. The structure of .bin files are described in Binary Image/Video Files.
Compiling with the DPC C-Model

Linux (32- and 64-bit)

To compile the example code, first ensure that the directory in which the files libIp_v_spc_v6_00_a_bitacc_cmodel.so and libstlport.so.5.1 are located is present in your $LD_LIBRARY_PATH environment variable. These shared libraries are referenced during the compilation and linking process. Then cd into the directory where the header files, library files and run_bitacc_cmodel.c were unpacked. The libraries and header files are referenced during the compilation and linking process.

Place the header file and C source file in a single directory. Then in that directory, compile using the GNU C Compiler:

```
gcc -m32 -x c++ ../run_bitacc_cmodel.c ../parsers.c -o run_bitacc_cmodel -L. -lIp_v_spc_v6_00_a_bitacc_cmodel -Wl,-rpath,.
gcc -m64 -x c++ ../run_bitacc_cmodel.c ../parsers.c -o run_bitacc_cmodel -L. -lIp_v_spc_v6_00_a_bitacc_cmodel -Wl,-rpath,.
```

Windows (32- and 64-bit)

Precompiled library v_spc_v6_00_a_bitacc_cmodel.dll, and top level demonstration code run_bitacc_cmodel.c should be compiled with an ANSI C compliant compiler under Windows. Here an example is presented using Microsoft Visual Studio.

In Visual Studio create a new, empty Windows Console Application project. As existing items, add:

- The llibIpv_spc_v6_00_a_bitacc_cmodel.dll file to the "Resource Files" folder of the project
- The run_bitacc_cmodel.c file to the "Source Files" folder of the project
- The v_spc_v6_00_a_bitacc_cmodel.h header files to "Header Files" folder of the project (optional)

After the project has been created and populated, it needs to be compiled and linked (built) to create a win32 executable. To perform the build step, choose **Build Solution** from the Build menu. An executable matching the project name has been created either in the Debug or Release subdirectories under the project location based on whether **Debug** or **Release** has been selected in the **Configuration Manager** under the Build menu.
SECTION II: VIVADO DESIGN SUITE

Customizing and Generating the Core

Constraining the Core

Detailed Example Design
Chapter 5

Customizing and Generating the Core

This chapter includes information on using Xilinx tools to customize and generate the core using Vivado tools.

Graphical User Interface

The Defective Pixel Correction core is easily configured to meet the developer's specific needs through the Vivado tools GUI. This section provides a quick reference to parameters that can be configured at generation time.

![Graphical User Interface – Screen 1](image)

The GUI (Figure 5-1) displays a representation of the IP symbol on the left side, and the parameter assignments on the right side, which are described as follows:
• **Component Name:** The component name is used as the base name of output files generated for the module. Names must begin with a letter and must be composed from characters: a to z, 0 to 9 and “_”. The name v_spc_v6_00_a cannot be used as a component name.

• **Video Component Width:** Specifies the bit width of the input channel. Permitted values are 8, 10, and 12.

• **Optional Features:**
  - **AXI4-Lite Register Interface:** When selected, the core will be generated with an AXI4-Lite interface, which gives access to dynamically program and change processing parameters. For more information, refer to Control Interface in Chapter 2.
  - **Include Debug Features:** When selected, the core will be generated with debugging features, which simplify system design, testing and debugging. For more information, refer to Debugging Features in Appendix C.
    
    **Note:** Note: Debugging features are only available when the AXI4-Lite Register Interface is selected.
  - **Enable INTC Port:** When selected, the core will generate the optional INTC_IF port, which gives parallel access to signals indicating frame processing status and error conditions. For more information, refer to The Interrupt Subsystem in Chapter 2.

• **Defective Pixels Tracked:** This option specifies the maximum number of potential defective pixels. Candidate defective pixels will be stored in Block RAMs.

• **Temporal Variance Threshold:** This option defines the range a pixel value needs to stay in to be classified as stuck. The lower the value, the lower the chance that slowly varying pixels get characterized as stuck. However, if the sensor image is loaded with noise, or blooming may modify the readout values of dead pixels, this option may need to be increased to identify all stuck pixels. As a practical value, the square root of the maximum pixel value is suggested.

• **Spatial Variance Threshold:** Spatial Variance Threshold defines how different a pixel needs to be from the surrounding pixels to be classified as an outlier. A practical value of $2^{\text{DATA_WIDTH}-5}$ identifies pixels that visually stand out from their surroundings. A higher threshold value results in a lower number of outlier candidates and slower convergence time for identifying all outliers, but at the same time returns fewer false positives. If heuristics for the total number of outliers (M) are known, a feedback mechanism can be implemented that tunes the threshold so that the number of outlier pixels identified, NUM_CANDIDATES, approximates M.

• **Pixel Age:** This option defines the number of frames presumed outliers have to hold their values within Temporal Threshold Variance range before an outlier pixel is considered defective, and replacement (interpolation) of the pixels begin. The higher the Pixel Age value, the less flickering due to incorrect defective pixel correction the algorithm produces, but also the longer it takes for the algorithm to converge and start
replacing defective pixels. Values in the range of several thousands allow virtually no flickering while identifying outliers within minutes.

- **Input Frame Dimensions:**
  - **Number of Active Pixels per Scan line:** When the AXI4-Lite control interface is enabled, the generated core will use the value specified in the CORE Generator GUI as the default value for the lower half-word of the `ACTIVE_SIZE` register. When an AXI4-Lite interface is not present, the GUI selection permanently defines the horizontal size of the frames the generated core instance is to process.
  - **Number of Active Lines per Frame:** When the AXI4-Lite control interface is enabled, the generated core will use the value specified in the CORE Generator GUI as the default value for the upper half-word of the `ACTIVE_SIZE` register. When an AXI4-Lite interface is not present, the GUI selection permanently defines the vertical size (number of lines) of the frames the generated core instance is to process.
  - **Maximum Number of Active Pixels Per Scan line:** Specifies the maximum number of pixels per scan line that can be processed by the generated core instance. Permitted values are from 32 to 7680. Specifying this value is necessary to establish the depth of line buffers. The actual value selected for Number of Active Pixels per Scan line, or the corresponding lower half-word of the `ACTIVE_SIZE` register must always be less than the value provided by Maximum Number of Active Pixels Per Scan line. Using a tight upper-bound results in optimal block RAM usage. This field is enabled only when the AXI4-Lite interface is selected. Otherwise contents of the field are reflecting the actual contents of the **Number of Active Pixels per Scan line** field as for constant mode the maximum number of pixels equals the active number of pixels.

**Output Generation**

Vivado generates the files necessary to build the core and place those files in the `<project>/<project>.srcs/sources_1/ip/<core>` directory.

**File Details**

The Vivado design tools output consists of some or all the following files in Table 5-1.

<table>
<thead>
<tr>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>v_spc_v6_00_a</td>
<td>Library directory for the v_spc_v6_00_a core which contain the encrypted source files.</td>
</tr>
<tr>
<td>v_tc_v5_00_a</td>
<td>Library directory for the helper core which contain the encrypted source files used with the v_spc_v6_00_a.</td>
</tr>
<tr>
<td>v_spc_v6_00_a.veo</td>
<td>Verilog instantiation template.</td>
</tr>
<tr>
<td>v_spc_v6_00_a.vho</td>
<td>VHDL instantiation template.</td>
</tr>
</tbody>
</table>
### Table 5-1: CORE Generator Output Files

<table>
<thead>
<tr>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>v_spc_v6_00_a.xci</td>
<td>IP-XACT XML file describing which options were used to generate the core. An XCI file can also be used as a source file for Vivado.</td>
</tr>
<tr>
<td>v_spc_v6_00_a.xml</td>
<td>IP-XACT XML file describing how the core is constructed so Vivado can properly build the core.</td>
</tr>
</tbody>
</table>
Chapter 6

Constraining the Core

Required Constraints
The $\text{ACLK}$ pin should be constrained at the pixel clock rate desired for your video stream.

Device, Package, and Speed Grade Selections
There are no device, package, or speed grade requirements for this core. For a complete listing of supported devices, see the release notes for this core.

Clock Frequencies
The pixel clock ($\text{ACLK}$) frequency is the required frequency for the Color Filter Array Interpolation core. See Maximum Frequencies in Chapter 2. The $\text{S\_AXI\_ACLK}$ maximum frequency is the same as the $\text{ACLK}$ maximum.

Clock Management
The core automatically handles clock domain crossing between the $\text{ACLK}$ (video pixel clock and AXI4-Stream) and the $\text{S\_AXI\_ACLK}$ (AXI4-Lite) clock domains. The $\text{S\_AXI\_ACLK}$ clock can be slower or faster than the $\text{ACLK}$ clock signal, but must not be more than 128x faster than $\text{ACLK}$.

Clock Placement
There are no specific Clock placement requirements for this core.
Banking

There are no specific Banking rules for this core.

Transceiver Placement

There are no Transceiver Placement requirements for this core.

I/O Standard and Placement

There are no specific I/O standards and placement requirements for this core.
Chapter 7

Detailed Example Design

No example design is available at the time for the LogiCORE IP Defective Pixel Correction v6.00.a core.
SECTION III: ISE DESIGN SUITE

Customizing and Generating the Core
Constraining the Core
Detailed Example Design
Chapter 8

Customizing and Generating the Core

This chapter includes information on using Xilinx tools to customize and generate the core.

Graphical User Interface

The Defective Pixel Correction core is easily configured to meet developers’ specific needs before instantiation through the CORE Generator™ or EDK graphical user interface (GUI). Once developers start to build the Defective Pixel Correction core, they are guided through and asked to set various parameters. This section provides a quick reference to the windows and parameters that can be configured at compile time.

![Graphical User Interface – Screen 1](image)

The first screen (Figure 8-1) for CORE Generator shows a representation of the IP symbol on the left side, and the settable parameters on the right, which are described as follows:

- **Component Name**: The component name is used as the base name of output files generated for the module. Names must begin with a letter and must be composed
Graphical User Interface

from characters: a to z, 0 to 9 and “_” The name v_spc_v6_00_a cannot be used as a component name.

- **Video Component Width**: Specifies the bit width of the input channel. Permitted values are 8, 10, and 12.

- **Optional Features**:
  - **AXI4-Lite Register Interface**: When selected, the core will be generated with an AXI4-Lite interface, which gives access to dynamically program and change processing parameters. For more information, refer to Control Interface in Chapter 2.
  
  - **Include Debug Features**: When selected, the core will be generated with debugging features, which simplify system design, testing and debugging. For more information, refer to Debugging Features in Appendix C.

  **Note**: Note: Debugging features are only available when the AXI4-Lite Register Interface is selected.

  - **Enable INTC Port**: When selected, the core will generate the optional INTC_IF port, which gives parallel access to signals indicating frame processing status and error conditions. For more information, refer to The Interrupt Subsystem in Chapter 2.

- **Defective Pixels Tracked**: This option specifies the maximum number of potential defective pixels. Candidate defective pixels will be stored in Block RAMs.

- **Temporal Variance Threshold**: This option defines the range a pixel value needs to stay in to be classified as stuck. The lower the value, the lower the chance that slowly varying pixels get characterized as stuck. However, if the sensor image is loaded with noise, or blooming may modify the readout values of dead pixels, this option may need to be increased to identify all stuck pixels. As a practical value, the square root of the maximum pixel value is suggested.

- **Spatial Variance Threshold**: Spatial Variance Threshold defines how different a pixel needs to be from the surrounding pixels to be classified as an outlier. A practical value of $2^{\text{DATA_WIDTH}}-5$ identifies pixels that visually stand out from their surroundings. A higher threshold value results in a lower number of outlier candidates and slower convergence time for identifying all outliers, but at the same time returns fewer false positives. If heuristics for the total number of outliers (M) are known, a feedback mechanism can be implemented that tunes the threshold so that the number of outlier pixels identified, $\text{NUM_CANDIDATES}$, approximates M.

- **Pixel Age**: This option defines the number of frames presumed outliers have to hold their values within Temporal Threshold Variance range before an outlier pixel is considered defective, and replacement (interpolation) of the pixels begin. The higher the Pixel Age value, the less flickering due to incorrect defective pixel correction the algorithm produces, but also the longer it takes for the algorithm to converge and start replacing defective pixels. Values in the range of several thousands allow virtually no flickering while identifying outliers within minutes.
• **Input Frame Dimensions:**
  
  - **Number of Active Pixels per Scan line:** When the AXI4-Lite control interface is enabled, the generated core will use the value specified in the CORE Generator GUI as the default value for the lower half-word of the $\text{ACTIVE\_SIZE}$ register. When an AXI4-Lite interface is not present, the GUI selection permanently defines the horizontal size of the frames the generated core instance is to process.
  
  - **Number of Active Lines per Frame:** When the AXI4-Lite control interface is enabled, the generated core will use the value specified in the CORE Generator GUI as the default value for the upper half-word of the $\text{ACTIVE\_SIZE}$ register. When an AXI4-Lite interface is not present, the GUI selection permanently defines the vertical size (number of lines) of the frames the generated core instance is to process.
  
  - **Maximum Number of Active Pixels Per Scan line:** Specifies the maximum number of pixels per scan line that can be processed by the generated core instance. Permitted values are from 32 to 7680. Specifying this value is necessary to establish the depth of line buffers. The actual value selected for Number of Active Pixels per Scan line, or the corresponding lower half-word of the $\text{ACTIVE\_SIZE}$ register must always be less than the value provided by Maximum Number of Active Pixels Per Scan line. Using a tight upper-bound results in optimal block RAM usage. This field is enabled only when the AXI4-Lite interface is selected. Otherwise contents of the field are reflecting the actual contents of the Number of Active Pixels per Scan line field as for constant mode the maximum number of pixels equals the active number of pixels.

  Figure 8-2 shows the EDK GUI. Definitions of the EDK GUI controls are identical to the corresponding CORE Generator GUI functions.
Graphical User Interface

Parameter Values in the XCO File

Table 8-1 defines valid entries for the XCO parameters. Xilinx strongly suggests that XCO parameters are not manually edited in the XCO file; instead, use the CORE Generator software GUI to configure the core and perform range and parameter value checking. The XCO parameters are helpful in defining the interface to other Xilinx tools.

Table 8-1: XCO Parameters

<table>
<thead>
<tr>
<th>XCO Parameter</th>
<th>Default Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>active_cols</td>
<td>1920</td>
</tr>
<tr>
<td>active_rows</td>
<td>1080</td>
</tr>
<tr>
<td>component_name</td>
<td>v_spc_v6_00_a_u0</td>
</tr>
<tr>
<td>data_width</td>
<td>8</td>
</tr>
</tbody>
</table>
### Output Generation

CORE Generator will output the core as a netlist that can be inserted into a processor interface wrapper or instantiated directly in an HDL design. The output is placed in the `<project director>`.

### File Details

The CORE Generator output consists of some or all the following files in Table 8-2.

#### Table 8-2: CORE Generator Output Files

<table>
<thead>
<tr>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>&lt;component_name&gt;_readme.txt</code></td>
<td>Readme file for the core.</td>
</tr>
<tr>
<td><code>&lt;component_name&gt;.ngc</code></td>
<td>The netlist for the core.</td>
</tr>
<tr>
<td><code>&lt;component_name&gt;.veo</code></td>
<td>The HDL template for instantiating the core.</td>
</tr>
<tr>
<td><code>&lt;component_name&gt;.vho</code></td>
<td>The structural simulation model for the core. It is used for functionally simulating the core.</td>
</tr>
<tr>
<td><code>&lt;component_name&gt;.vhd</code></td>
<td>Log file from CORE Generator software describing which options were used to generate the core. An XCO file can also be used as an input to the CORE Generator software.</td>
</tr>
<tr>
<td><code>&lt;component_name&gt;.xco</code></td>
<td>Log file from CORE Generator software describing which options were used to generate the core. An XCO file can also be used as an input to the CORE Generator software.</td>
</tr>
</tbody>
</table>

#### Table 8-1: XCO Parameters (Cont'd)

<table>
<thead>
<tr>
<th>XCO Parameter</th>
<th>Default Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>has_axi4_lite</td>
<td>false</td>
</tr>
<tr>
<td>has_debug</td>
<td>false</td>
</tr>
<tr>
<td>has_intc_if</td>
<td>false</td>
</tr>
<tr>
<td>max-cols</td>
<td>1920</td>
</tr>
<tr>
<td>status_width</td>
<td>1024</td>
</tr>
<tr>
<td>thresh_pixel_age</td>
<td>120</td>
</tr>
<tr>
<td>thresh_spatial_var</td>
<td>6554</td>
</tr>
<tr>
<td>thresh_temporal_var</td>
<td>16</td>
</tr>
</tbody>
</table>
Constraining the Core

Required Constraints

The $ACLK$ pin should be constrained at the pixel clock rate desired for your video stream.

Device, Package, and Speed Grade Selections

There are no device, package, or speed grade requirements for this core. For a complete listing of supported devices, see the release notes for this core.

Clock Frequencies

The pixel clock ($ACLK$) frequency is the required frequency for the Color Filter Array Interpolation core. See Maximum Frequencies in Chapter 2. The $S_AXI_ACLK$ maximum frequency is the same as the $ACLK$ maximum.

Clock Management

The core automatically handles clock domain crossing between the $ACLK$ (video pixel clock and AXI4-Stream) and the $S_AXI_ACLK$ (AXI4-Lite) clock domains. The $S_AXI_ACLK$ clock can be slower or faster than the $ACLK$ clock signal, but must not be more than 128x faster than $ACLK$.

Clock Placement

There are no specific Clock placement requirements for this core.
Banking

There are no specific Banking rules for this core.

Transceiver Placement

There are no Transceiver Placement requirements for this core.

I/O Standard and Placement

There are no specific I/O standards and placement requirements for this core.
Detailed Example Design

No example design is available at the time for the LogiCORE IP Defective Pixel Correction v6.00.a core.

Demonstration Test Bench

A demonstration test bench is provided which enables core users to observe core behavior in a typical use scenario. The user is encouraged to make simple modifications to the test conditions and observe the changes in the waveform.

Test Bench Structure

The top-level entity, `tb_main.v`, instantiates the following modules:

- **DUT**
  The DPC core instance under test.

- **axi4lite_mst**
  The AXI4-Lite master module, which initiates AXI4-Lite transactions to program core registers.

- **axi4s_video_mst**
  The AXI4-Stream master module, which opens the stimuli txt file and initiates AXI4-Stream transactions to provide stimuli data for the core

- **axi4s_video_slv**
  The AXI4-Stream slave module, which opens the result txt file and verifies AXI4-Stream transactions from the core

- **ce_gen**
  Programmable Clock Enable (ACLKEN) generator
Running the Simulation

- Simulation using ModelSim for Linux:
  From the console, Type "source run_mti.sh".
- Simulation using iSim for Linux:
  From the console, Type "source run_isim.sh".
- Simulation using ModelSim for Windows:
  Double-click on "run_mti.bat" file.
- Simulation using iSim:
  Double-click on "run_isim.bat" file.

Directory and File Contents

The directory structure underneath the top-level folder is:

- expected:
  Contains the pre-generated expected/golden data used by the testbench to compare actual output data.
- stimuli:
  Contains the pre-generated input data used by the testbench to stimulate the core (including register programming values).
- Results:
  Actual output data will be written to a file in this folder.
- Src:
  Contains the .vhd simulation files and the .xco CORE Generator parameterization file of the core instance. The .vhd file is a netlist generated using CORE Generator. The .xco file can be used to regenerate a new netlist using CORE Generator.

The available core C-model can be used to generate stimuli and expected results for any user bmp image. For more information, refer to Chapter 4, C Model Reference.

The top-level directory contains packages and Verilog modules used by the test bench, as well as:

- isim_wave.wcfg:
  Waveform configuration for ISIM
- mti_wave.do:
  Waveform configuration for ModelSim
• run_isim.bat:  
  Runscript for iSim in Windows

• run_isim.sh:
  Runscript for iSim in Linux

• run_mti.bat:
  Runscript for ModelSim in Windows

• run_mti.sh:
  Runscript for ModelSim in Linux
SECTION IV: APPENDICES

Verification, Compliance, and Interoperability
Migrating
Debugging
Additional Resources
Verification, Compliance, and Interoperability

Simulation

A highly parameterizable test bench was used to test the Defective Pixel Correction core. Testing included the following:

- Register accesses
- Processing multiple frames of data
- AXI4-Stream bidirectional data-throttling tests
- Testing detection, and recovery from various AXI4-Stream framing error scenarios
- Testing different ACLKEN and ARESETn assertion scenarios
- Testing of various frame sizes
- Varying parameter settings

Hardware Testing

The Defective Pixel Correction core has been validated in hardware at Xilinx to represent a variety of parameterizations, including the following:

- A test design was developed for the core that incorporated a MicroBlaze™ processor, AXI4-Lite interconnect and various other peripherals. The software for the test system included pre-generated input and output data along with live video stream. The MicroBlaze processor was responsible for:
  - Initializing the appropriate input and output buffers
  - Initializing the Color Filer Array Interpolation core
  - Launching the test
  - Comparing the output of the core against the expected results
Interoperability

The core slave (input) AXI4-Stream interface can work directly with the Video Input core. The core master (output) interface can work directly with the Color Filter Array Interpolation Xilinx Video core.

- Reporting the Pass/Fail status of the test and any errors that were found
Migrating

From version v4.0 to v5.00.a of the DPC core the following significant changes took place:

- XSVI interfaces were replaced by AXI4-Stream interfaces
- Since AXI4-Stream does not carry video timing data, the timing detector and timing generator modules were trimmed.
- The pCore, General Purpose Processor and Transparent modes became obsolete and were removed
- Native support for EDK have been added - the DPC core appears in the EDK IP Catalog
- Debugging features have been added
- The AXI4-Lite control interface register map is standardized between Xilinx video cores

From v5.00.a to v6.00.a of the DPC core, the following changes took place:

- The core originally had aclk, aclken and aresetn to control both the Video over AXI4-Stream and AXI4-Lite interfaces. Separate clock, clock enable and reset pins now control the Video over AXI4-Stream and the AXI4-Lite interfaces with clock domain crossing logic added to the core to handle the dissimilar clock domains between the AXI4-Lite and Video over AXI4-Stream domains.

Because of the complex nature of these changes, replacing a v4.0 version of the core in a customer design is not trivial. An existing EDK pCore, Transparent, or Constant DPC instance can be converted from XSVI to AXI4-Stream, the Video in to AXI4-Stream core or using components from XAPP521 (v1.0), Bridging Xilinx Streaming Video Interface with the AXI4-Stream Protocol located at: http://www.xilinx.com/support/documentation/application_notes/xapp521_XSVI_AXI4.pdf.

A v4.0 pCore instance in EDK can be replaced from v6.00.a directly from the EDK IP Catalog. However, the application software needs to be updated for the changed functionality and addresses of the DPC’s registers. Consider replacing a legacy DPC pCore from EDK with a v6.00.a instance without AXI4-Lite interface to save resources.

If the user design explicitly used the timing detector or generator functionality of the DPC core, consider adding the Video Timing Controller core to migrate the functionality.

An ISE design using the General Purpose Processor interface, all of the above steps might be necessary:
• Timing detection, generation using the Video Timing Controller Core
• Replacing XSVI interfaces with conversion modules described in XAPP521 or try using the Video in to AXI4-Stream core
• Updating the DPC core instance to v6.00.a with or without AXI4-Lite interface

The INTC interface and debug functionality are new features for v6.00.a. When migrating an existing design, these functions may be disabled.
Debugging

It is recommended to prototype the system with the AXI4-Lite interface enabled, so status and error detection, reset, and dynamic size programming can be used during debugging.

The following steps are recommended to bring-up/debug the core in a video/imaging system:

1. Bring up the AXI4-Lite interface
2. Bring up the AXI4-Stream interfaces
   - Balancing throughput

Once the core is working as expected, the user may consider 'hardening' the configuration by replacing the DPC core with an instance where GUI default values are set to the established register values, but the AXI4-Lite interface is disabled. This configuration reduces the core slice footprint.

---

Bringing up the AXI4-Lite Interface

Table C-1 describes how to troubleshoot the AXI4-Lite interface.

<table>
<thead>
<tr>
<th>Symptom</th>
<th>Solution</th>
</tr>
</thead>
<tbody>
<tr>
<td>Readback from the Version Register via the AXI4-Lite interface times out, or a core instance without an AXI4-Lite interface seems non-responsive.</td>
<td>Are the S_AXI_ACLK and ACLK pins connected? In EDK, verify that the S_AXI_ACLK and ACLK pin connections in the system.mhs file. The VERSION_REGISTER readout issue may be indicative of the core not receiving the AXI4-Lite interface.</td>
</tr>
<tr>
<td>Readback from the Version Register via the AXI4-Lite interface times out, or a core instance without an AXI4-Lite interface seems non-responsive.</td>
<td>Is the core enabled? Is s_axi_aclken connected to vcc? In EDK, verify that signal ACLKEN is connected in the system.mhs to either net_vcc or to a designated clock enable signal.</td>
</tr>
</tbody>
</table>
### Bringing up the AXI4-Stream Interfaces

Assuming the AXI4-Lite interface works, the second step is to bring up the AXI4-Stream interfaces.

#### Table C-2: Troubleshooting AXI4-Stream Interface

<table>
<thead>
<tr>
<th>Symptom</th>
<th>Solution</th>
</tr>
</thead>
<tbody>
<tr>
<td>Bit 0 of the ERROR register reads back set.</td>
<td>Bit 0 of the ERROR register, EOL_EARLY, indicates the number of pixels received between the latest and the preceding End-Of-Line (EOL) signal was less than the value programmed into the ACTIVE_SIZE register. If the value was provided by the Video Timing Controller core, read out ACTIVE_SIZE register value from the VTC core again, and make sure that the TIMING_LOCKED flag is set in the VTC core. Otherwise, using Chipscope, measure the number of active AXI4-Stream transactions between EOL pulses.</td>
</tr>
<tr>
<td>Bit 1 of the ERROR register reads back set.</td>
<td>Bit 1 of the ERROR register, EOL_LATE, indicates the number of pixels received between the last End-Of-Line (EOL) signal surpassed the value programmed into the ACTIVE_SIZE register. If the value was provided by the Video Timing Controller core, read out ACTIVE_SIZE register value from the VTC core again, and make sure that the TIMING_LOCKED flag is set in the VTC core. Otherwise, using Chipscope, measure the number of active AXI4-Stream transactions between EOL pulses.</td>
</tr>
<tr>
<td>Bit 2 or Bit 3 of the ERROR register reads back set.</td>
<td>Bit 2 of the ERROR register, SOF_EARLY, and bit 3 of the ERROR register SOF_LATE indicate the number of pixels received between the latest and the preceding Start-Of-Frame (SOF) differ from the value programmed into the ACTIVE_SIZE register. If the value was provided by the Video Timing Controller core, read out ACTIVE_SIZE register value from the VTC core again, and make sure that the TIMING_LOCKED flag is set in the VTC core. Otherwise, using Chipscope, measure the number of active AXI4-Stream transactions between subsequent SOF pulses.</td>
</tr>
<tr>
<td>s_axis_video_tready stuck low, the upstream core cannot send data.</td>
<td>During initialization, the DPC core keeps its s_axis_video_tready input low. Afterwards, the core should assert s_axis_video_tready automatically. Is m_axis_video_tready low? If so, the DPC core cannot send data downstream, and the internal FIFOs are full.</td>
</tr>
</tbody>
</table>
Debugging Features

The DPC core is equipped with optional debugging features which aim to accelerate system bring-up, optimize memory and data-path architecture and reduce time to market. The optional debug features can be turned on/off via the Include Debug Features checkbox on the GUI when an AXI4-Lite interface is present. Turning off debug features reduces the core Slice footprint.

Core Bypass Option

The bypass option facilitates establishing a straight through connection between input (AXI4-Stream slave) and output (AXI4-Stream master) interfaces bypassing any processing functionality.

### Table C-2: Troubleshooting AXI4-Stream Interface

<table>
<thead>
<tr>
<th>Symptom</th>
<th>Solution</th>
</tr>
</thead>
<tbody>
<tr>
<td>m_axis_video_tvalid stuck low, the downstream core is not receiving data</td>
<td>If the programmed active number of pixels per line is radically smaller than the actual line length, the core drops most of the pixels waiting for the (s_axis_video_tlast) End-of-line signal. Check the ERROR register.</td>
</tr>
<tr>
<td>Generated SOF signal (m_axis_video_tuser0) signal misplaced.</td>
<td>Check the ERROR register.</td>
</tr>
<tr>
<td>Generated EOL signal (m_axis_video_tlast) signal misplaced.</td>
<td>Check the ERROR register.</td>
</tr>
</tbody>
</table>
| Data samples lost between Upstream core and the DPC core. Inconsistent EOL and/or SOF periods received. | 1. Are the Master and Slave AXI4-Stream interfaces in the same clock domain?  
2. Is proper clock-domain crossing logic instantiated between the upstream core and the DPC core (Asynchronous FIFO)?  
3. Did the design meet timing?  
4. Is the frequency of the clock source driving the DPC ACLK pin lower than the reported Fmax reached? |
| Data samples lost between Downstream core and the DPC core. Inconsistent EOL and/or SOF periods received. | 1. Are the Master and Slave AXI4-Stream interfaces in the same clock domain?  
2. Is proper clock-domain crossing logic instantiated between the upstream core and the DPC core (Asynchronous FIFO)?  
3. Did the design meet timing?  
4. Is the frequency of the clock source driving the DPC ACLK pin lower than the reported Fmax reached? |
Flag **BYPASS** (bit 4 of the **CONTROL** register) can turn bypass on (1) or off, when the core instance Debugging Features were enabled at generation. Within the IP this switch controls multiplexers in the **AXI4-Stream** path.

In bypass mode the DPC core processing function is bypassed, and the core repeats **AXI4-Stream** input samples on its output.

Starting a system with all processing cores set to bypass, then by turning bypass off from the system input towards the system output allows verification of subsequent cores with known good stimuli.

**Built in Test-Pattern Generator**

The optional built-in test-pattern generator facilitates to temporarily feed the output **AXI4-Stream** master interface with a predefined pattern.

Flag **TEST_PATTERN** (bit 5 of the **CONTROL** register) can turn test-pattern generation on (1) or off, when the core instance Debugging Features were enabled at generation. Within the IP this switch controls multiplexers in the **AXI4-Stream** path, switching between the regular core processing output and the test-pattern generator. When enabled, a set of counters generate 256 scan-lines of color-bars, each color bar 64 pixels wide, repetitively cycling through Black, Red, Green, Yellow, Blue, Magenta, Cyan, and White colors till the end of each scan-line. After the Color-Bars segment, the rest of the frame is filled with a monochrome horizontal and vertical ramp.

Starting a system with all processing cores set to test-pattern mode, then by turning test-pattern generation off from the system output towards the system input allows successive bring-up and parameterization of subsequent cores.

**Throughput Monitors**

Throughput monitors enable the user to monitor processing performance within the core. This information can be used to help debug frame-buffer bandwidth limitation issues, and if possible, allow video application software to balance memory pathways.

Often times video systems, with multiport access to a shared external memory, have different processing islands. For example a pre-processing sub-system working in the input video clock domain may clean up, transform, and write a video stream, or multiple video streams, to memory. The processing sub-system may read the frames out, process, scale, encode, then write frames back to the frame buffer, in a separate processing clock domain. Finally, the output sub-system may format the data and read out frames locked to an external clock.

Typically, access to external memory using a multiport memory controller involves arbitration between competing streams. However, to maximize the throughput of the system, different memory ports may need different specific priorities. To fine tune the
Interfacing to Third-Party IP

Table C-3 describes how to troubleshoot third-party interfaces.

<table>
<thead>
<tr>
<th>Symptom</th>
<th>Solution</th>
</tr>
</thead>
<tbody>
<tr>
<td>Severe color distortion or color-swap when interfacing to third-party video IP.</td>
<td>Verify that the color component logical addressing on the AXI4-Stream TDATA signal is in alignment with the data format expected by the software drivers reading/writing external memory. If misaligned: In HDL, break up the TDATA vector to constituent components, and manually connect the slave and master interface sides. In EDK, create a new vector for the slave side TDATA connection. In the MPD file, manually assign components of the master-side TDATA vector to sections of the new vector.</td>
</tr>
<tr>
<td>Severe color distortion or color-swap when processing video written to external memory using the AXI-VDMA core.</td>
<td>Unless the particular software driver was developed with the AXI4-Stream TDATA signal color component assignments described in Data Interface in Chapter 2 in mind, there are no guarantees that the software will correctly identify bits corresponding to color components. Verify that the color component logical addressing TDATA is in alignment with the data format expected by the software drivers reading/writing external memory. If misaligned: In HDL, break up the TDATA vector to constituent components, and manually connect the slave and master interface sides. In EDK, create a new vector for the slave side TDATA connection. In the MPD file, manually assign components of the master-side TDATA vector to sections of the new vector.</td>
</tr>
</tbody>
</table>
Application Software Development

Programmer’s Guide

The software API is provided to allow easy access to the DPC AXI4-Lite registers defined in Table 2-9. To utilize the API functions, the following two header files must be included in the user C code:

```c
#include "dpc.h"
#include "xparameters.h"
```

The hardware settings of your system, including the base address of your DPC core, are defined in the `xparameters.h` file. The `dpc.h` file contains the macro function definitions for controlling the DPC pCore.

For examples on API function calls and integration into a user application, the drivers subdirectory of the pCore contains a file, `example.c`, in the `dpc_v6_00_a0_a/example` subfolder. This file is a sample C program that demonstrates how to use the DPC pCore API.

Table D-1: DPC Driver Function Definitions

<table>
<thead>
<tr>
<th>Function Name and Parameterization</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>DPC_Enable (uint32 BaseAddress)</td>
<td>Enables a DPC instance.</td>
</tr>
<tr>
<td>DPC_Disable (uint32 BaseAddress)</td>
<td>Disables a DPC instance.</td>
</tr>
<tr>
<td>DPC_Reset (uint32 BaseAddress)</td>
<td>Immediately resets a DPC instance. The core stays in reset until the RESET flag is cleared.</td>
</tr>
<tr>
<td>DPC_ClearReset (uint32 BaseAddress)</td>
<td>Clears the reset flag of the core, which allows it to re-sync with the input video stream and return to normal operation.</td>
</tr>
<tr>
<td>DPC_FSync_Reset (uint32 BaseAddress)</td>
<td>Resets a DPC instance on the next SOF signal.</td>
</tr>
<tr>
<td>DPC_ReadReg (uint32 BaseAddress, uint32 RegOffset)</td>
<td>Returns the 32-bit unsigned integer value of the register. Read the register selected by RegOffset (defined in Table 2-12).</td>
</tr>
</tbody>
</table>
Software Reset

Software reset reinitializes registers of the AXI4-Lite control interface to their initial value, resets FIFOs, forces \texttt{m\_axis\_video\_tvalid} and \texttt{s\_axis\_video\_tready} to 0. \texttt{DPC\_Reset()} and \texttt{DPC\_AutoSyncReset()} reset the core immediately if the core is not currently processing a frame. If the core is currently processing a frame calling \texttt{DPC\_Reset()}, or setting bit 30 of the CONTROL register to 1 will cause image tearing. After calling \texttt{DPC\_Reset()}, the core remains in reset until \texttt{DPC\_ClearReset()} is called.

Calling \texttt{DPC\_AutoSyncReset()} automates this reset process by waiting until the core finishes processing the current frame, then asserting the reset signal internally, keeping the core in reset only for 32 ACLK cycles, then deasserting the signal automatically. After calling \texttt{DPC\_AutoSyncReset()}, it is not necessary to call \texttt{DPC\_ClearReset()} for the core to return to normal operating mode.

\textbf{Note:} Calling \texttt{DPC\_FSync\_Reset()} does not guarantee prompt, or real-time resetting of the core. If the AXI4-Stream communication is halted mid frame, the core will not reset until the upstream core finishes sending the current frame or starts a new frame.

Double Buffering

The \texttt{ACTIVE\_SIZE} register and all of the core specific registers double-buffered to ensure no image tearing happens if values are modified during frame processing. Values from the AXI4-Lite interface are latched into processor registers immediately after writing, and processor register values are copied into the active register set at the Start Of Frame (SOF) signal. Double-buffering decouples AXI4-Lite register updates from the AXI4-Stream processing, allowing software a large window of opportunity to update processing parameter values without image tearing.

If multiple register values are changed during frame processing, simple double buffering would not guarantee that all register updates would take effect at the beginning of the same frame. Using a semaphore mechanism, the \texttt{RegUpdateEnable()} and \texttt{RegUpdateDisable()} functions allows synchronous commitment of register changes. The DPC core will start using the updated \texttt{ACTIVE\_SIZE} and core-specific values only if the \texttt{REGUPDATE} flag of the CONTROL register is set (1), after the next Start-Of-Frame signal.
(s_axis_video_tuser0) is received. Therefore, it is recommended to disable the register update before writing multiple double-buffered registers, then enable register update when register writes are completed.

**Reading and Writing Registers**

Each software register that is defined in Table 2-12 has a constant that is defined in spc.h which is set to the offset for that register listed in Table D-2. It is recommended that the application software uses the predefined register names instead of register values when accessing core registers, so future updates to the DPC drivers which may change register locations will not affect the application dependent on the DPC driver.

*Table D-2: Predefined Constants Defined in spc.h*

<table>
<thead>
<tr>
<th>Constant Name Definition</th>
<th>Value</th>
<th>Target Register</th>
</tr>
</thead>
<tbody>
<tr>
<td>DPC_CONTROL</td>
<td>0x0000</td>
<td>CONTROL</td>
</tr>
<tr>
<td>DPC_STATUS</td>
<td>0x0004</td>
<td>STATUS</td>
</tr>
<tr>
<td>DPC_ERROR</td>
<td>0x0008</td>
<td>ERROR</td>
</tr>
<tr>
<td>DPC_IRQ_ENABLE</td>
<td>0x000C</td>
<td>IRQ_ENABLE</td>
</tr>
<tr>
<td>DPC_VERSION</td>
<td>0x0010</td>
<td>VERSION</td>
</tr>
<tr>
<td>DPC_SYSDEBUG0</td>
<td>0x0014</td>
<td>SYSDEBUG0</td>
</tr>
<tr>
<td>DPC_SYSDEBUG1</td>
<td>0x0018</td>
<td>SYSDEBUG1</td>
</tr>
<tr>
<td>DPC_SYSDEBUG2</td>
<td>0x001C</td>
<td>SYSDEBUG2</td>
</tr>
<tr>
<td>DPC_ACTIVE_SIZE</td>
<td>0x0020</td>
<td>ACTIVE_SIZE</td>
</tr>
<tr>
<td>DPC_THRESH_TEMPORAL_VAR</td>
<td>0x0100</td>
<td>THRESH_TEMPORAL_VAR</td>
</tr>
<tr>
<td>DPC_THRESH_SPATIAL_VAR</td>
<td>0x0104</td>
<td>THRESH_SPATIAL_VAR</td>
</tr>
<tr>
<td>DPC_THRESH_PIXEL_AGE</td>
<td>0x0108</td>
<td>THRESH_PIXEL_AGE</td>
</tr>
<tr>
<td>DPC_NUM_CANDIDATES</td>
<td>0x010C</td>
<td>NUM_CANDIDATES</td>
</tr>
<tr>
<td>DPC_NUM_DEFECTIVE</td>
<td>0x0120</td>
<td>NUM_DEFECTIVE</td>
</tr>
</tbody>
</table>
Appendix E

Additional Resources

Xilinx Resources

For support resources such as Answers, Documentation, Downloads, and Forums, see the Xilinx Support website at:


For a glossary of technical terms used in Xilinx documentation, see:


For a comprehensive listing of Video and Imaging application notes, white papers, reference designs and related IP cores, see the Video and Imaging Resources page at:


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.

References

These documents provide supplemental material useful with this user guide:

1. UG761 AXI Reference Guide.
Technical Support

Xilinx provides technical support at www.xilinx.com/support for this LogiCORE™ IP product when used as described in the product documentation. Xilinx cannot guarantee timing, functionality, or support of product if implemented in devices that are not defined in the documentation, if customized beyond that allowed in the product documentation, or if changes are made to any section of the design labeled DO NOT MODIFY.

See the IP Release Notes Guide (XTP025) for more information on this core. For each core, there is a master Answer Record that contains the Release Notes and Known Issues list for the core being used. The following information is listed for each version of the core:

- New Features
- Resolved Issues
- Known Issues

Revision History

The following table shows the revision history for this document.

<table>
<thead>
<tr>
<th>Date</th>
<th>Version</th>
<th>Revision</th>
</tr>
</thead>
<tbody>
<tr>
<td>4/24/2012</td>
<td>2.0</td>
<td>Updated for core version. Added Zynq-7000 devices, added AXI4-Stream interfaces, deprecated GPP interface.</td>
</tr>
<tr>
<td>07/25/2012</td>
<td>3.0</td>
<td>Updated for core version. Added Vivado information.</td>
</tr>
</tbody>
</table>
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