

EXERCISE 4

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All questions have been performed on Jetson Board

QUESTION 1

```
ubuntu@tegra-ubuntu:~$ lsusb

Bus 002 Device 011: ID 046d:0802 Logitech, Inc. Webcam C200

Bus 002 Device 008: ID 0461:4d51 Primax Electronics, Ltd 0Y357C PMX-MMOCZUL (B) [Dell Laser Mouse]

Bus 002 Device 007: ID 413c:2113 Dell Computer Corp.

Bus 002 Device 006: ID 214b:7000

Bus 002 Device 001: ID 1d6b:0002 Linux Foundation 2.0 root hub

Bus 001 Device 001: ID 1d6b:0002 Linux Foundation 2.0 root hub

Bus 003 Device 001: ID 1d6b:0002 Linux Foundation 2.0 root hub

Bus 003 Device 001: ID 1d6b:0002 Linux Foundation 2.0 root hub

ubuntu@tegra-ubuntu:~$ lsusb | grep C200

Bus 002 Device 011: ID 046d:0802 Logitech, Inc. Webcam C200

ubuntu@tegra-ubuntu:~$
```

The "Isusb" command is first run in order to display the USB buses in the system and the various devices connected to these buses. The "Isusb | grep C200" command is executed to confirm that the camera is connected.

```
ubuntu@tegra-ubuntu:~$ dmesg | grep video

[ 0.534697] Linux video capture interface: v2.00

[ 4.230610] usbcore: registered new interface driver uvcvideo
ubuntu@tegra-ubuntu:~$ dmesg | grep video

[ 0.534697] Linux video capture interface: v2.00

[ 4.230610] usbcore: registered new interface driver uvcvideo

[ 69.008966] uvcvideo: Found UVC 1.00 device <unnamed> (046d:0802)
ubuntu@tegra-ubuntu:~$ dmesg | grep video

[ 0.534697] Linux video capture interface: v2.00

[ 4.230610] usbcore: registered new interface driver uvcvideo

[ 69.008966] uvcvideo: Found UVC 1.00 device <unnamed> (046d:0802)
ubuntu@tegra-ubuntu:~$
```

The "dmesg | grep video" command is executed in order to ensure that the USB device i.e. the camera was found.



QUESTION 2

The Cheese Tool is installed and used as shown below:

```
Cheese:12895): Cheese-WARNING **: Internal data flow problem: gotbasesink.c(3264): gst base_sink_chain_unlocked (): /GstCameraBin:camerabin/GstWrapperCameraBinSrc:camera_source/GstBin:video_filter_bin/Cl
Received buffer without a new-segment. Assuming timestamps start from 8.

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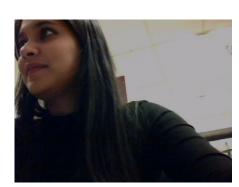
Woglikandle: infreed handle of upon egi deint: type=2 refcnt=1

Woglikandle: infreed handle of upon egi deint: type=2 refcnt=1

Woglikandle: infreed handle of upon egi deint: type=2 refcnt=1

Woglikandle: infreed handle of upon egi deint: type=2 refcnt=1
```

Screenshot of capture using Cheese Tool:





The various effects using the Cheese Tool:











QUESTION 3

Simpler Capture

```
ubuntu@tegra-ubuntu:~/Downloads/excercise 4/simpler-capture$ make
g++ -00 -g -c capture.cpp
g++ -00 -g -c capture capture.o `pkg-config --libs opencv` -L/usr/lib -lopencv_core -lopencv_flann -lopencv_video
ubuntu@tegra-ubuntu:~/Downloads/excercise 4/simpler-capture$ ls
capture capture.cpp capture.o Makefile
ubuntu@tegra-ubuntu:~/Downloads/excercise 4/simpler-capture$ ./capture
```



This code is used for continuous streaming of picture using an infinite loop in which the image frame is captured, and it is checked if it is NULL which would result in break. cvNamedWindow API is used to create a window called Simple capture example and cvShowImage API is used to display the image in this named window. ESC key can be used to terminate the program.

Simple Capture 2

```
ubuntu@tegra-ubuntu:~/Downloads/excercise 4/simpler-capture-2$ make all
g++ -00 -g -c capture.cpp
g++ -00 -g -o capture capture.o `pkg-config --libs opencv` -L/usr/lib -lopencv_core -lopencv_flann -lopencv_video
ubuntu@tegra-ubuntu:~/Downloads/excercise 4/simpler-capture-2$ ls
capture capture.cpp capture.cpp~ capture.o Makefile
ubuntu@tegra-ubuntu:~/Downloads/excercise 4/simpler-capture-2$ ./capture
```

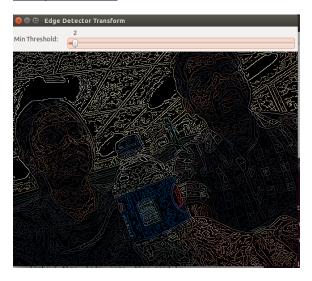


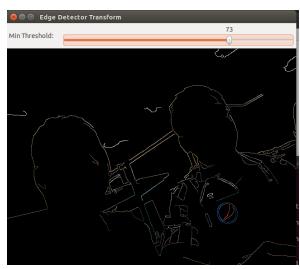


This code is used for continuous streaming of picture using an infinite loop in which the image frame is captured, and it is checked if it is NULL which would result in break. cvNamedWindow API is used to create a window called Simpler capture 2 Example and cvShowImage API is used to display the image in this named window. cvSetCaptureProperty API is used to set the width and height of the image frames. ESC key can be used to terminate the program.

QUESTION 4

Canny Interactive

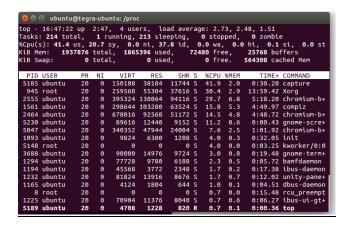




This code is used to apply canny transform on images which is basically an edge detection transform. createTrackbar API is used to create a trackbar to set the low threshold for the implementation of the canny algorithm. mat_frame is an object of Mat class which is initialised with captured image frame. cvtColor API to convert the image to grey scale from RGB. Noise reduction is done using blur API with a filter of kernel size of 3X3. Canny API is used to return the edge detected canny mask. It takes lowthreshold and highthreshold as argument where highthreshold is coded as 3 times the lowthreshold value. If the variation in the gradient is higher than the highthreshold, then it is detected as a boundary of an edge and if it is between the lowthreshold and the high threshold, then it is detected as a continuation of an edge and if it is lower than the low threshold, then it is ignored. Scalar::all(0) is used to fill the image with zeros. copyTo function returns the original image masked using canny mask. imshow function is used to display the resutant image. The program will terminate when the user presses q.

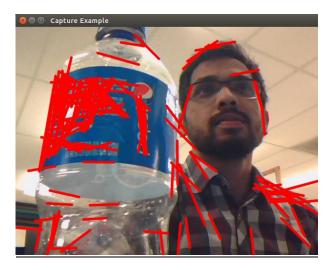


CPU Loading



On running the top command, we can see that CPU Loading is 41.9%.

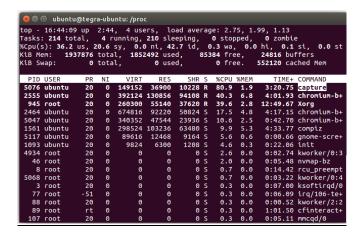
Hough Interactive



This code is used to apply hough transform on images which is basically a straight line detection transform. mat_frame is an object of Mat class which is initialised with captured image frame. The canny transform is applied to detect the edges of this image. lines is a variable of vector type which stores the 4 intergers for the lines that are detected in the image. HoughLinesP function returns the endpoints of the detected lines. Line function is used draw the lines on the original image i.e. mat_frame. cvShowImage is used to display the resultant image. The program will terminate when the user presses ESC.



CPU Loading



On running the top command, we can see that CPU Loading is 80.9%.

QUESTION 5

<u>Note:</u> We have used a single program to calculate the average frame rate for each of the 3 interactive transformations and to check if the transformations meets its respective deadline.

By default, the program just checks and analyses if the transformations meet its respective deadlines.

To calculate just the average frame rate without checking for deadline, "#define CAL_FRAME_RATE" should be uncommented and "#define CHECK_DEADLINE" should be commented out.

The following transformations were used in this program:

- Canny Edge Detection
- Hough Transform
- Hough Elliptical Transform

Calculating average frame rate

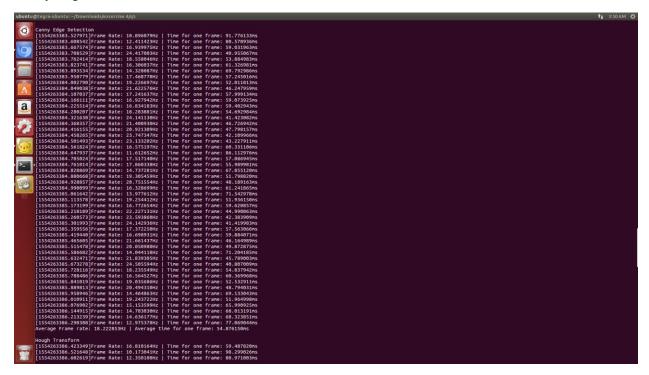
The transformation is carried out on 50 frames to calculate the average frame rate and therefore determine the deadline. Time taken between 2 consecutive frames is negated to determine time taken to run one frame. 1 is divided by this value to get the frames per second (fps). After 50 frames are obtained and processed on, the average frame rate is determined for each transformation.

The following screenshots shows the average frame rate calculation for each resolution and for each of the transformations.

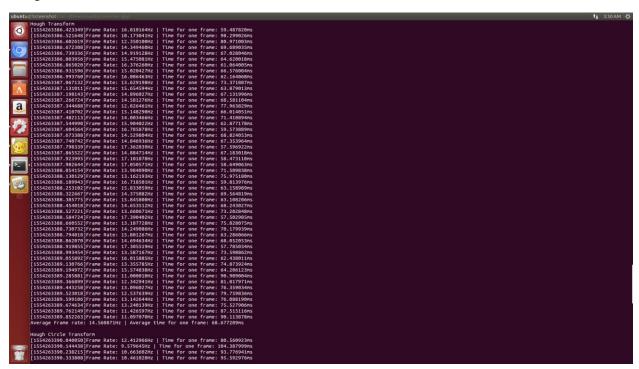


640x480

Canny Edge Detection

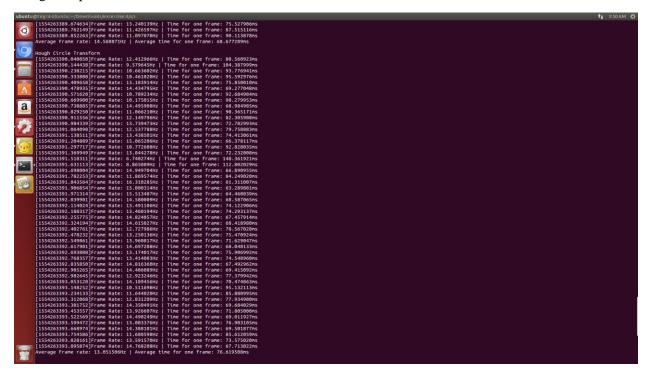


Hough Transform



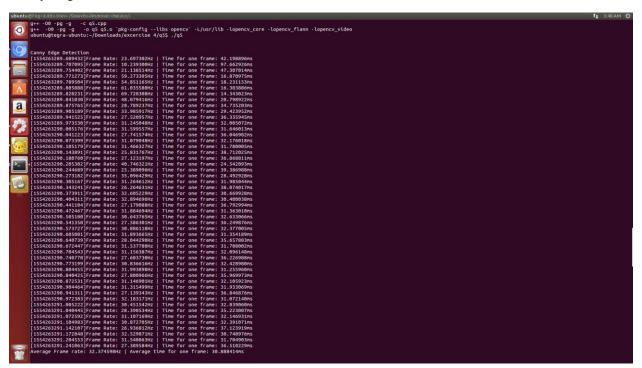


Hough Elliptical Transform



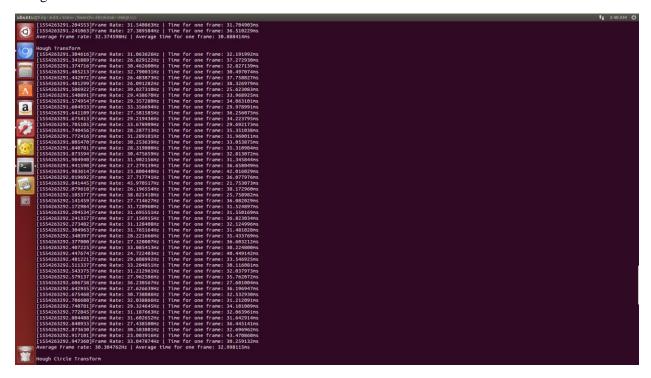
160x120

Canny Edge Detection

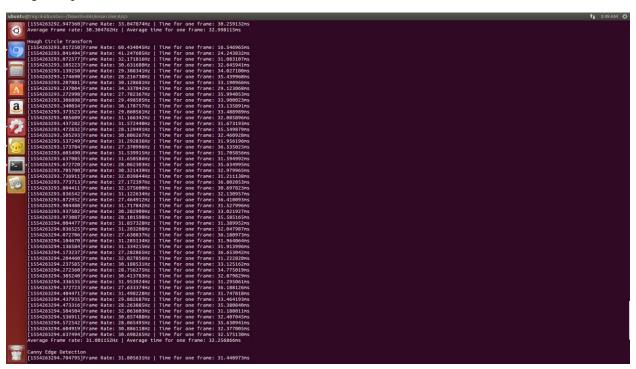




Hough Transform



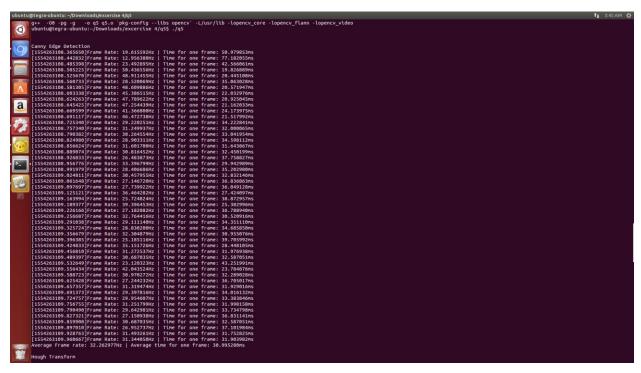
Hough Elliptical Transform



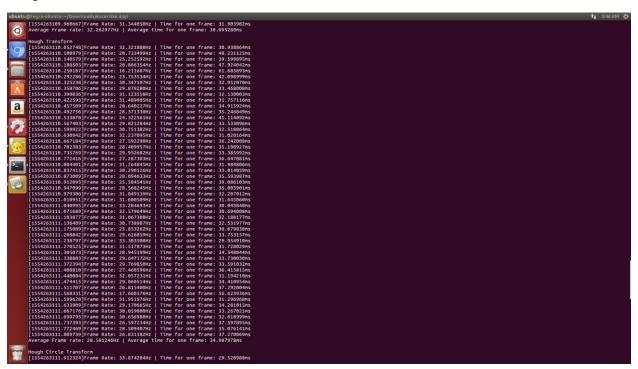


320x240

Canny Edge Detection

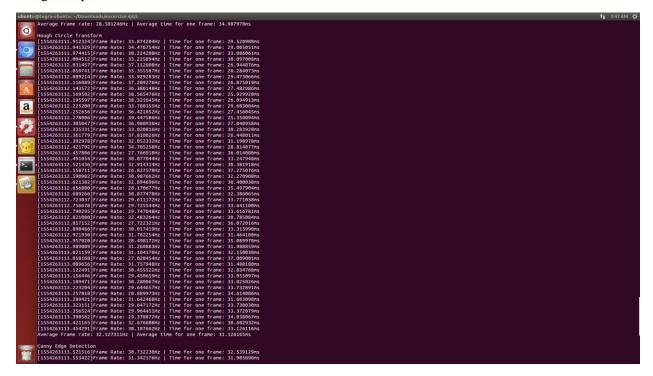


Hough Transform





Hough Elliptical Transform



According to our analysis and the above images, following are the average frame rates obtained:

	640x480	160x120	320x240
Canny Edge Detection	21 fps	31 fps	32 fps
Hough Transform	14 fps	31 fps	28 fps
Hough Elliptical Transform	13 fps	32 fps	32 fps

Following are the deadlines (with margin) used:

	640x480	160x120	320x240
Canny Edge Detection	63ms	47ms	46ms
Hough Transform	89ms	47ms	51ms
Hough Elliptical Transform	92ms	46ms	46ms

Determining if transformation meets deadline

SCHED_FIFO scheduling algorithm is utilized to execute this program.

Using the above calculated deadlines, the time taken to carry out the transformation on each of the frame is checked with the deadline to determine if the deadline is missed or if the deadline is passed. If the deadline is passed, the positive jitter is printed. If the deadline is missed, a message is printed along with the frame number and the negative jitter. At the end of 50 frames, an analysis is printed, which prints the number of deadlines missed, the number of deadlines passed, the average positive jitter and average negative jitter. Once this is carried out for 50 frames for one transformation, the analysis for the 50 frames for other transformation is carried out. Therefore, 50 frames for each transformation is processed and analyzed



sequentially in an infinite loop. Three Semaphores regulate this sequence of execution. Therefore, 50 frames of Canny Edge Detection are analyzed, then 50 frames of Hough Transform, then 50 frames of Hough Elliptical Transform, and so on infinitely. The semaphore also protects the camera object in each thread and ensures there is no contention among the 3 three threads.

Final predictable response jitter analysis

The final screenshots of the response analysis are attached below. The analysis of the 50 frames is at the bottom which displays the number of missed deadlines, number of passed deadlines, the average of positive jitter and the average of negative jitter.

640x480

Canny Edge Detection

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160x120

Canny Transform

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```

Hough Transform

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Hough Elliptical Transform

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320x240

Canny Transform

```
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Hough Transform

```
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```

Hough Elliptical Transform

```
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```



REFERENCES

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https://docs.opencv.org/3.0-beta/doc/py_tutorials/py_imgproc/py_houghlines/py_houghlines.html https://docs.opencv.org/3.4/d4/d70/tutorial_hough_circle.html