

# Stepping into next-generation architectures for multi-camera operations in automobiles

A highly integrated approach to achieve extended synchronization and advanced high-dynamic range image quality to enable automotive surround view and camera monitoring systems



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# Introduction

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Today's surround view systems may have four cameras or more to observe and analyze the scene around an automobile. Typically, at least four camera streams will be stitched together in a 2D or 3D display for the best driver experience.

Camera monitor systems (CMS), which are now replacing as many as six mirrors on trucks, may require two cameras on the driver's side and two cameras on the passenger side, rendering the video streams to create a very wide view. Both architectures interconnect megapixel image sensors with one central application processor by bridging the long distance over a single coax cable. This requires that the video streams to arrive fully synchronized. While current generation systems are 1 megapixel (MP) in resolution, but next-generation systems demand image resolutions of 2 MP and more at up to 60 frames per second frame (fps) rate. Light-emitting diode (LED) flickering caused by the pulse-width modulation (PWM) of LED lights in traffic signs and cars is another problem. In addition, the market demands higher dynamic range (HDR) imaging suitable for extreme lighting conditions, requiring additional pixel processing.

Video stream transmission systems need to feature central clock distribution; video synchronization, back-channel communication and power over coax (PoC) capabilities. In order to achieve all this, highly integrated solutions feature chipsets of multiple FPD-Link serializers combined with a single FPD-Link deserializer hub.

This paper discusses how to fulfill market demands for HDR, LED flicker mitigation, low-light performance and advanced image quality.

## Image sensor technology

Today's complementary metal-oxide semiconductor (CMOS) color imagers provide 1 MP, 2 MP or more on an image sensor chip for automotive applications. They record highly detailed images, providing video streams up to 60 fps. HDR sensors usually output multiple images for the same frame with different exposure/gain values. There are many sensor architectures like split-pixel, digital overlap and staggered HDR. Those sensor architectures require significantly higher computational

performance in image signal processing (ISP) units to process HDR images. Currently, image sensor manufacturers are moving the ISP block off the imager chip to limit power dissipation and heat generation in the camera and help increase image quality. In addition, this helps counter for the larger technology node that the imagers are fabricated in. So, ISPs will be integrated into vision processors (SoC) or remain as standalone devices. With advanced HDR capabilities, ISPs can even process multiple camera streams concurrently, reducing the

number of ISP devices needed in the system. To accomplish this, camera streams need additional indication for channel separation otherwise, the video streams may get mixed up in the system path.

## Multi-camera processing with external ISP

This section highlights the signal chain of the [Texas Instruments \(TI\) Automotive ADAS Reference Design for Four-Camera Hub with Integrated ISP and DVP Outputs](#). Flat panel display (FPD-Link III) serializers such as the DS90UB933 or DS90UB953 transform an incoming parallel low-voltage CMOS (LVCMOS) or a camera serial interface (CSI-2) stream into a single high-speed differential pair. The serializers can accept up to 12 bits of data plus 2 bits (for example, horizontal sync [HSYNC]/vertical sync [VSYNC]) plus a pixel clock (PCLK). In turn, the FPD-Link III deserializer hub (the DS90UB964 or DS90UB960), when coupled with serializers receives the streams from up to four image sensors concurrently. The deserializer hub provides two Mobile Industry Processor Interface (MIPI) CSI-2 output ports, each consisting of four physical lanes. The deserializer decodes incoming streams for multiplexing on one or two of the MIPI CSI-2 output ports.

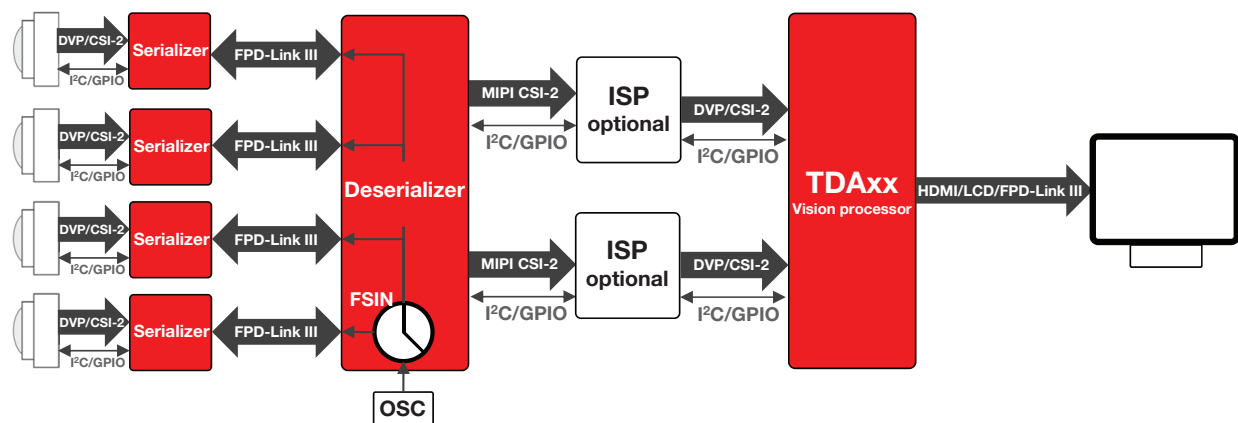
In order to keep the incoming video streams separated, the MIPI CSI-2 ports offer up to four virtual channels. Every data stream is partitioned

into packets designated for each virtual channel. The ISP combines values with different exposures to generate image frames and also provides local tone scaling to provide HDR images that are pleasing to the eye, filling dark areas with pixels from long exposure values while bright areas will be filled with pixels from either mid or short values. As a result, the image pixels of each video stream provide an extended dynamic range.

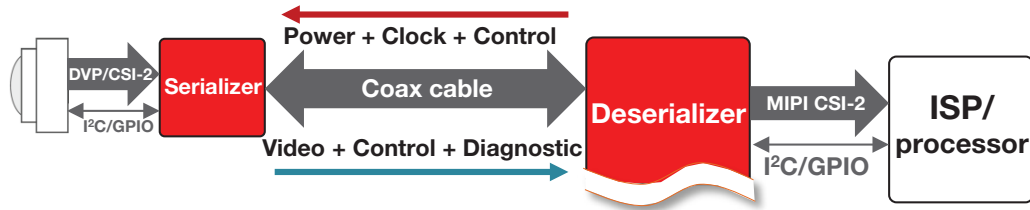
The weighted output of the combination feeds back into the ISP's sub modules as, such as automatic gain control (AGC), automatic exposure control (AEC) in order to calculate statistics. The statistics and histogram can be transferred to the host as part of idle rows within the video stream. **Figure 1** illustrates the use of an external ISP, reducing the number of ISP devices in the system to two rather than four (one for each camera module).

## Vision processing

TI's TDAxx vision processor, illustrated in **Figure 1**, requires an external ISP. The video streams arrive in the processor's memory through its video interface ports (VIPs) without burdening the processing cores. Instead, its direct memory access (DMA) controller ensures that all video streams are stored in its frame buffers. In turn, the processing cores receive notifications via interrupts when new frames arrive. The processor's software accesses the frame



**Figure 1.** Quad-camera design with an external ISP.



**Figure 2.** FPD-Link channel technology offers multiple features.

buffers as needed to process the video data. For monitoring purposes multiple video streams can be stitched to form up a rendered single “multi-channel” video stream. TDAx processors offer several options to output video streams onto a monitoring back end. Beside HDMI and RGB LCDs even transfers over FPD-Link III serializers (e.g., DS90UB925) are possible. Those will bridge longer distances to the display side.

Next-generation TDAx processors integrate the ISP on-chip pushing chip integration to a higher level. This results in reduced cost, better photometric alignment and lower power consumption.

### Achieving video stream synchronization

Camera synchronization can become a challenge. The processing time of each camera can vary due to component tolerances or even conditions in the visual scene being processed, necessitating the introduction of time stamp mechanisms in software to overcome the problem. However, additional software would further utilize the vision processor. As a solution, we will discuss four hardware features that ensure frames from all video streams arrive in the vision processor at same time and no additional software engagement would be required.

### Back-channel technology

The SerDes integrated bidirectional control channel transfers data over the same cable. It eliminates the need for additional wires for programming the

image sensors’ registers via I<sup>2</sup>C. The bidirectional control channel also allows controlling GPIO pins of the SerDes chips in both directions. It is commonly used to send frame sync trigger pulses from the central processing unit into the image sensors for synchronization. It can concurrently carry status signals from all image sensors and pass it on to the central processing unit for monitoring purposes. The bidirectional control channel can also carry a central system reference clock from the deserializer to each camera serializer. **Figure 2** illustrates the bi-directional control channel highlighting its feature set. Power transmission, clock distribution and control information can be provided on the back channel. Instead, the video streams, control and diagnostic information will be provided on the forward channel.

### Central clock distribution

A central reference clock applied at the deserializer hub is distributed to all camera modules. In this mode, each serializer is able to derive its clock from the FPD-Link III system link. The serializers drive the clock into each image sensor’s system clock input pin avoiding camera streams drifting beyond each other. Central clock distribution ensures all the cameras are operating in the same clock domain, eliminating the need for data buffering and re-synchronization. **Figure 3** on the following page illustrates the impact of central clock distribution vs. individual clock supply.

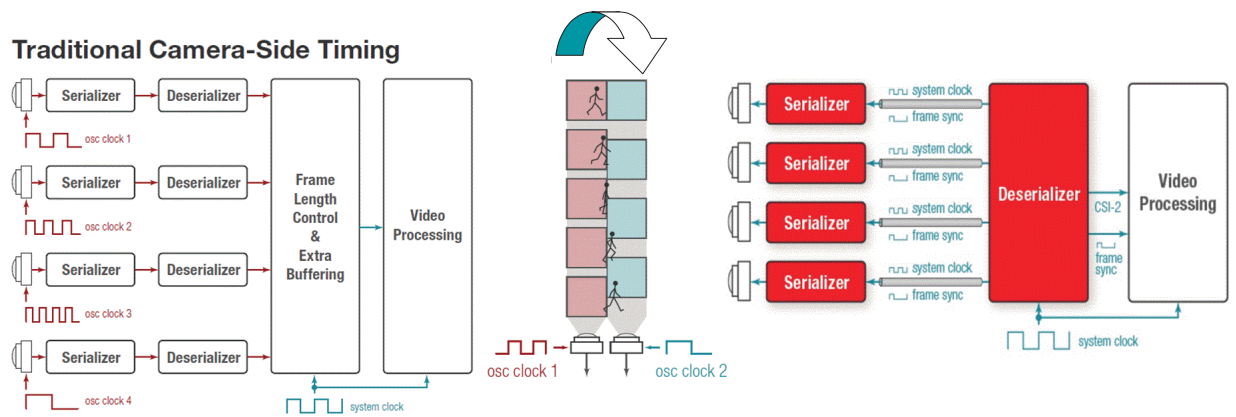


Figure 3. Central clock distribution ensures cameras are in sync.

## Central frame synchronized trigger

Common image sensors offer a single frame synchronization input (FSIN) (see Figure 4). FSIN controls each image sensor's capture logic. During normal operation, when the frame synchronization pulse is applied, a new frame will start automatically. The introduction of one additional line extends the frame height until frame synchronization occurs. An appropriate deserializer hub can generate a periodic synchronization pulse using its internal timer. The deserializer hub passes the periodic frame synchronization pulse to all the serializers. In turn, the serializers pass the pulse to each

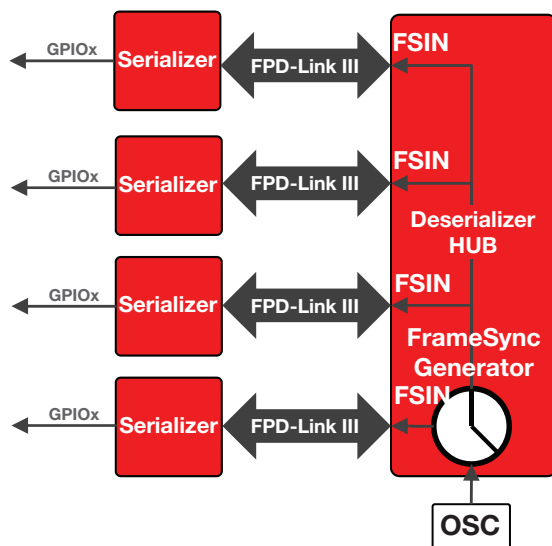


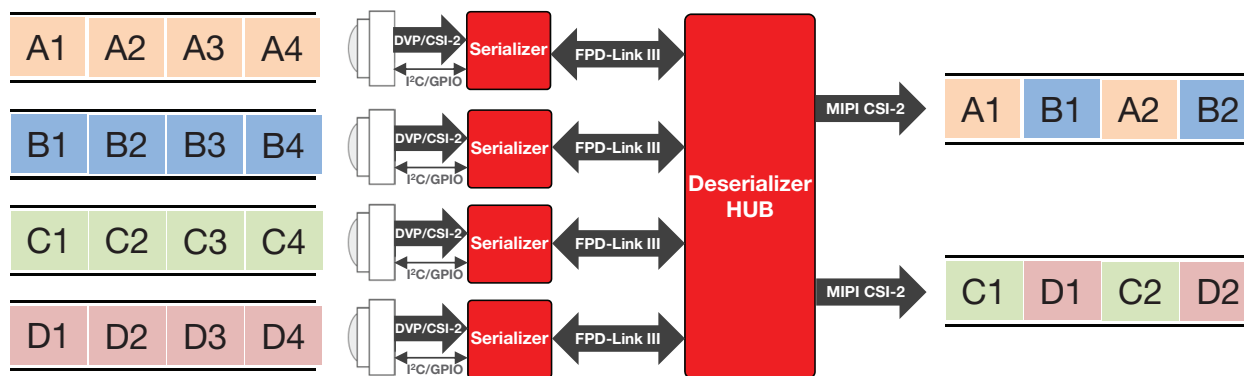
Figure 4. Frame synchronization controls image sensors.

camera using its GPIOs. This concept guarantees the simultaneous start of frames from all camera streams, with a variance of one line maximum.

## Line-based synchronization

Commonly, deserializer hubs support several line synchronization modes. In non-synchronized forwarding mode, the deserializer hub embeds the lines from all video streams in a “first come, first send” order. The same video lines from all cameras do not arrive in the ISP at the same time. Thus, lines captured at the same time are not stored in the buffer queues of the vision processor sequentially.

In synchronized forwarding mode, the deserializer hub waits for the video lines from all camera modules to arrive before encoding the lines and embedding them into the CSI-2 output stream. As a result, the same lines from all cameras are interleaved. The deserializer's job is to pack the incoming streams into one or two MIPI CSI-2 output streams. To do so, virtual channel identifiers (VC-ID) differentiate video streams on the MIPI CSI-2 output bus, so that the ISP and the vision processor can distinguish the streams. If the vision processor is programmed to provide four independent buffer queues in memory, frames from each of the video streams will be stored in their own queue. This method leads to a scheme in which each frame



**Figure 5.** Virtual channels transfer four video streams across two interface outputs. Colored boxes highlight the moving and nonmoving vehicles and pedestrians in the scene.

captured at the same time will be stored in the queues side by side. For instance, the frame from all four streams captured at time slot x in buffer queues at the same location x, therefore eliminating the need for time-stamp support. **Figure 5** illustrates how four video streams are merged to become two combined output streams.

## Power-over-coax (PoC)

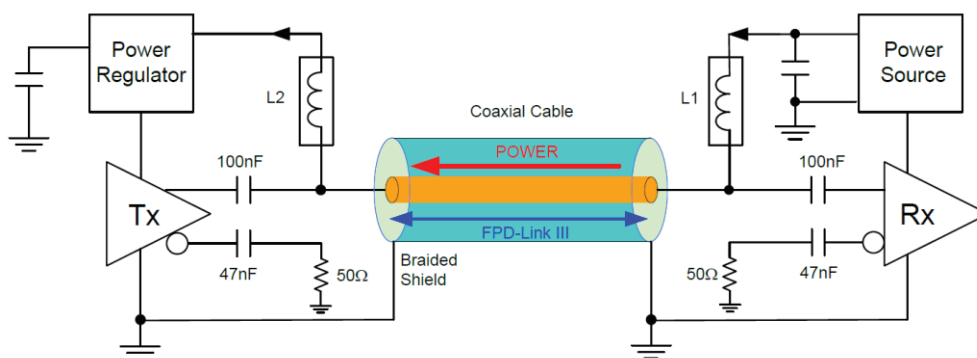
Applying power over the data coax cable, or PoC, is a convenient way to power the camera without extra cabling. Supplying the camera modules over a coax line and the cable's shielding eliminates the need for additional wires. On the deserializer side power can be injected to supply all camera modules. Separating the DC power supply from the data signals requires the incorporation of PoC filters. For more details on PoC filter design, see the

application report, “[Sending Power Over Coax in DS90UB913A Designs](#)”. **Figure 6** illustrates the scheme injecting power into the transmission line.

## Multi-camera processing with internal ISP

TI's TDAx processors include an on-chip ISP. This ISP is powerful enough to handle up to eight 1-MP cameras. These processors also provide one or more quad-lane CSI-2 Rx interfaces with support for four virtual channels and four instances of parallel video input ports. Thus, you can interface a large number of cameras. **Figure 7** and **Figure 8** on the following page illustrate two examples out of many architectural options.

The camera output(s) can be completely RAW and all the processing will be done on the internal ISP.



**Figure 6.** Power-over-Coax (PoC) supplies camera modules with power.

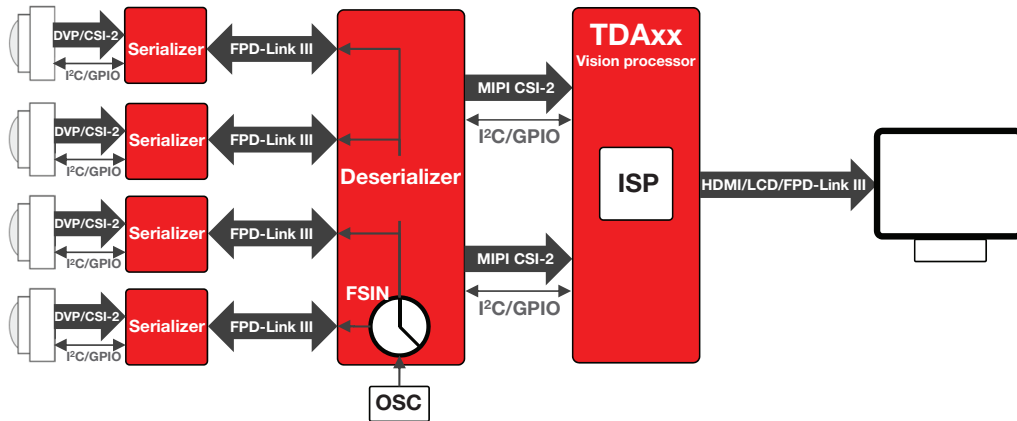


Figure 7. Optimized quad-camera design used for surround view applications.

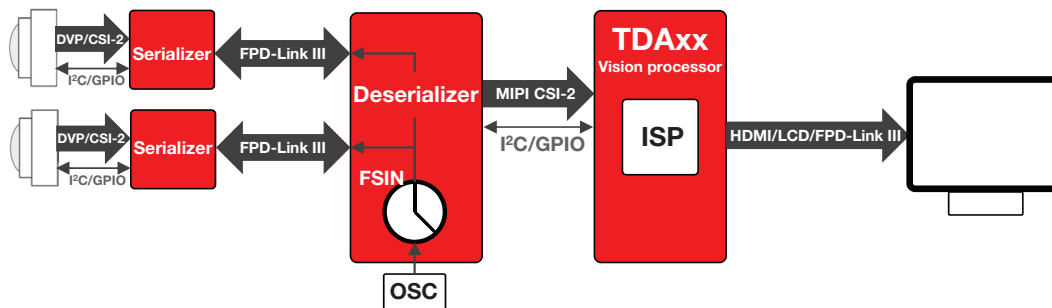


Figure 8. Optimized dual-camera design used for camera monitoring systems.

Time-slicing the image processing enables the handling of multiple cameras at very high frame rates while consuming low power. Virtual Channels (VC), as defined by the MIPI standard, allow up to four camera streams to be packed in a single CSI-2 byte stream. TDAx CSI-2 receivers can interpret VC information and separate it into independent streams. The ISP has hardware sub-blocks for all image processing needs such as black-level correction, auto exposure, auto white balance, noise reduction, high dynamic range, color correction, etc. In addition, the de-warping module (DeWarp), can correct geometric and perspective distortion and generate *GPU like* 3D transition effects.

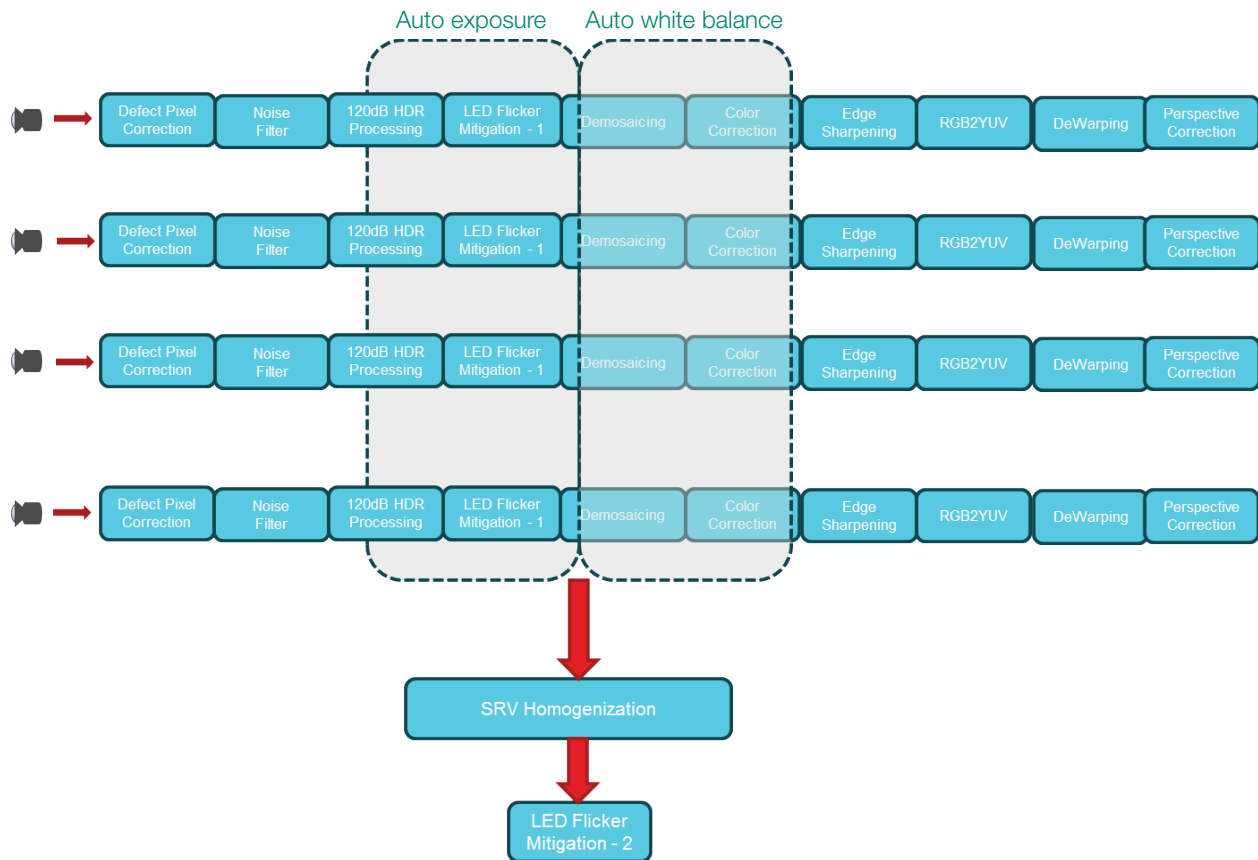
**Figure 9** on the following page shows a sample data flow of image processing on TDAx devices, which include ISP on-chip.

The ISP has all of the features needed to convert the sensor's RAW output into a computer vision format suitable for human viewing.

Hardware-accelerated blocks implement all pixel-processing functions, including:

1. Defect pixel correction
2. Spatial and temporal noise filters
3. 20-bit HDR processing with support for LED flicker mitigation
4. Demosaicing block capable of handling all major color filter array (CFA) patterns
5. Several color-correction modules to achieve high color precision
6. Gamma correction
7. Sharpness enhancement





**Figure 9.** ISP processing data flow.

8. YUV conversion with support for YUV420, NV12 and YUV422
9. Auto exposure and auto white balance
  - a. With special treatment for multi-camera scenarios where all cameras may be under different ambient conditions
10. DeWarp block which can
  - a. Correct geometric distortion for all lenses, including fish eye
  - b. Perspective correction
  - c. 3D view generation for SRV-like applications

In addition, there are generic ARM® and digital signal processing (DSP) cores in TDAx devices for control functions and sophisticated compute-intensive algorithms.

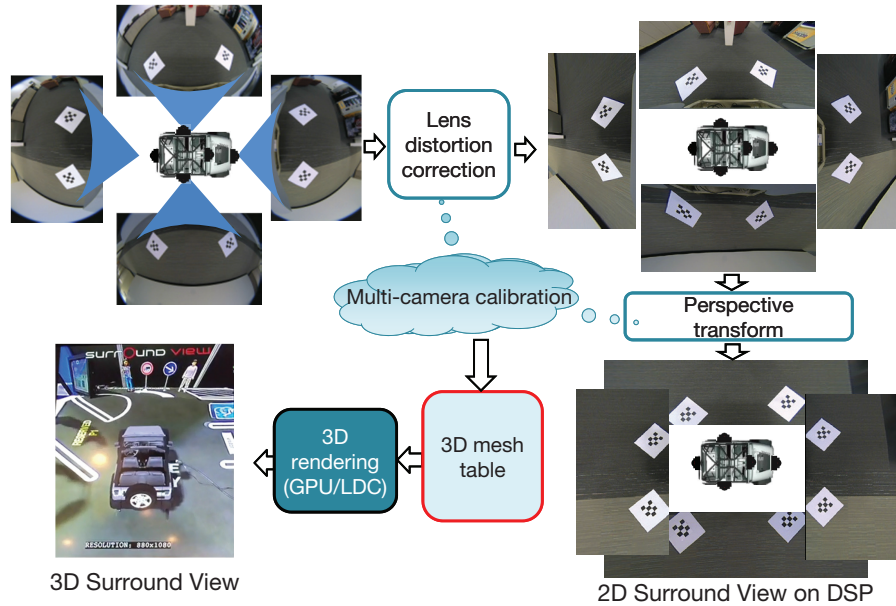
## Low-power multi-channel surround view

TI TDAx family devices are well suited for supporting multi-camera use-cases and specifically surround view. The heterogeneous architecture of TDAx devices enable you to scale across a wide variety of implementations from full-fledged GPU-based use case to very powerful and area efficient hardware accelerator (HWA)-based implementations.

**Figure 10** on the following page shows a conceptual data and algorithmic flow for surround view applications.

In this data flow the different operations map to different processing cores on the TDAx processors. For instance, for extremely low cost 2D surround view implementations, TI's DSP cores can perform perspective transform as well





**Figure 10.** Surround view processing flow.

as rendering operations. Alternatively, either the GPU or TI's proprietary mesh warp/lens distortion correction (LDC) HWA can perform the transform and rendering.

Let's discuss the implementation of GPU-less 3D surround view using the mesh warp/LDC HWA. The mesh warp hardware accelerator (HWA) is a dedicated pixel re-map engine which is part of the imaging subsystem (ISS) on several TDA3x and other TDAx devices and can be used to perform a variety of functions, from fish-eye-distortion correction, perspective transform on single images to multi-camera surround view application(s).

The mesh warp HWA works by re-mapping every pixel in the output image to a pixel in one or more input images. To achieve this it requires a remapping look-up table (LUT) which is a sub-sampled offset mesh in the memory. The mesh-based surround view supports unlimited predefined virtual view points. The PC-based tool (provided by TI) creates mesh tables and virtual car overlay images for each virtual viewpoint and stores them in memory. During the calibration stage an algorithm running

on the DSP takes the information of the viewpoints and combines them with the calculated camera calibration parameters to create the final look-up table that is used by the mesh warp HWA. The LUT in this case contains a single remap that accounts for fish-eye-distortion correction, perspective transform and backward ray tracing required for generating the virtual view.

Once the multiple perspective views are generated (one corresponding to each input camera), the DSP blends and stitches them and overlays the corresponding virtual car image to create the final output. **Figure 11** on the following page illustrates the entire data flow.

## Camera monitoring systems (CMS)

Camera monitoring system refers to cameras that are designed to replace the physical mirrors (side and rear-view) of an automobile with a combined camera, ISP and display. The advantages include better image quality, the ability to add analytics and improved ergonomics. Camera monitoring systems also introduce challenges not usually encountered

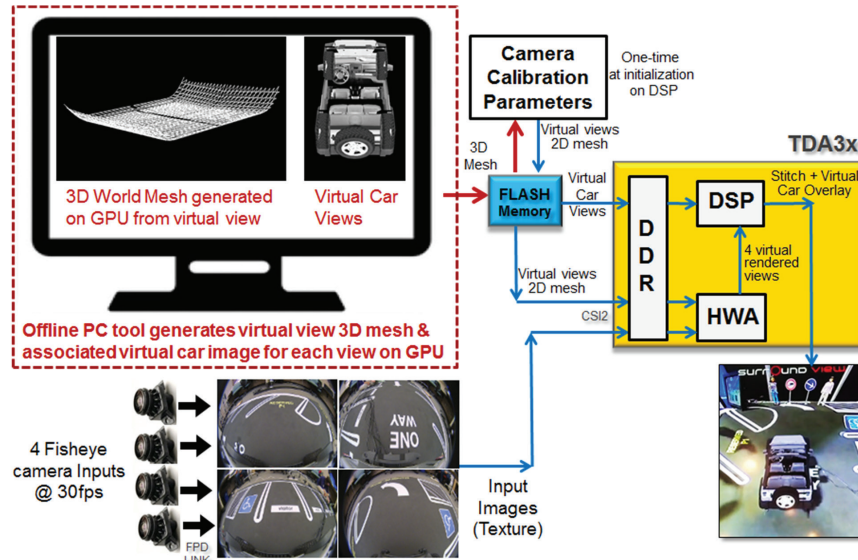


Figure 11. Surround view system flow.

in other categories of imaging applications. Let's describe some of these challenges and the solution implemented on the TI TDAx processor family.

## Typical requirements of a CMS system include:

### Higher frame rate and low light performance

International Organization for Standardization (ISO) 16505 requires 15–30 fps, but higher frame rates are recommended for a high-quality camera monitoring solution. To get better low-light performance, variable frame rate is desired depending on lighting conditions and driving speed. TDAx ISPs can process high-resolution images at very high frame rates because of a fully hardware-accelerated implementation. Variable frame rate is achieved by adding a feedback loop between the hardware 3A engine (H3A), auto exposure (AE) algorithm and sensor driver achieves a variable frame rate. The H3A generates scene statistics which are used by the AE algorithm to estimate the average brightness of the scene. The result of the AE estimation is fed back to the sensor driver to account for increased or decreased exposures and

gain. Furthermore, the result of the AE algorithm also sets sensor timing registers to adjust the frame rate allowing longer time in low light to achieve higher signal-to-noise ratio (SNR).

### Very high image quality

Image quality needs to match (or exceed) the expected response of physical mirrors and human visual system. Therefore noise must be very low, colors must be accurate and very high contrast high dynamic range (HDR) scenes must appear natural. HDR is achieved by capturing multiple frames at different exposures and merging pixel-by-pixel using a TI proprietary algorithm designed specifically for CMS. Figure 12 illustrates how an HDR scene is constructed.



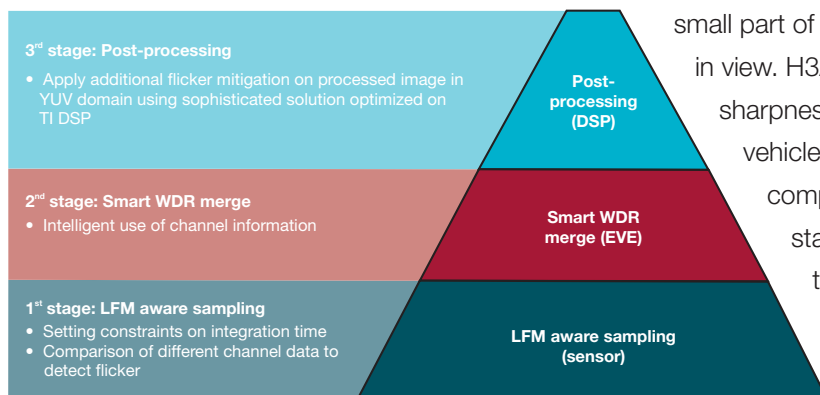
Figure 12. HDR scene construction.

## LED flicker mitigation

LEDs have revolutionized the lighting industry including automotive headlights and road signs. While this is a welcome development, it poses a challenge for CMOS camera sensors. LED illumination is based on PWM, where light is emitted only during the ON cycle. CMOS sensors use a rolling shutter mechanism and are not able to capture the LED signal entirely in every consecutive frame. This leads to a flicker effect where the LEDs are seen as OFF in some frames and ON in others. This problem is compounded by wide dynamic range imaging since the rolling shutter window is set to a very small time to capture highlights in the scene. TI's TDAx CMS solution addresses this challenge with a three-tiered approach. **Figure 13** illustrates the three-step approach mitigating LED flickering.

## Aspherical mirror effect

Some countries allow mirrors to be aspherical such that they are primarily flat except the outer edges which are curved to provide a wider field-of-view (FOV) to reduce blind spots. Camera monitoring systems must be able to provide the same effect. The TDAx ISP has a HWA for lens distortion correction (LDC) which is used to achieve this effect. A LUT for LDC mapping is defined in a way that the flat part of the image is mapped 1-to-1 but the curvature is introduced in the outer edges.



**Figure 13.** Three-tiered LED flicker mitigation scheme.

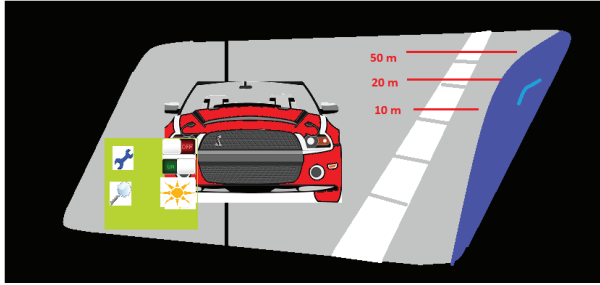
## Obstruction detection

Cameras, particularly those mounted outside the vehicle, are prone to obstructions such as dirt, fog, water, etc. This poses an unsafe condition for drivers if not detected. TDAx devices feature a learning-based algorithm which uses sharpness statistics from the H3A engine to detect if there is any obstruction. The H3A provides a block-by-block sharpness score thus providing fine-level statistics to the algorithm. **Figure 14** shows an example of lens obstruction detection.



**Figure 14.** Example of lens obstruction detection.

The algorithm is smart enough to differentiate that the sharpness is low because of flatness in the scene or because of an actual obstruction. The algorithm does this by harnessing the fact that a small part of the vehicle's body frame is always in view. H3A windows are defined such that sharpness and color information from the vehicle's body are easily identifiable and comparable against a golden set of statistics. When there is a mismatch, the algorithm concludes that an obstruction is in view and triggers the driver to take action to clean the camera lens.



**Figure 15.** Example of HMI overlay on video frame.

Camera monitoring systems require human machine interface (HMI) to control the mirror position, zoom level, etc. The display includes additional information like distance lines and turn signal. **Figure 15** shows HMI symbols overlaid on each video frame.

Generation graphics layers can be done using GPU, DSP or can be done in other available on-chip processing cores. The Display Controller in the TDAx Display SubSystem is used for real-time overlay of graphics layers with ISP video out.

## Conclusion

Self-driving cars will demand a high number of sensor technologies in order to completely map its environment. Sensor technologies such as vision, RADAR and LIDAR will play a significant role. Sensors mounted around the car will need

compact, low-cost cabling to connect satellite sensors to a central fusion processing unit. FPD-Link III solutions fulfill the demands of future sensor fusion systems as functionality is going to extend from generation to generation.

Highly integrated processors, such as the TDAx family, provide multiple benefits. Using one ISP for multiple cameras achieves significant cost reduction. Single ISP blocks result in better photometric alignment since one centralized processing unit controls all cameras. In addition, it ensures that similar color gains and noise filters are running on all cameras at the same time, making the stitched view look more natural. For instance, the DeWarp block is a lot smaller than a comparable GPU and allows the TDAx device, and system, to be in a smaller package with lower power consumption.

Texas Instruments provides all required key components to design multi-sensor applications for the automotive market.

### For more information

For additional information please visit:

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