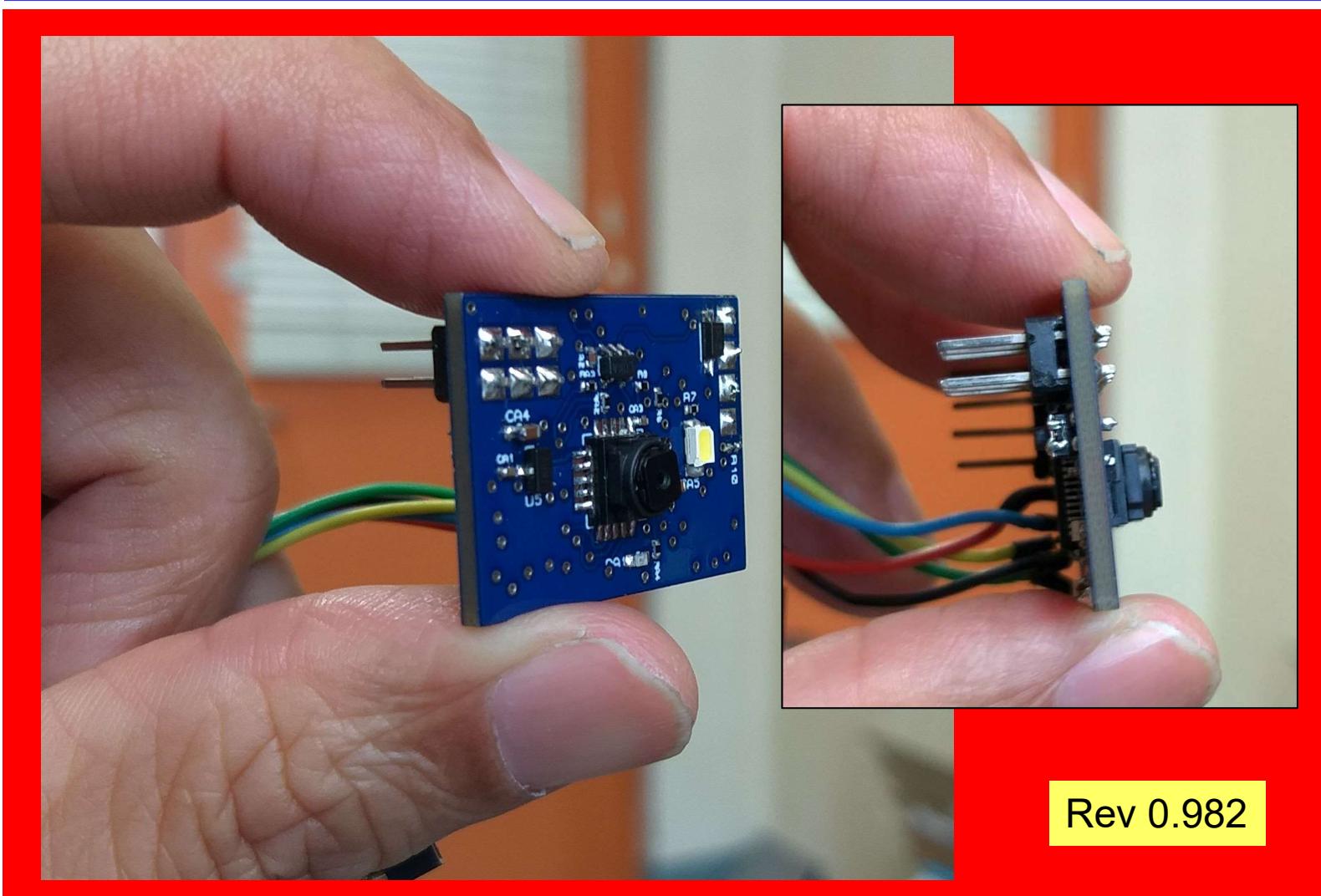


MVM V1.5C Quick Start Guide



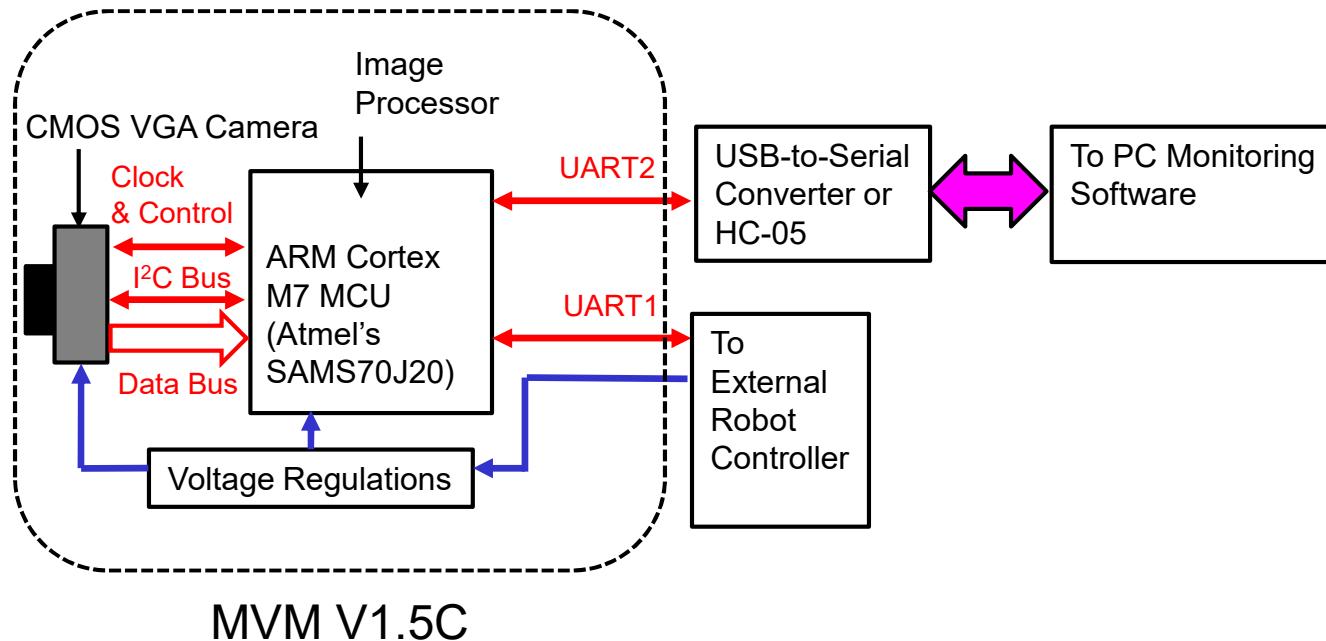
Rev 0.982

What Is It?

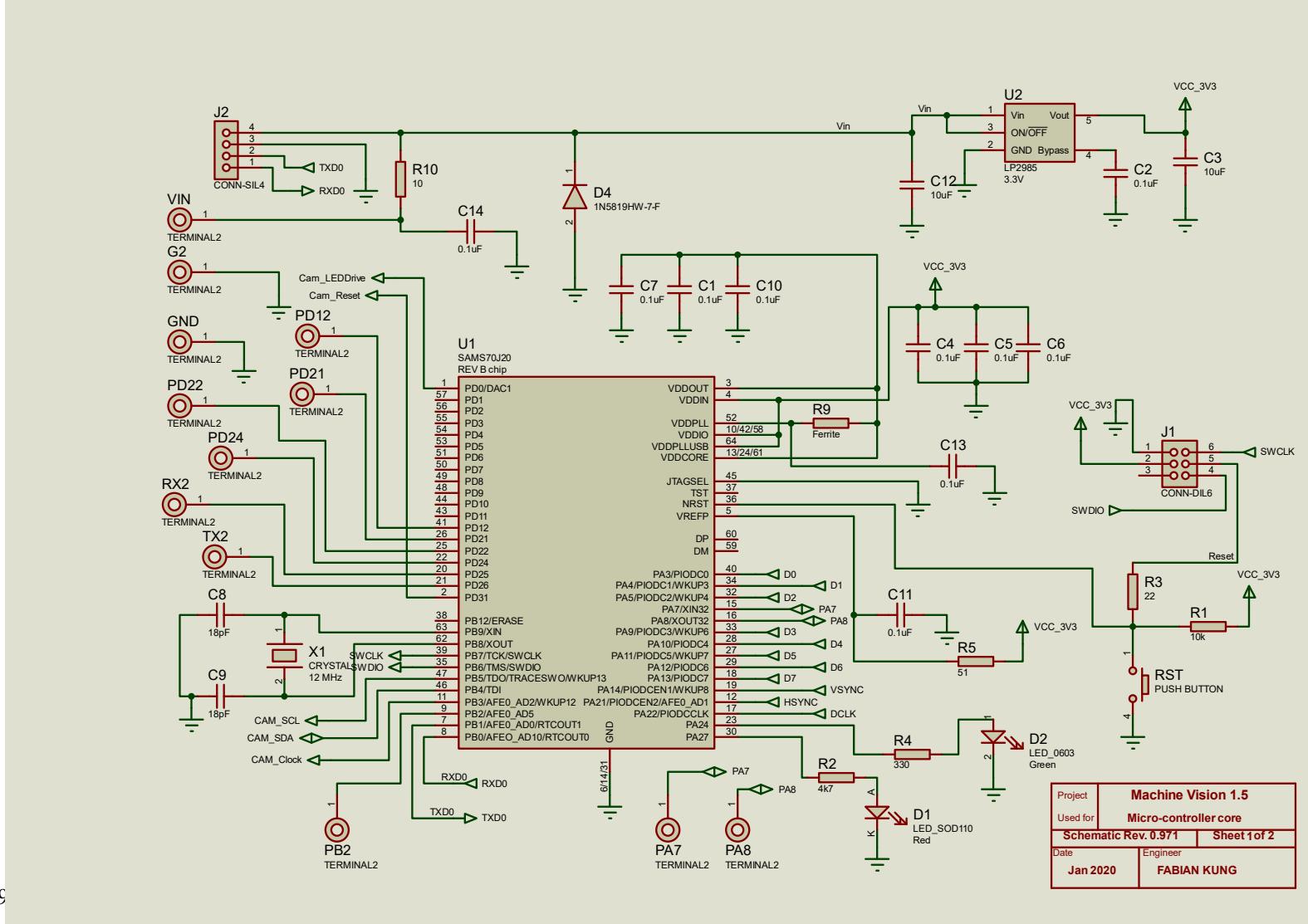
- An open source, easy to use low resolution CMOS camera with on-board real-time image processing.
- Requires 5V, 150 mA power source, and interface through UART port.
- Support 160x120 pixels (QQVGA) and 320x240 pixels (QVGA) color image at 20 frames-per-second.
- Current image processing algorithm:
 - Edge detection via Sobel kernel.
 - Bright spot detection.
 - Obstacle detection using luminance contrast.
 - Color detection.
 - Convolutional Neural-Network.
- Work-in-progress:
 - Line following.
 - Optical flow.

Block Diagram

WARNING: Because the processor runs on 3.3V, UART1 and UART2 works at 3.3V logic level. Applying higher voltage (for example 5V) to the terminals may damage the processor

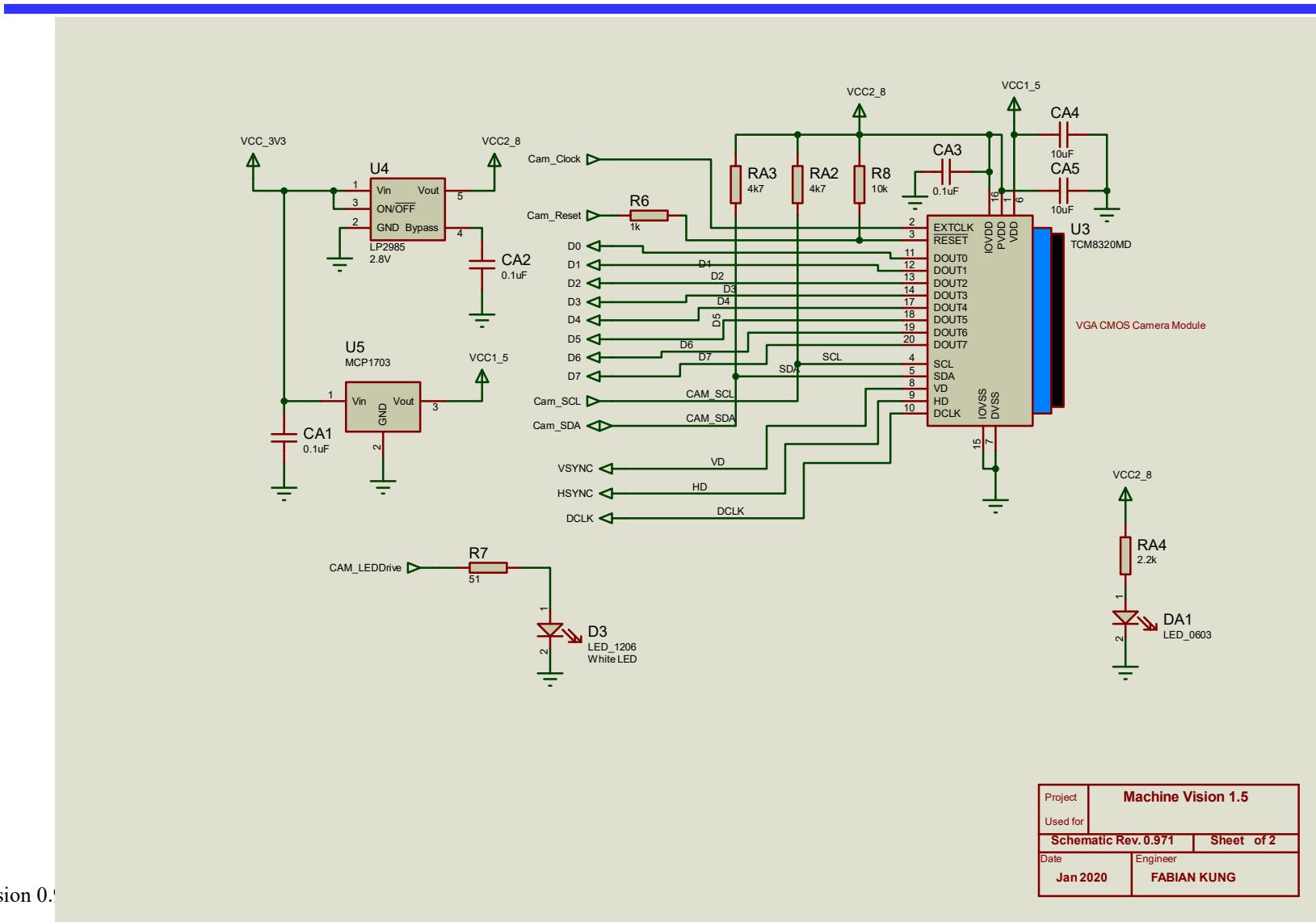


Schematic 1 – Micro-controller Core



Version 0.9

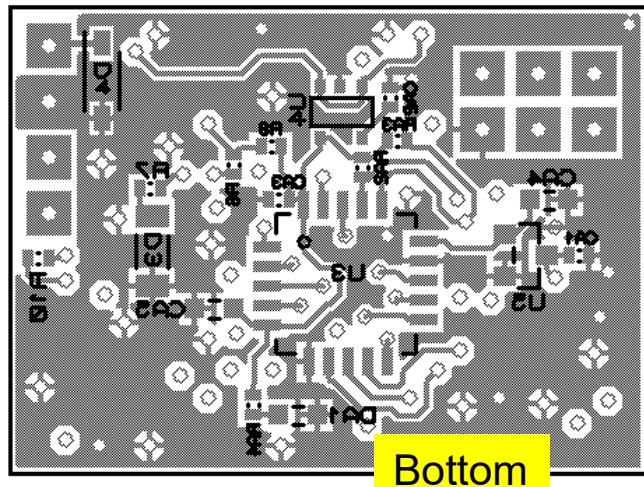
Schematic 2 – Camera Sub-Circuit



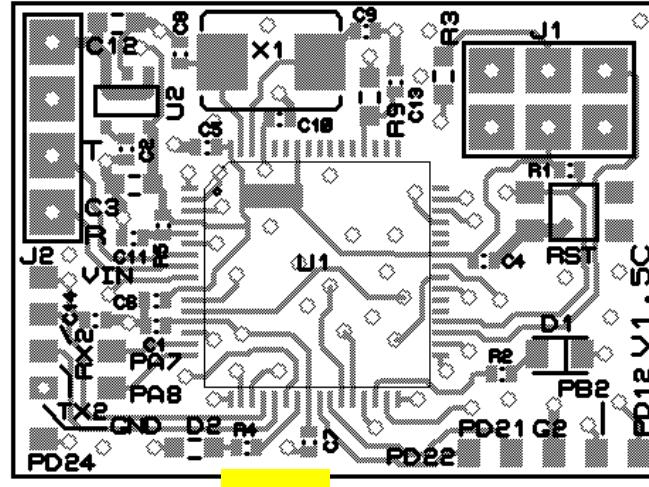
Version 0.9

Project	Machine Vision 1.5	
Used for		
Schematic Rev. 0.971	Sheet of 2	
Date	Engineer	
Jan 2020	FABIAN KUNG	

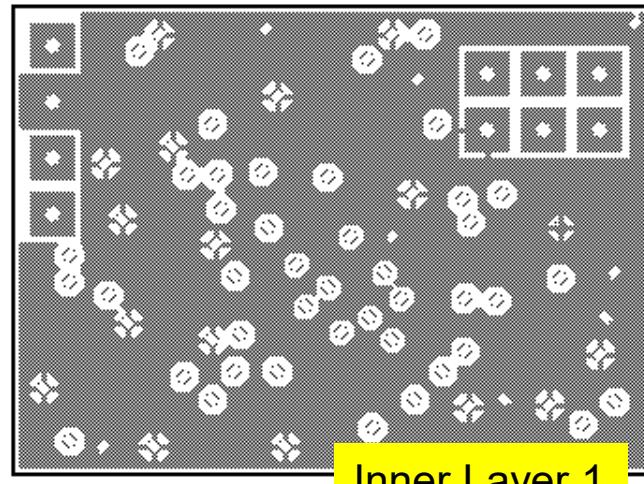
PCB Layers



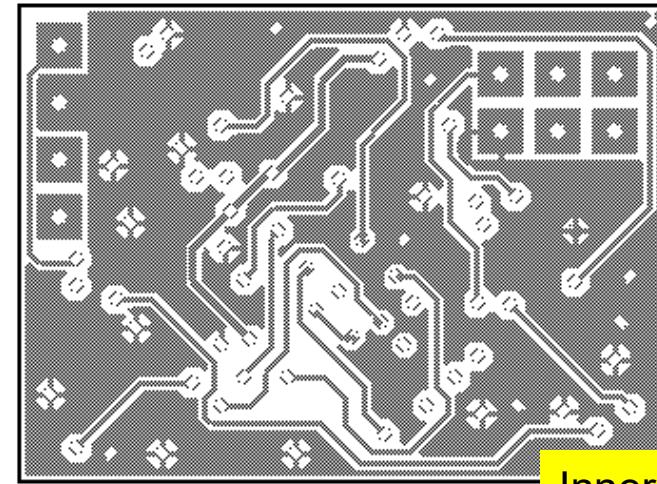
Bottom



Top

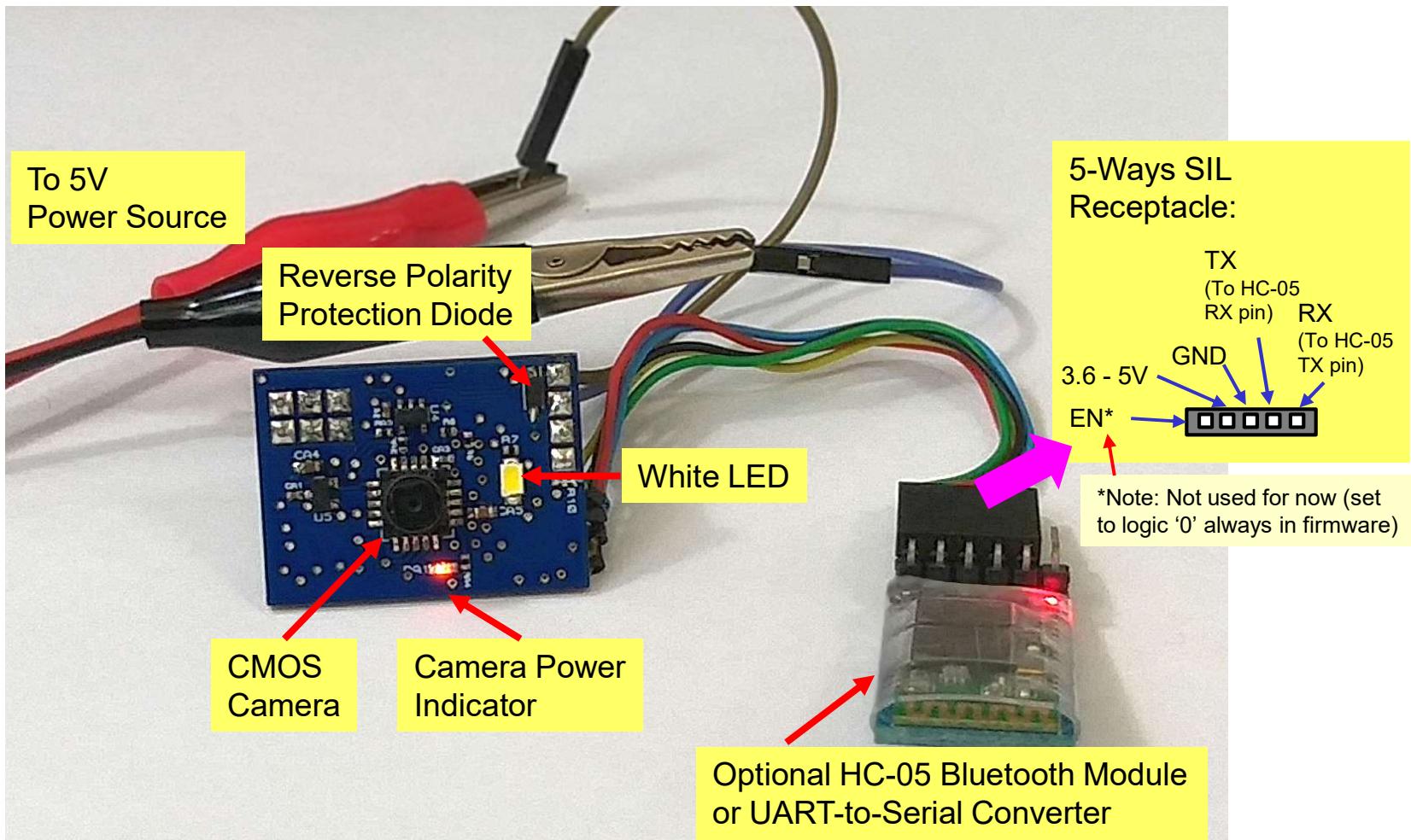


Inner Layer 1

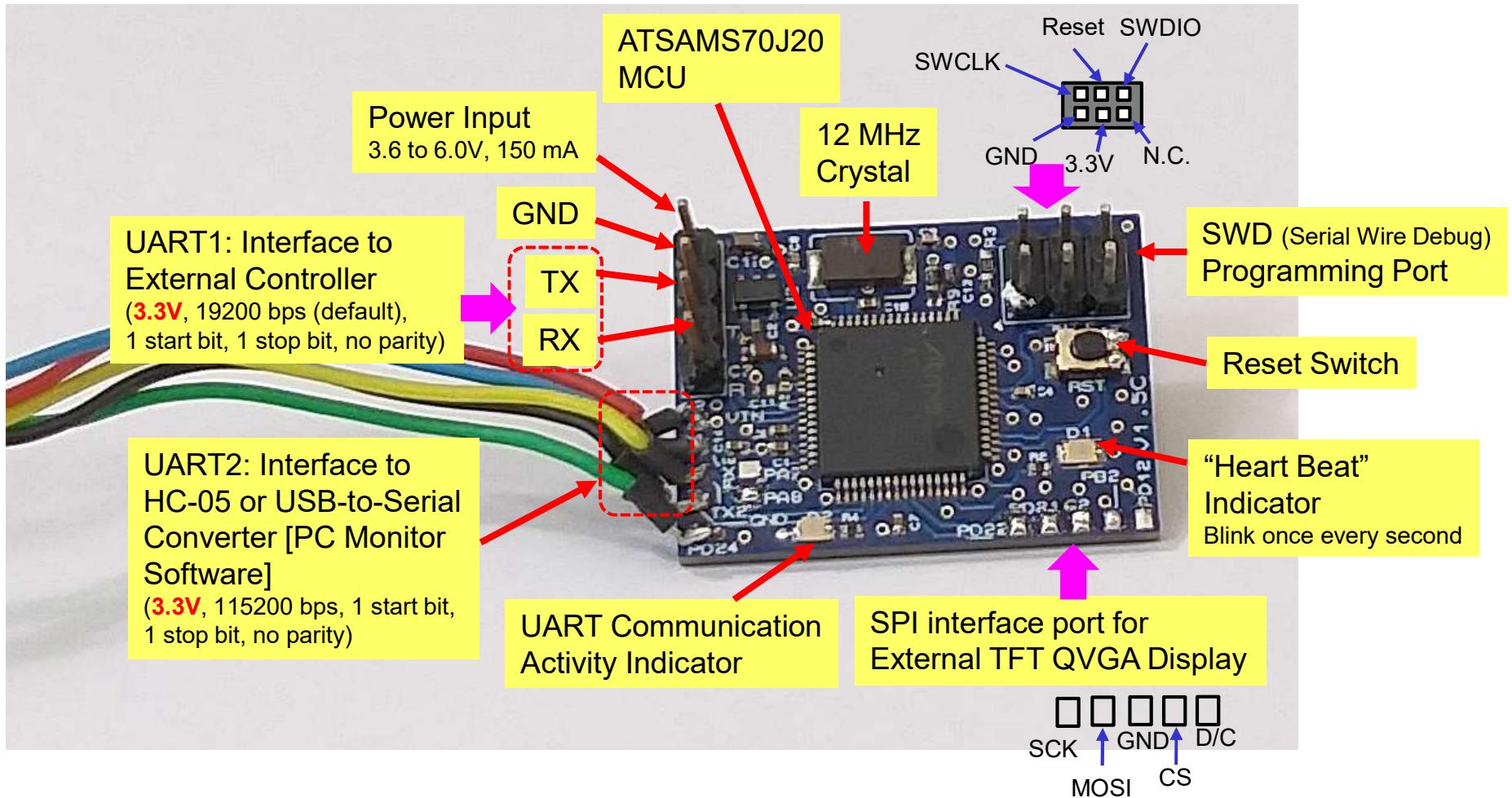


Inner Layer 2

Rear View (MVM V1.5C)



Front View (MVM V1.5C)



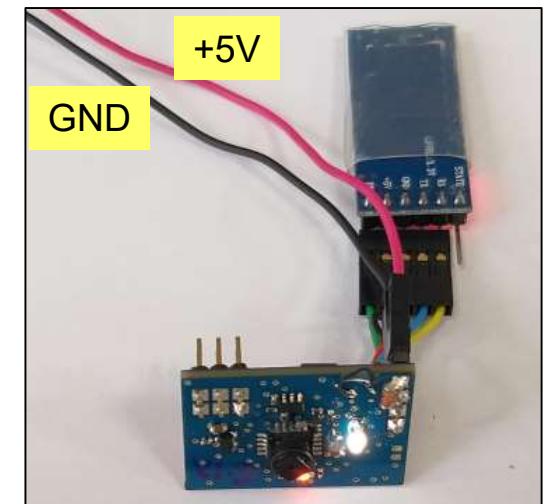
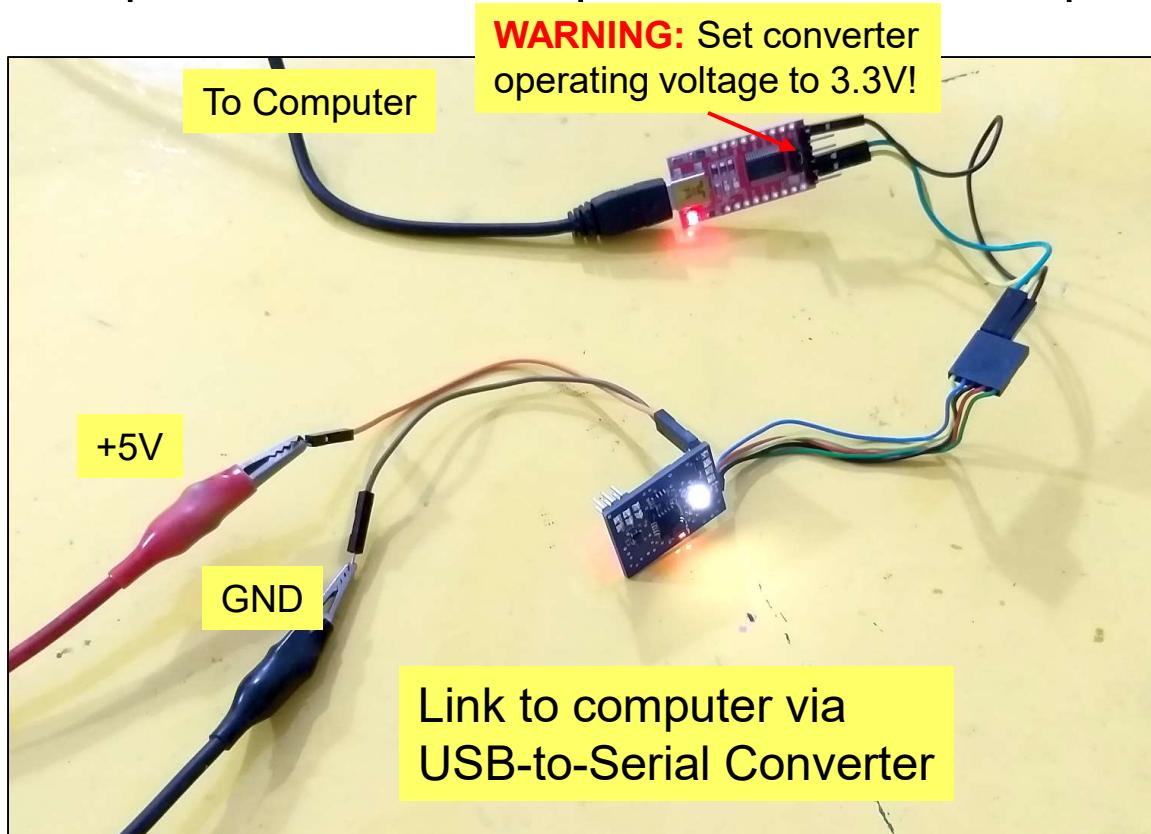
Files

- All relevant files can be obtained from
https://github.com/fabiankung/MVM_V1_5C
- Firmware is build using **Atmel Studio 7**.
- PC software is build using **Visual Studio Community 2017** or later.

Observing the Camera Image via Machine Vision Monitor Software

Step 1 – Power Up the MVM

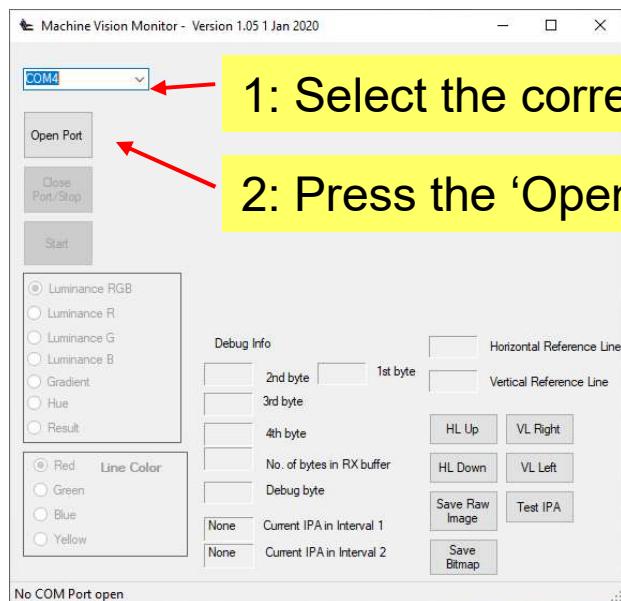
- Here we assume the MVM is connected to HC-05 Bluetooth wireless module or a USB-to-Serial Converter, as shown in the various implementation examples below. Power up the module.



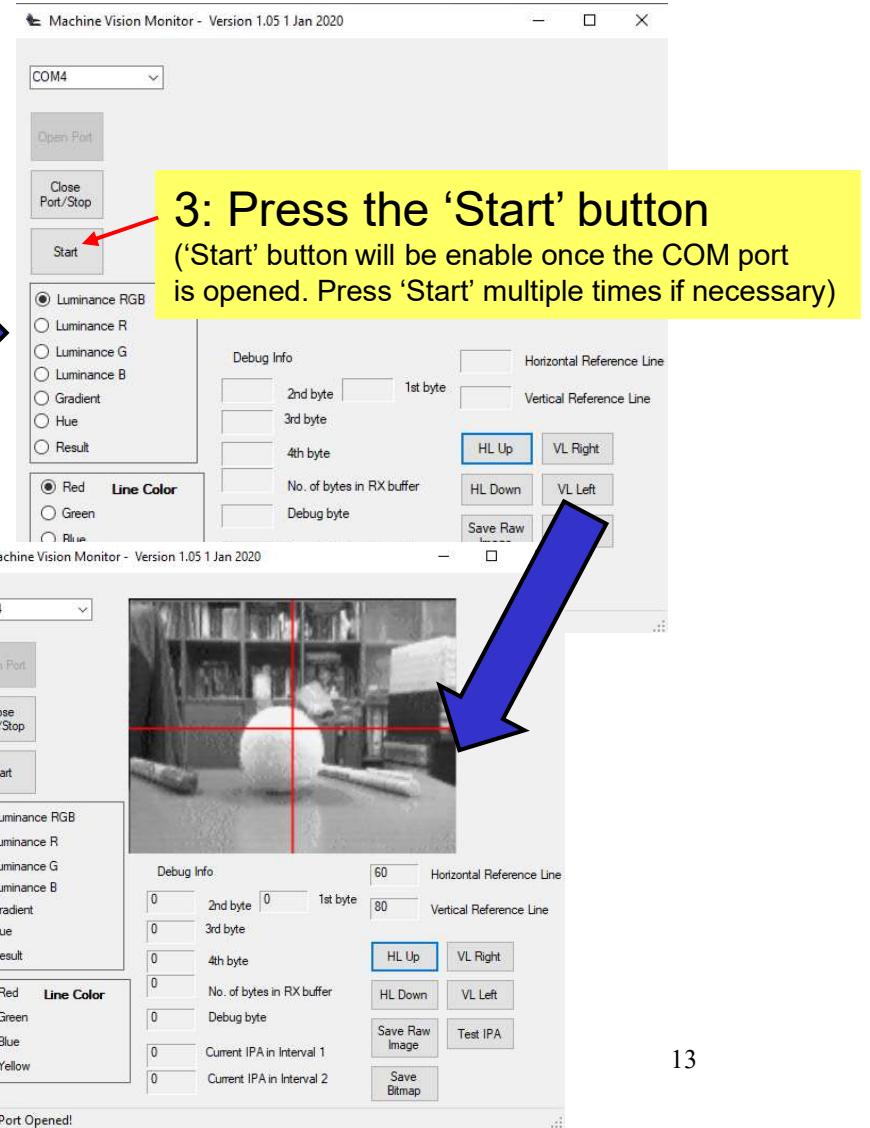
Step 2 – Pair Computer to HC-05

- If need to, pair the computer to HC-05 first.
- Then check virtual COM port number on the computer (for instance by going to the Device Manager in Windows).

Step 3 – Run the Machine Vision PC Monitor Software (MV_Monitor.exe)



- 1: Select the correct COM port
- 2: Press the 'Open Port' button



- 3: Press the 'Start' button
('Start' button will be enable once the COM port is opened. Press 'Start' multiple times if necessary)

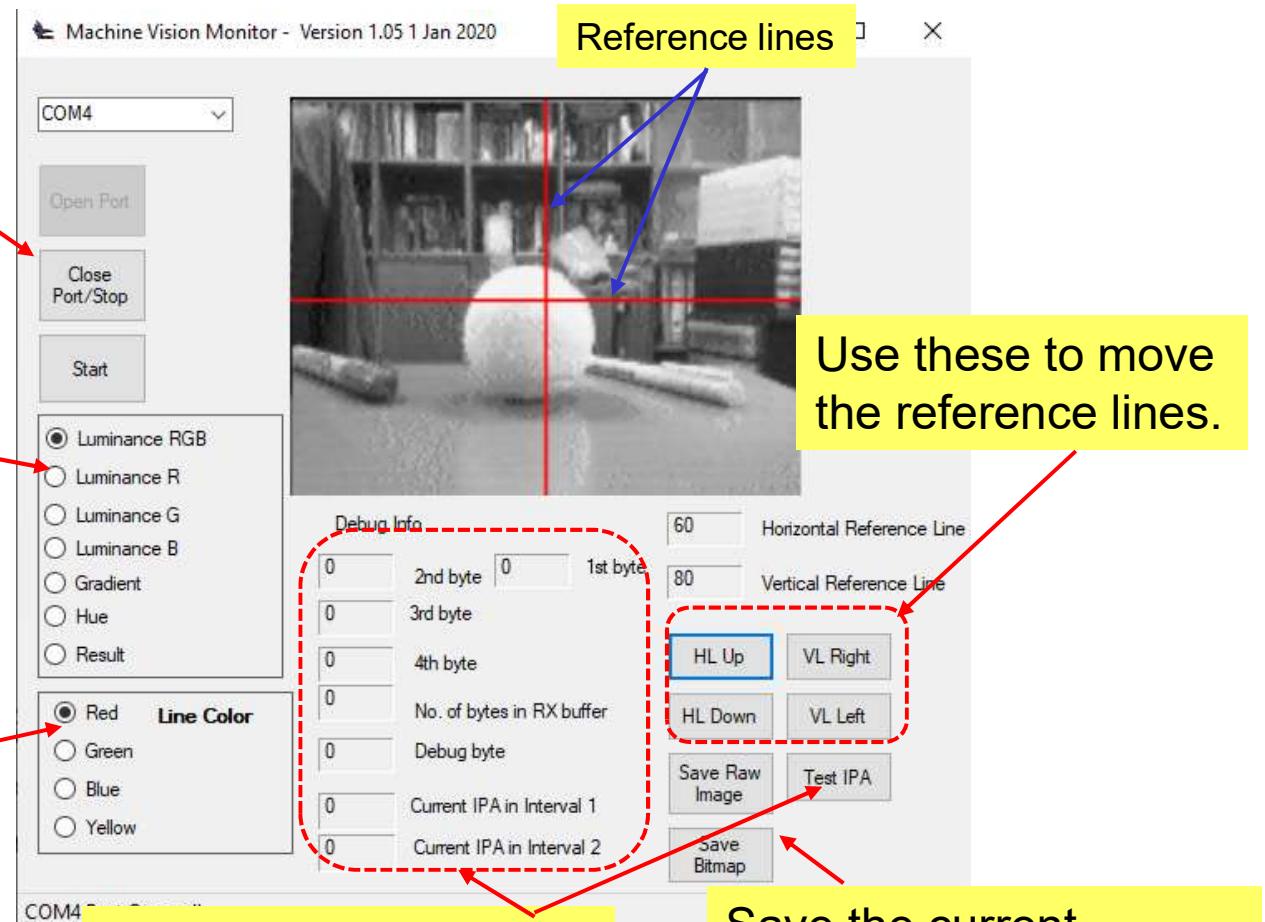
- 4: Now the MVM will transmit the image data line-by-line to the PC monitor software

Other Information [1 of 2]

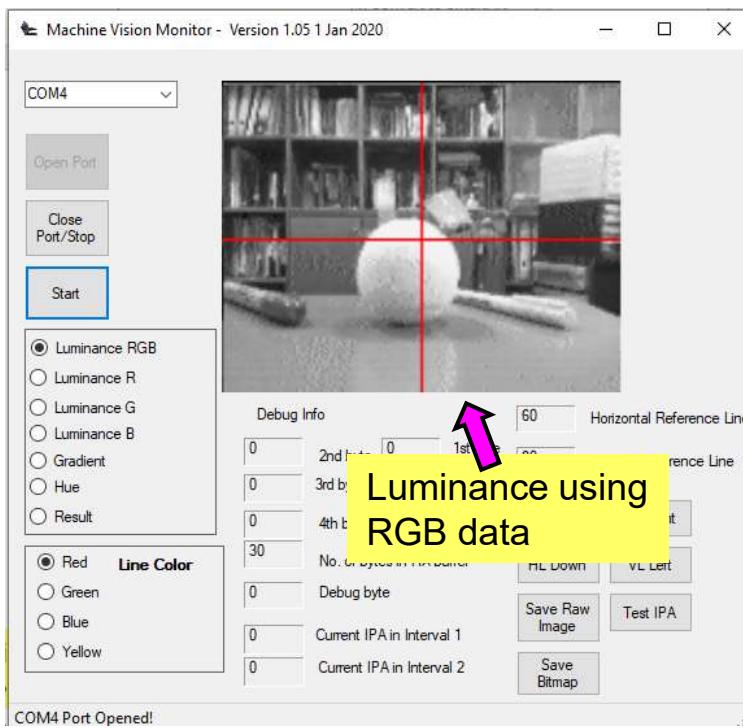
Always close the COM port before shutting down the software

Select between various display options. All these are processed in the MVM. (See next slide)

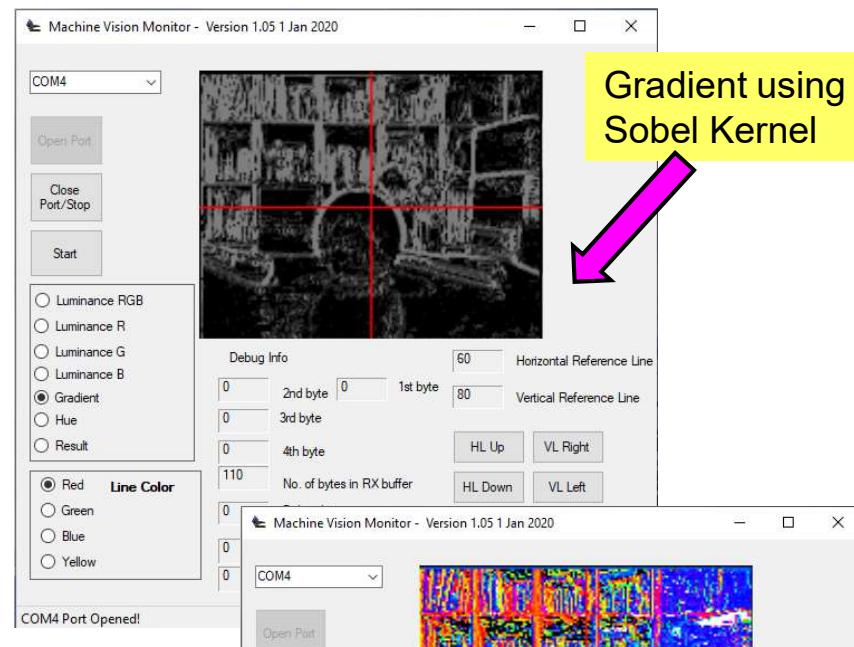
Change reference line color.



Other Information [2 of 2]

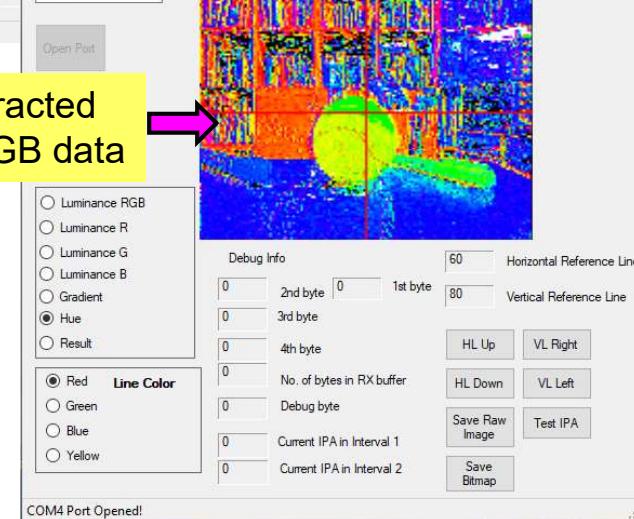


Luminance using
RGB data



Gradient using
Sobel Kernel

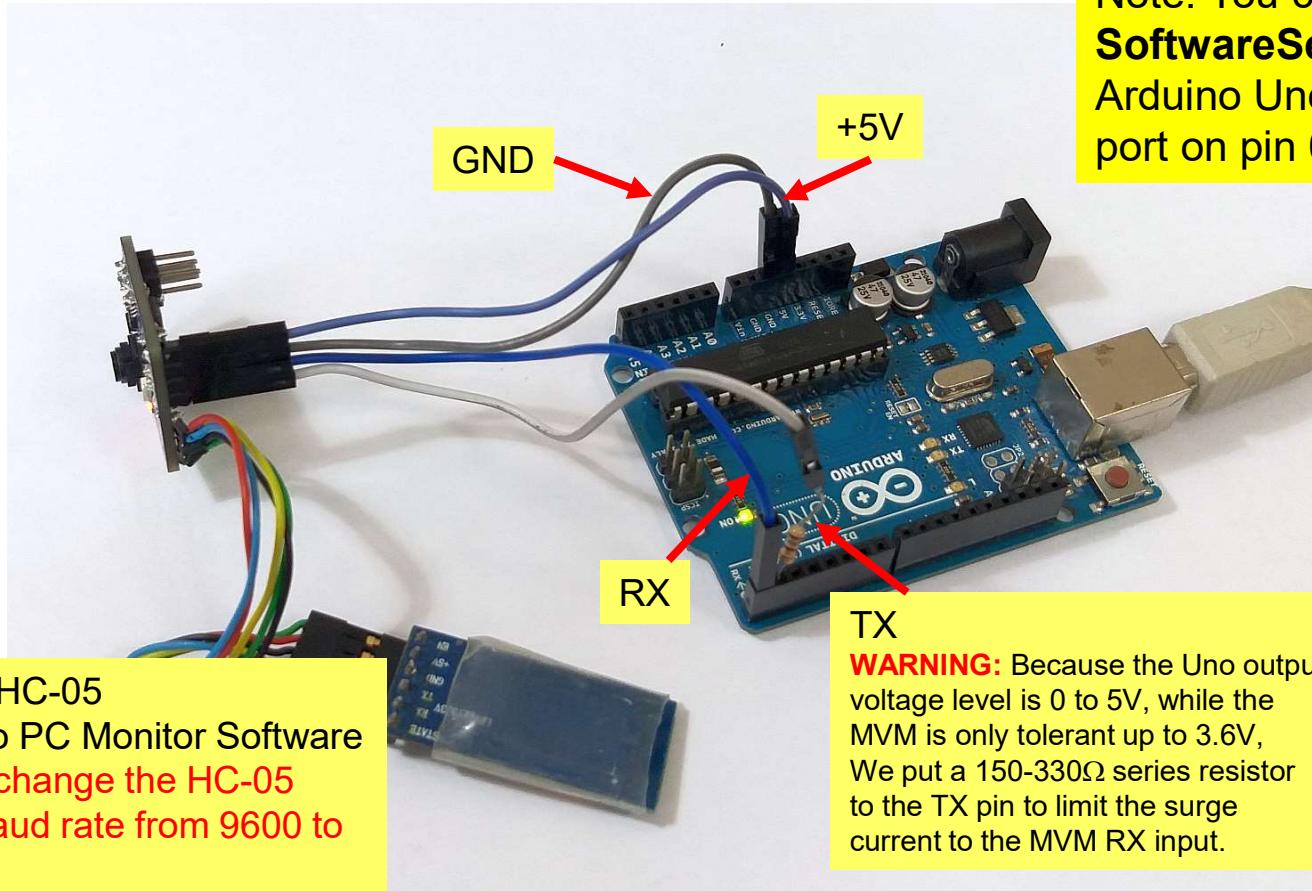
Hue extracted
From RGB data



Connection to External Controller for Robotic Projects

Connection to External Controllers

- Here we use an Arduino Uno to demonstrate the connection.



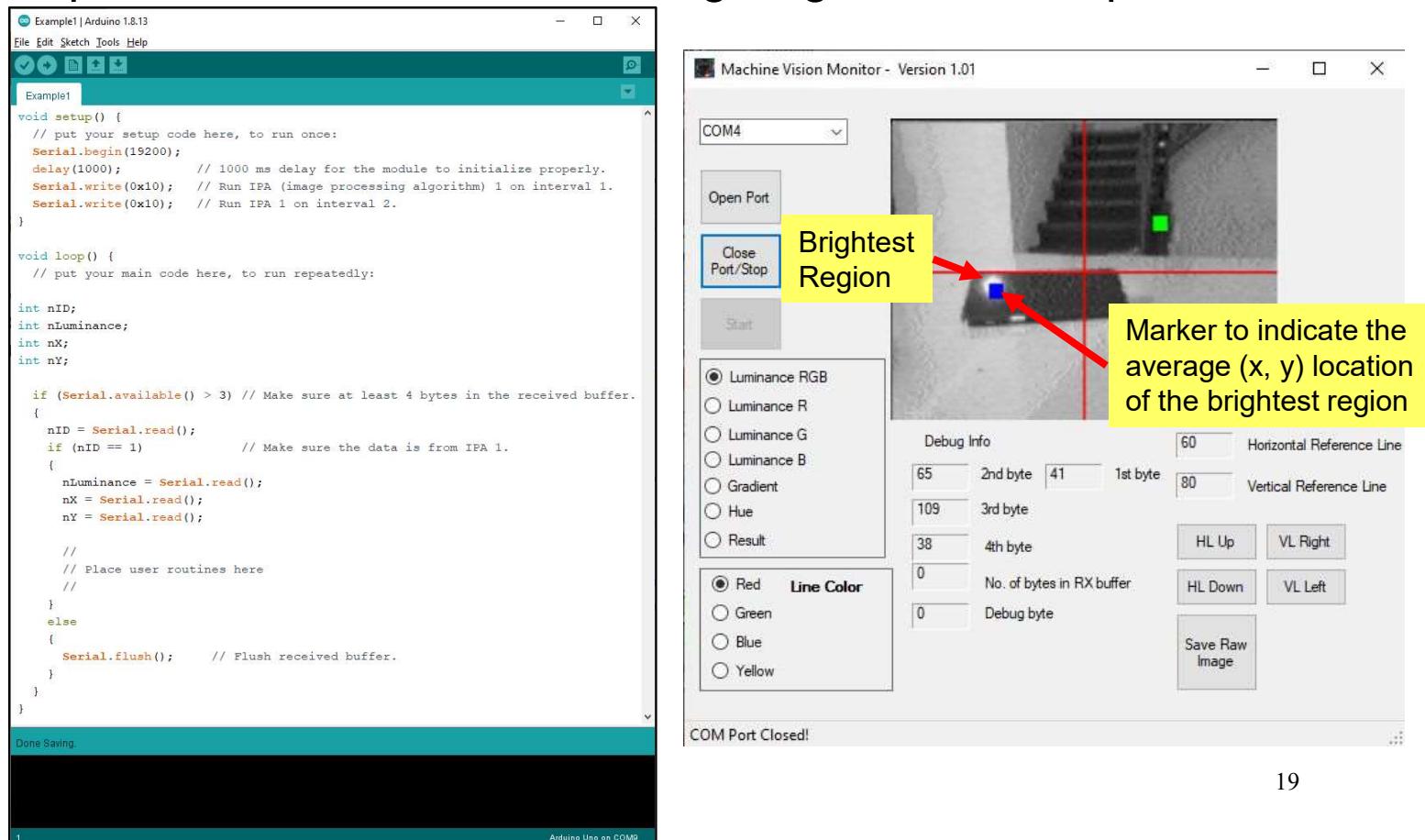
UART1 Communication Protocol

Image Processing Algorithm (IPA)	To Activate	MVM Output
Search for brightest spot in a scene. Image resolution = 160x120	Send hex values to MVM: 0x10 to search for brightest spot	4 bytes: Byte 1 = 1 (Algorithm ID) Byte 2 = Maximum luminance value (1 to 127). Byte 3 = x coordinate of region Byte 4 = y coordinate of region
Obstacle detection on lower half of the image. Image resolution = 160x120	Send hex value to MVM: 0x20	4 bytes: Byte 1 = 2 Byte 2 = 0b00000b ₂ b ₁ b ₀ Byte 3 = 0b00000b ₂ b ₁ b ₀ Byte 4 = 0b00000b ₂ b ₁ b ₀
Color object detection. Image resolution = 160x120	Send hex values to MVM: 0x30 for yellow-green object 0x31 for red object 0x32 for green object 0x33 for blue object	4 bytes: Byte 1 = 3 Byte 2 = Number of pixels matched Byte 3 = x coordinate of region Byte 4 = y coordinate of region

Example 1 – Activate Search for Brightest Spot Algorithm

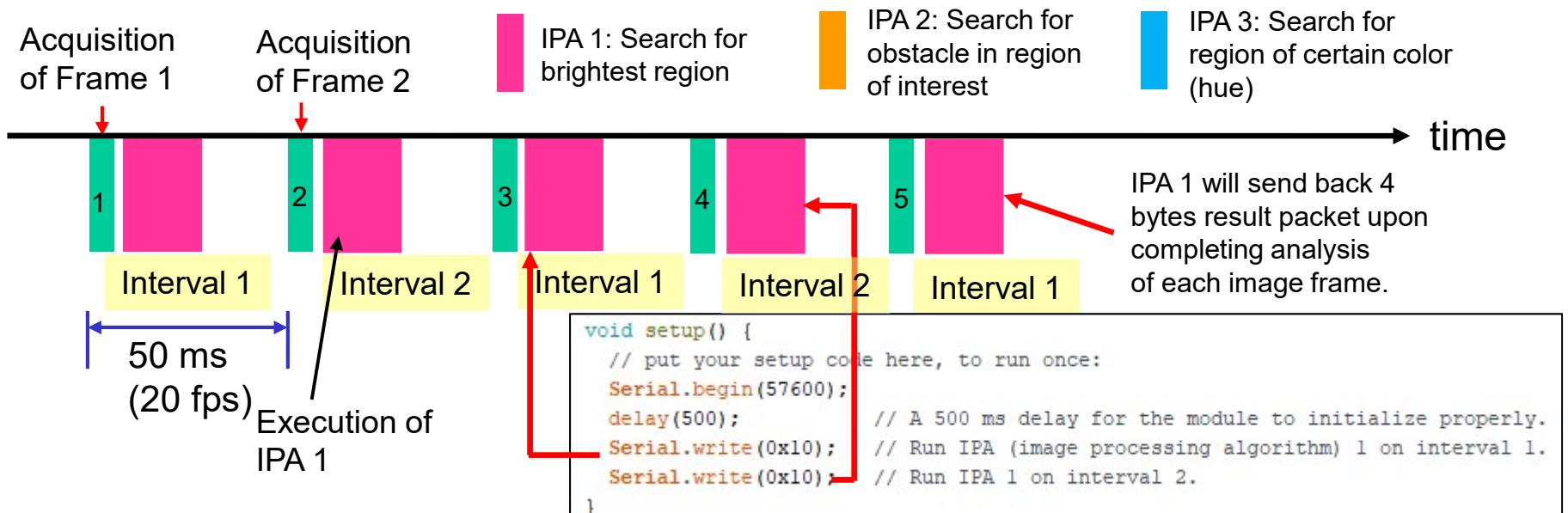
- Assume the MVM is connected to an Arduino Uno. The left panel shows a simple Arduino Sketch to activate the image processing algorithm to search for brightest spot on both **Interval 1** and **2**, giving effective response time of 50 ms.

Note:
See Appendix for
Another version
of this code using
SoftwareSerial



Example 1 - More on 'Interval'

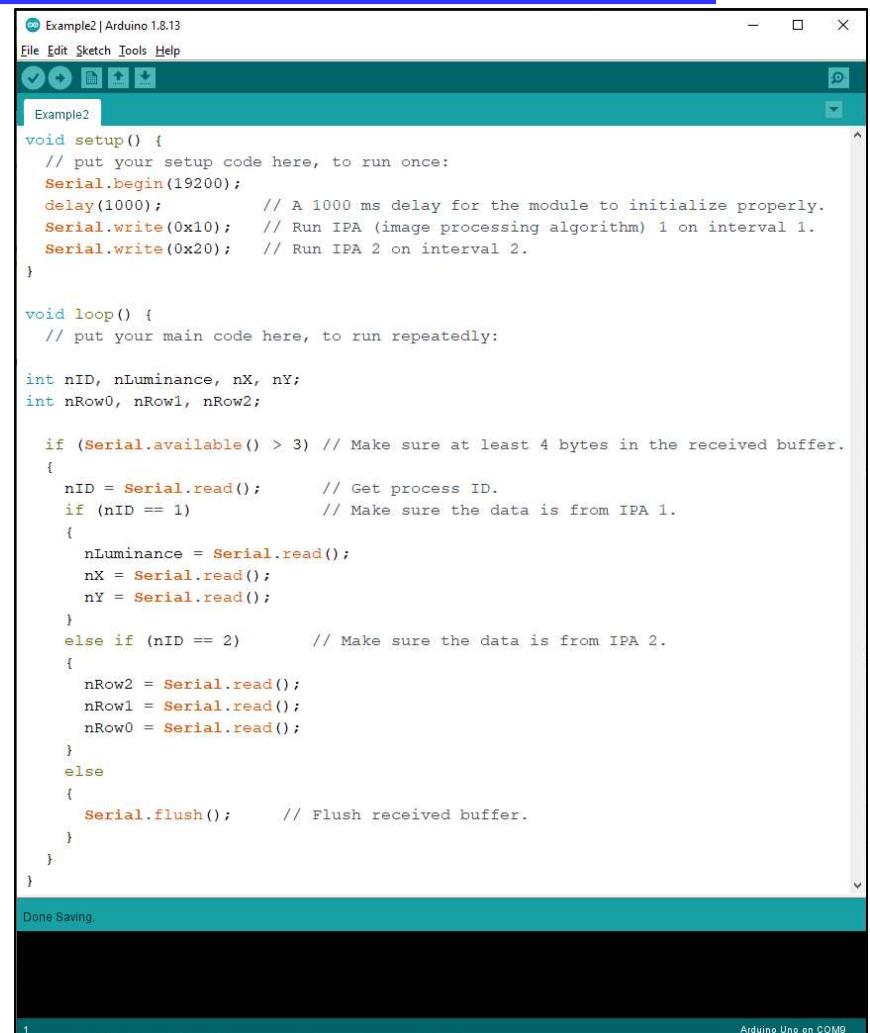
- The firmware of MVM V1.5C assigns odd image frames to *Interval 1* and even image frames to *Interval 2*.
- An image processing algorithm (IPA) can be attached to each interval as shown below and executed after acquisition of a new image frame.



- The C code snippet attaches IPA 1 to both Interval 1 and Interval 2 of the execution flow, thus in this setting IPA 1 runs every 50 ms and any changes in scene is detected within 50 ms.

Example 2 - Activate Both Search for Brightest Region (IPA 1) and Obstacle (IPA 2) Algorithms

- In this example we attach IPA 1 to Interval 1 and IPA 2 to Interval 2.
- Thus a robot using the MVM V1.5C can be programmed to move towards a bright light source while at the same time avoid any obstacle on the floor.



The screenshot shows the Arduino IDE interface with the sketch named "Example2". The code implements two parallel search algorithms using the Image Processing Algorithm (IPA) module. It initializes the serial connection, runs IPA 1 on interval 1 and IPA 2 on interval 2, and then processes data from both IPA modules via the serial port. The code includes comments explaining the setup and loop logic.

```
void setup() {
    // put your setup code here, to run once:
    Serial.begin(19200);
    delay(1000);           // A 1000 ms delay for the module to initialize properly.
    Serial.write(0x10);    // Run IPA (image processing algorithm) 1 on interval 1.
    Serial.write(0x20);    // Run IPA 2 on interval 2.
}

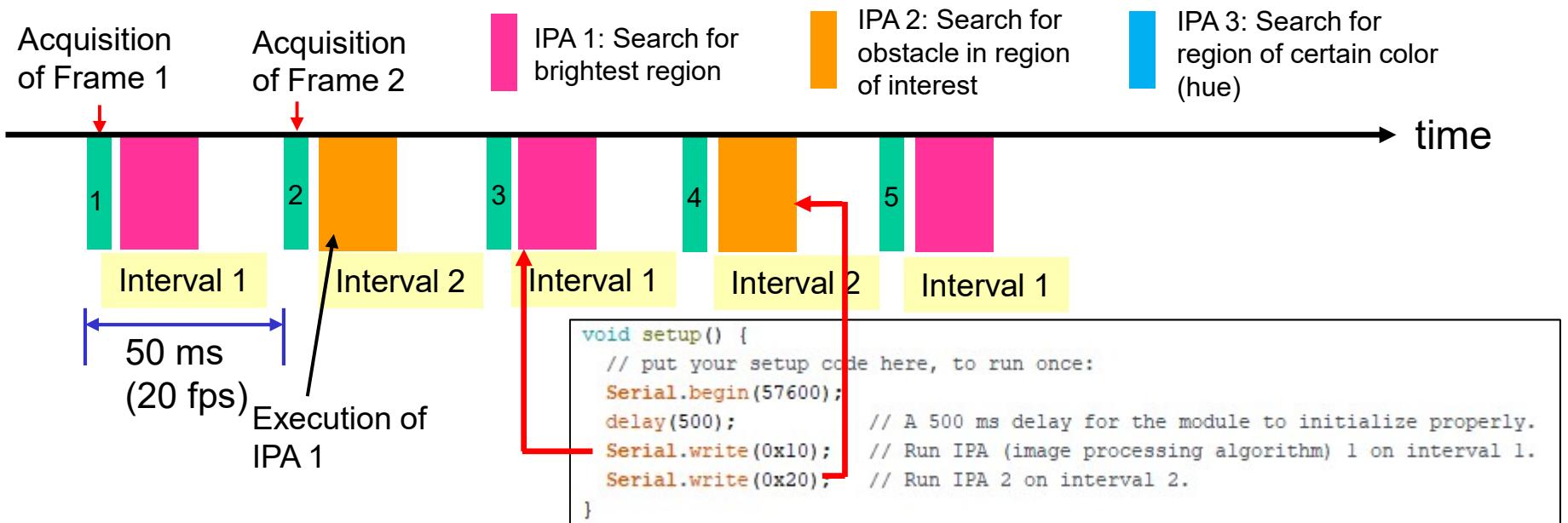
void loop() {
    // put your main code here, to run repeatedly:

    int nID, nLuminance, nX, nY;
    int nRow0, nRow1, nRow2;

    if (Serial.available() > 3) // Make sure at least 4 bytes in the received buffer.
    {
        nID = Serial.read();      // Get process ID.
        if (nID == 1)            // Make sure the data is from IPA 1.
        {
            nLuminance = Serial.read();
            nX = Serial.read();
            nY = Serial.read();
        }
        else if (nID == 2)        // Make sure the data is from IPA 2.
        {
            nRow2 = Serial.read();
            nRow1 = Serial.read();
            nRow0 = Serial.read();
        }
        else
        {
            Serial.flush();      // Flush received buffer.
        }
    }
}

Done Saving.
```

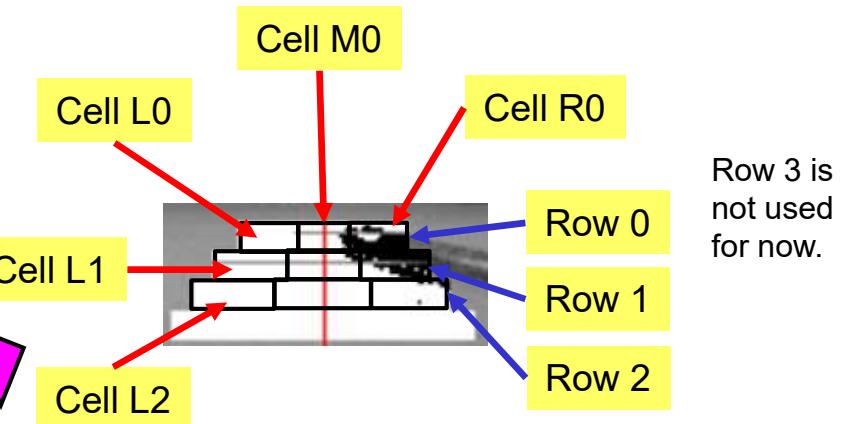
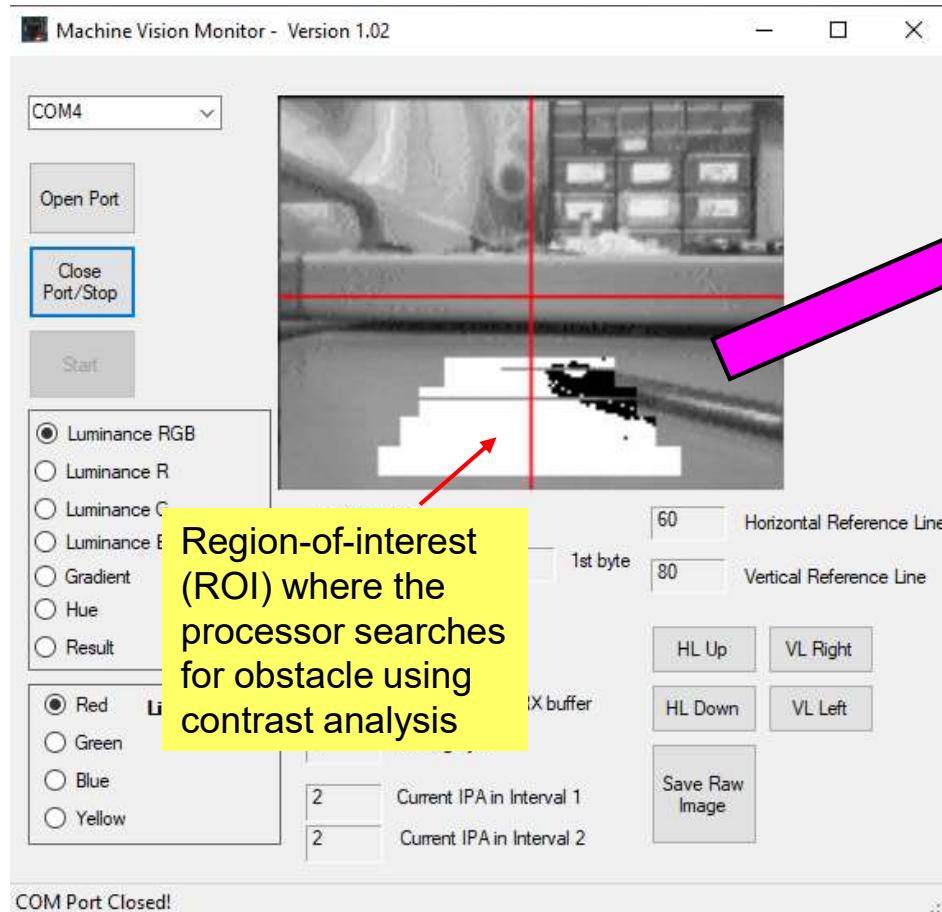
Example 2 – The Assignment of IPAs to Intervals



- Each IPA only executes every 100 ms, thus the response time now slows down to 100 ms, however the up side is we get to run two different algorithms simultaneously.

Interpreting the Results of IPA 2

- When IPA 2 is activated:



Whenever the number of black pixels exceed a pre-determined threshold in a cell, an obstacle is deemed present. Thus, for this example, cells R0, M0 and R1 contains obstacle and the bits corresponding to these cells will be set to '1'. The following result packet will be transmitted via UART 1 from MVM V1.5C:

Byte 1 = 2 ID

Byte 2 = 0b00000000 Row 2

Byte 3 = 0b00000001 Row 1

Byte 4 = 0b00000011 Row 0

L M R

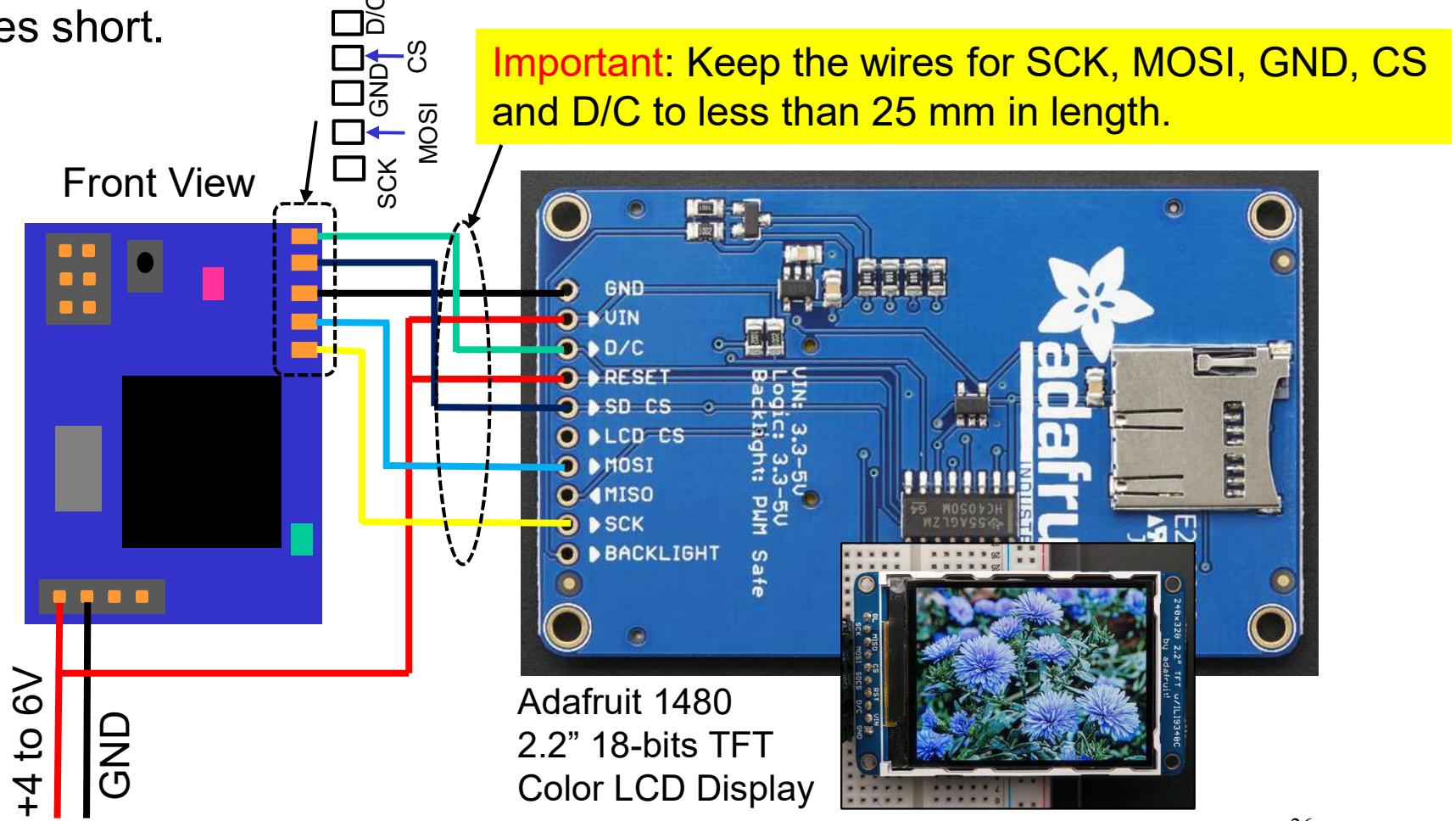
Connection to TFT LCD Display

Support for TFT LCD Display

- Presently only ILI9341 TFT LCD controller in 4-wires serial communication mode is supported. The ILI9341 TFT LCD controller support a resolution of 320x240 pixels (i.e. QVGA).
- So LCD display using this controller can be connected to the MVM V1.5C.
- Examples of compatible TFT Displays are products from Adafruit such as product ID 2478, 1770, 1743 and 1480.
- Due to limitation on the micro-controller bandwidth, the firmware can only support either streaming of image to PC (via serial port) or streaming of image to LCD, not both. As default the firmware pre-programmed into the micro-controller is the former. Thus if it is desire to interface the MVM V1.5C streaming output to TFT LCD display, another version of the firmware needs to be compiled and loaded into the micro-controller. See next section “Compiling and building your own firmware for MVM V1.5C”.

Connection Diagram

- As the SPI serial signals runs at 75 MHz, it is important to keep the wires short.



Compiling and Building Your Own Firmware for MVM V1.5C

Introduction 1

- The source codes for the sample firmware is a simplified version of the application pre-loaded into the MVM V1.5C micro-controller.
- The codes for IPA 1 is provided with the sample firmware and if the micro-controller is programmed with the sample firmware hex output, the micro-controller will run IPA 1 continuously at 20 fps upon power up.

Introduction 2

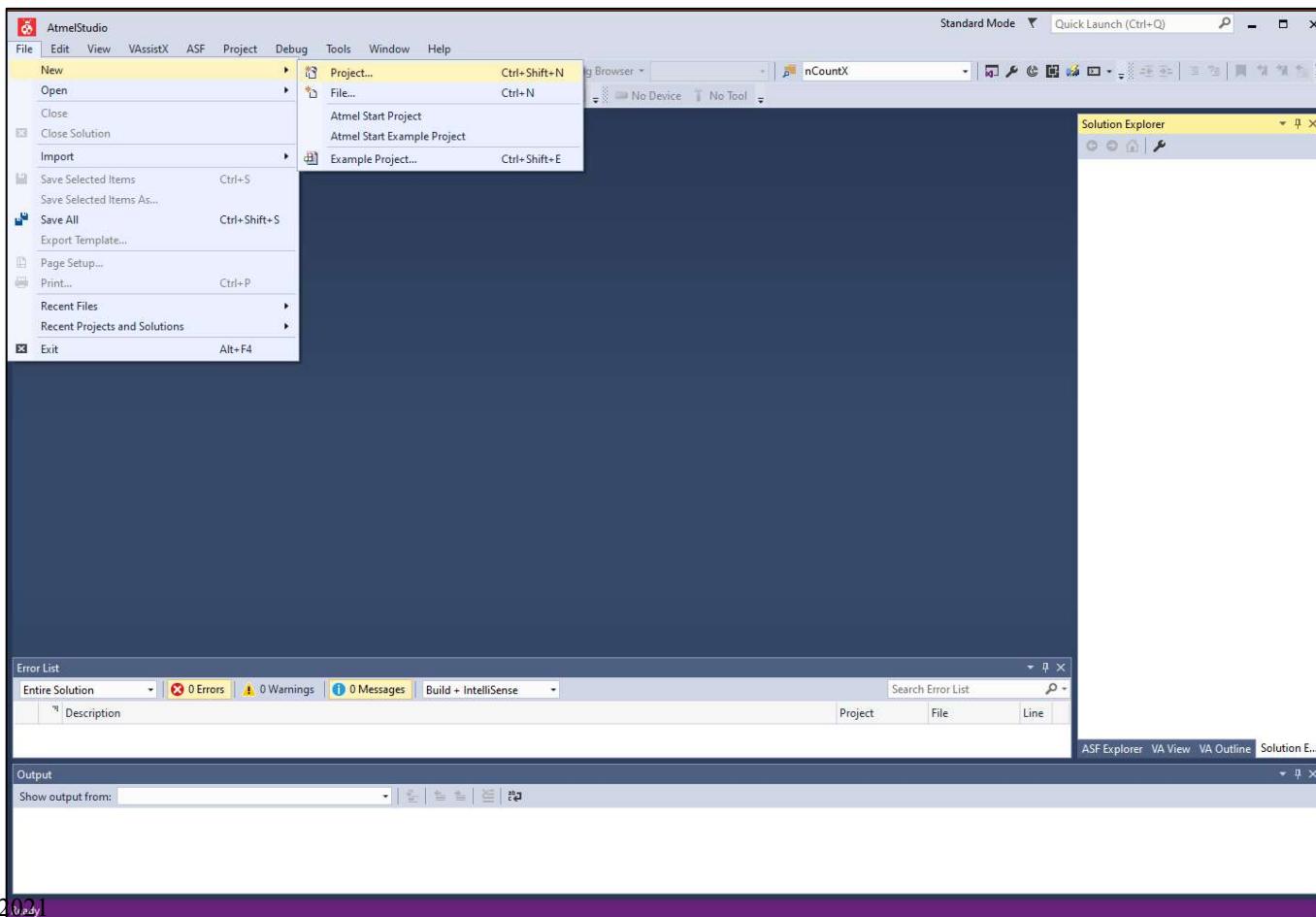
- Clone the MVM_V1_5C folder from
https://github.com/fabiankung/MVM_V1_5C

MVM_Arduino_Example	Arduino sketch for Example 3 & 4	Original firmware in hex format
MVM_Miscellaneous/Scilab	Add files via upload	
MVM_Original_Hex_File_R0.54	Latest firmware, to be used with latest PC software.	PC Application and Source codes for MV Monitor software
MVM_PC_Monitor_Software	Delete MV_Monitor.exe	
MVM_Sample_Firmware_R0.9	Minor update on transmission of hue information	Sample firmware in C for MVM V1.5C, stream image to PC, pre-programmed into unit
MVM_Sample_Firmware_R0.95_CNN	Add files via upload	
MVM_Sample_Firmware_R0.9LCD	Create Readme	Sample firmware in C for MVM V1.5C (stream Image to TFT LCD)
LICENSE	Create LICENSE	
MVM_TensorflowCNNModel_June202...	Add files via upload	
MVM_V1_5C_QuickStartGuide_V0_96...	Latest quick start guide	
README.md	Update README.md	

- “MVM_Sample_Firmware” contains all the drivers files and IPA 1 routines. You can use this to build your own custom applications.
- “MVM_PC_Monitor_Software” contains the Visual Studio template to build up the Machine Vision Monitor software in Visual Basic .NET and **also the executable** (be sure to allow exception from anti-virus software to download the *.exe file)

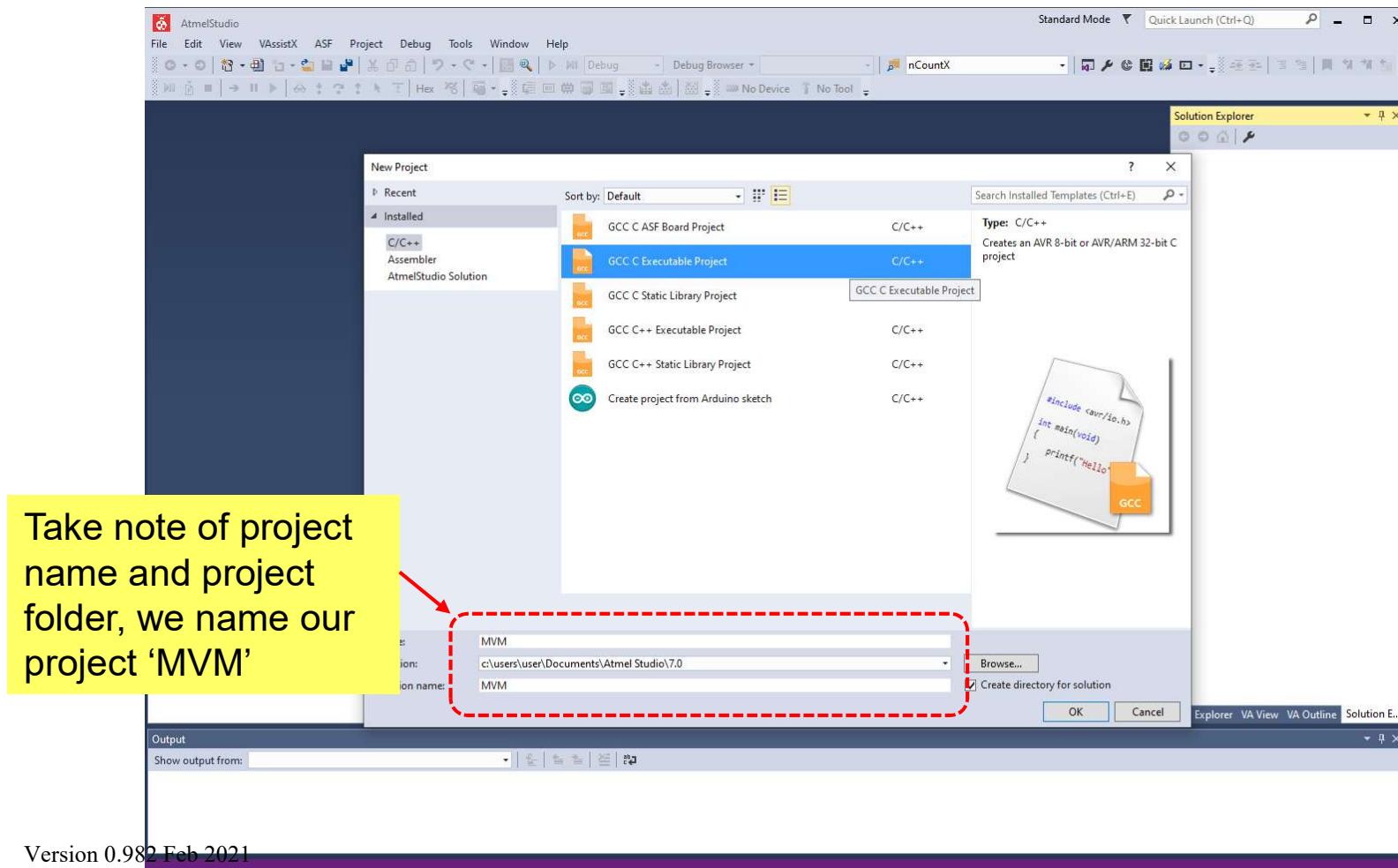
Setting Up An Atmel Studio 7 Project [1 of 10]

- Start a new project in Atmel Studio 7.



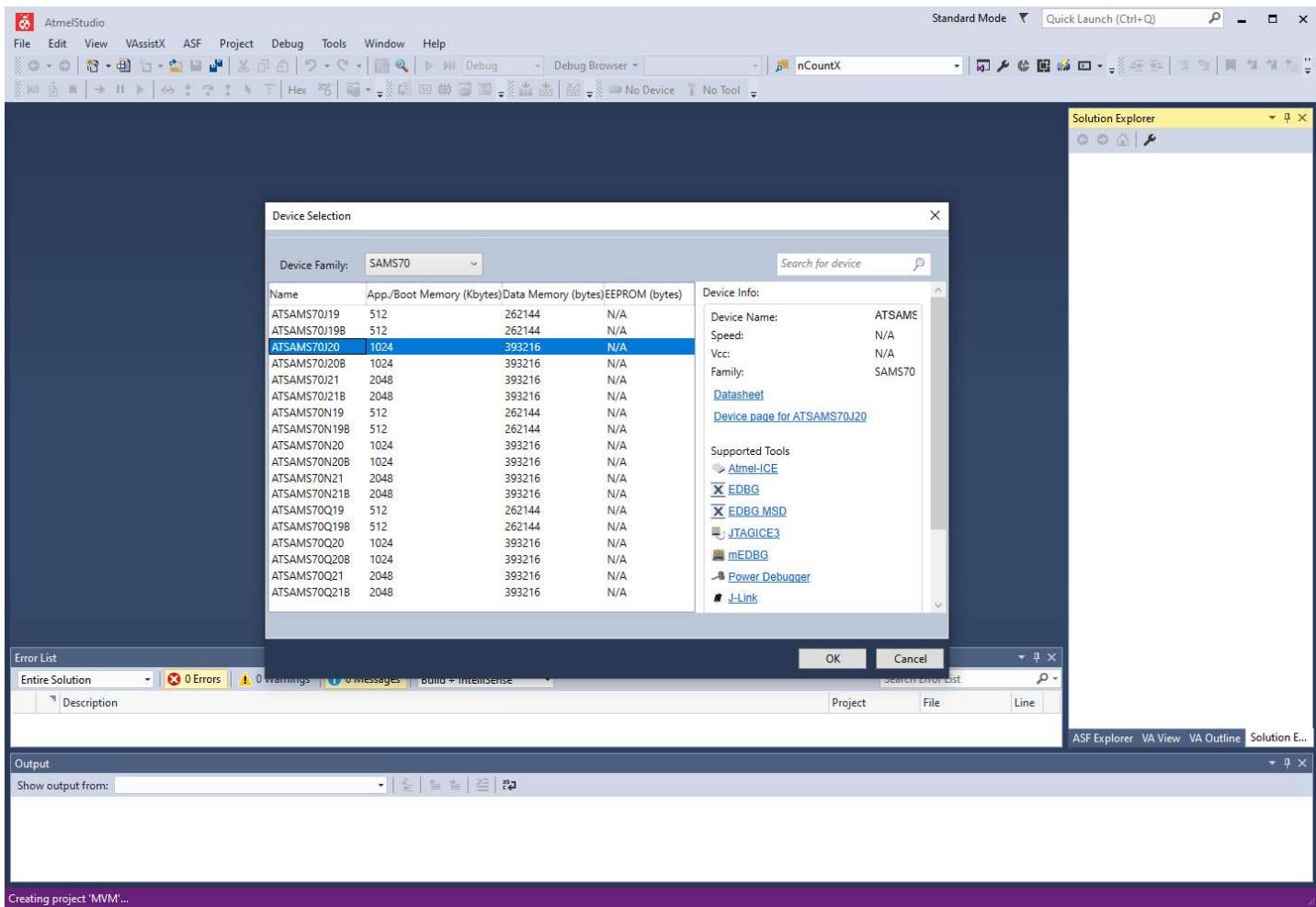
Setting Up An Atmel Studio 7 Project [2 of 10]

- Create a GCC C executable project.



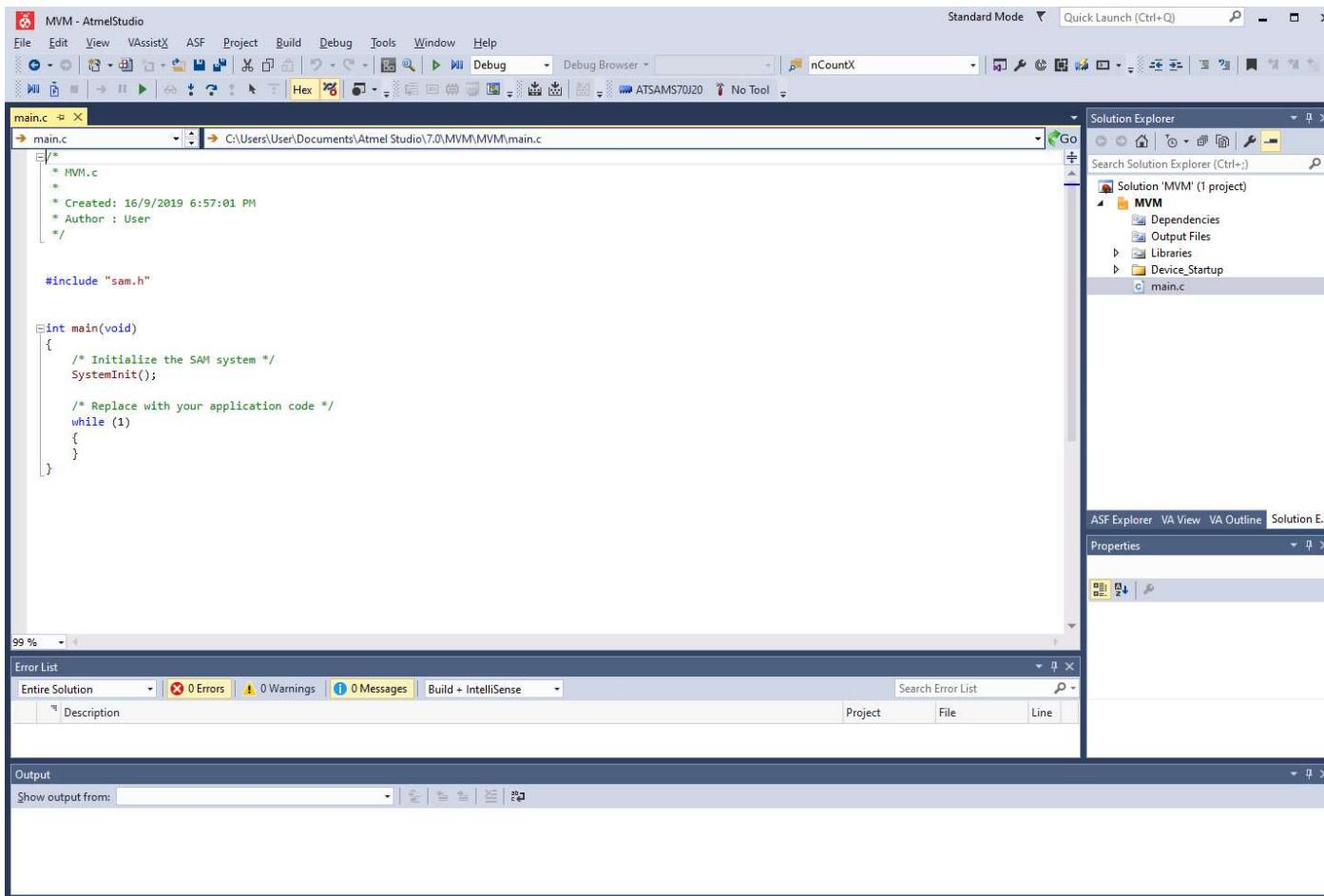
Setting Up An Atmel Studio 7 Project [3 of 10]

- Select the correct device.



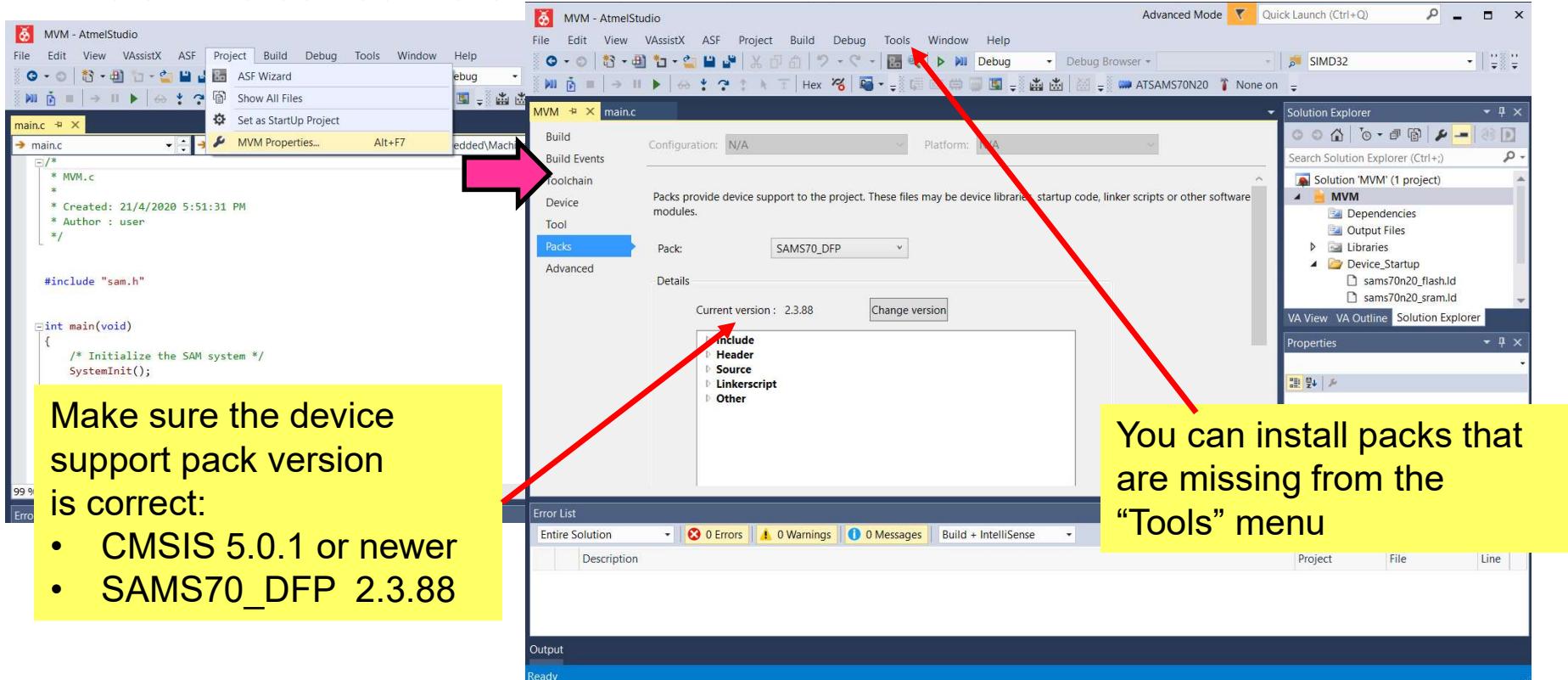
Setting Up An Atmel Studio 7 Project [4 of 10]

- A project with a default “main.c” file will be created.



Setting Up An Atmel Studio 7 Project [5 of 10]

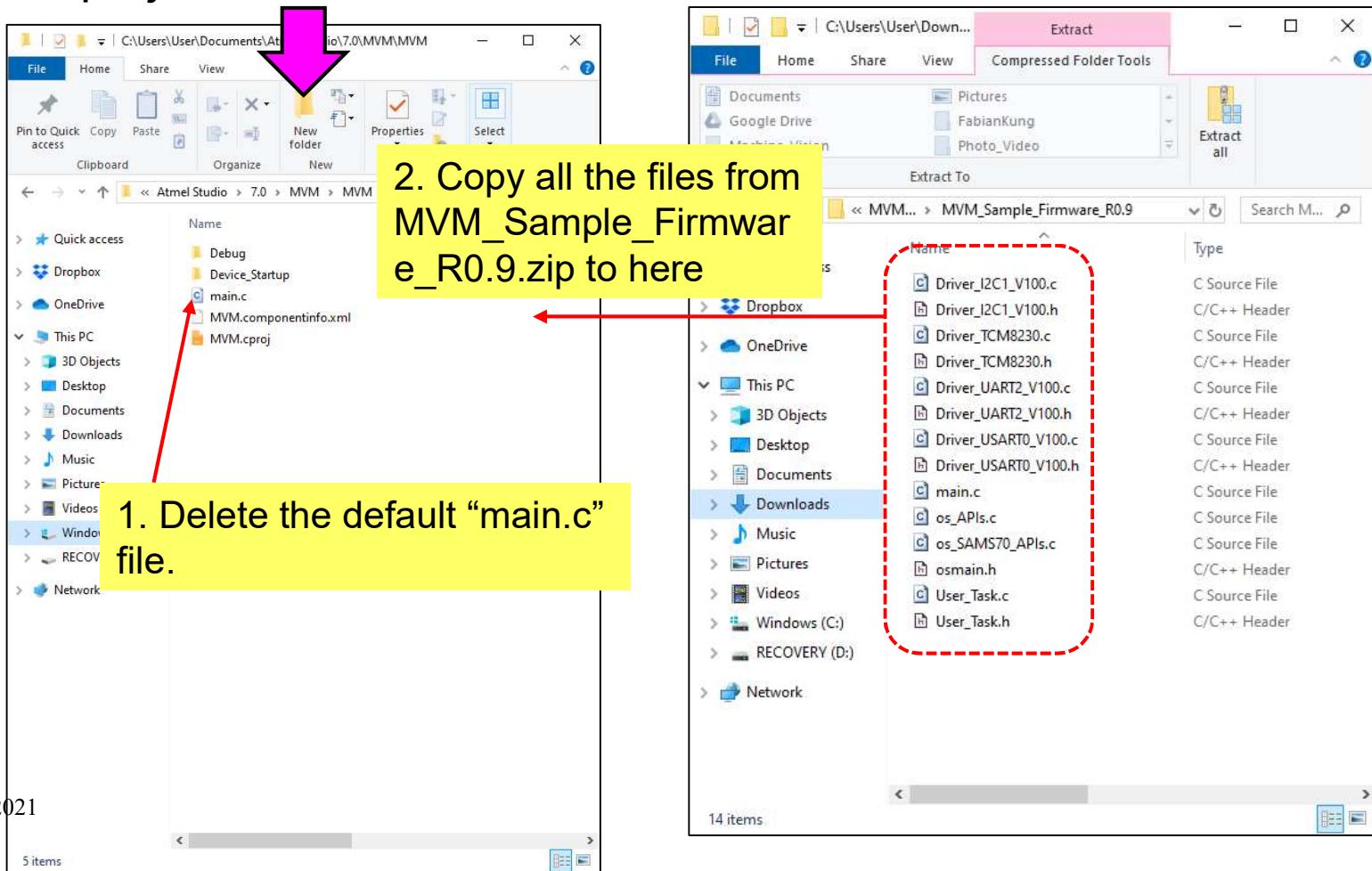
- Now view the properties of the project under the “Project” menu, make sure the CMSIS and device support package version is correct. Else you can install the correct version from the “Tool” menu.



Setting Up An Atmel Studio 7 Project

[6 of 10]

- Now close Atmel Studio 7.
- Go to the project folder.



Setting Up An Atmel Studio 7 Project [7 of 10]

- Now reopen Atmel Studio 7. The new “main.c” file will be reflected in the window.

The screenshot shows the Atmel Studio 7 interface with the following details:

- Solution Explorer:** Shows the project 'MVM' with a single item: 'main.c'. A red arrow points to this item with the text "New ‘main.c’ file."
- Properties:** Shows 'MVM Project Properties' and 'Misc' section with 'Project File' set to 'MVM.cproj'.
- Output:** Shows the output window which is currently empty.
- Error List:** Shows the error list with 'Entire Solution' selected, showing 0 Errors, 0 Warnings, and 0 Messages.
- Code Editor:** Displays the 'main.c' file content, which includes initialization code for various drivers and tasks.

```
main.c // C:\Users\User\Documents\Atmel Studio\7.0\MVM\MVM\Driver_TCM8230.h
#include "User_Task.h"

int main(void)
{
    int ni = 0;

    SAMS70_Init();           // Custom initialization, see file "os_SAMS70_APIS.c". This will overwrites the
                            // initialization done in SystemInit();
    OSInit();                // Custom initialization: Initialize the RTOS.
    gnTaskCount = 0;          // Initialize task counter.

    // Initialize core OS processes.
    OSCreateTask(&gstrcTaskContext[gnTaskCount], OSProce1);           // Start main blinking LED process.

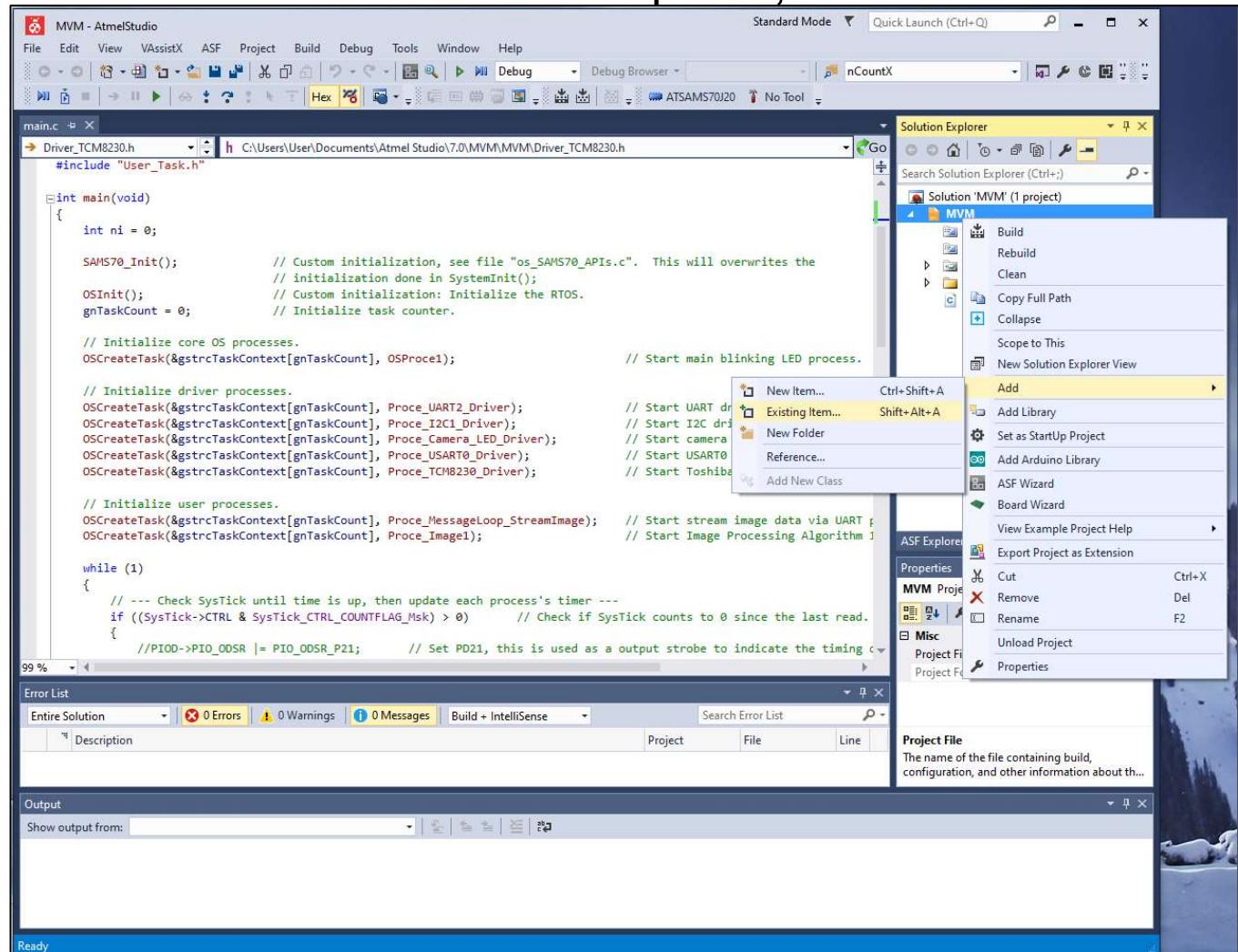
    // Initialize driver processes.
    OSCreateTask(&gstrcTaskContext[gnTaskCount], Proce_UART2_Driver);   // Start UART driver.
    OSCreateTask(&gstrcTaskContext[gnTaskCount], Proce_I2C1_Driver);     // Start I2C driver.
    OSCreateTask(&gstrcTaskContext[gnTaskCount], Proce_Camera_LED_Driver); // Start camera LED driver.
    OSCreateTask(&gstrcTaskContext[gnTaskCount], Proce_USART0_Driver);   // Start USART0 driver.
    OSCreateTask(&gstrcTaskContext[gnTaskCount], Proce_TC8230_Driver);   // Start Toshiba TC8230 camera driver

    // Initialize user processes.
    OSCreateTask(&gstrcTaskContext[gnTaskCount], Proce_MessageLoop_StreamImage); // Start stream image data via UART p
    OSCreateTask(&gstrcTaskContext[gnTaskCount], Proce_Image1);           // Start Image Processing Algorithm J

    while (1)
    {
        // --- Check SysTick until time is up, then update each process's timer ---
        if ((SysTick->CTRL & SysTick_CTRL_COUNTFLAG_Msk) > 0)           // Check if SysTick counts to 0 since the last read.
        {
            //PIO0->PIO_ODSR |= PIO_ODSR_P21;      // Set PD21, this is used as a output strobe to indicate the timing c
        }
    }
}
```

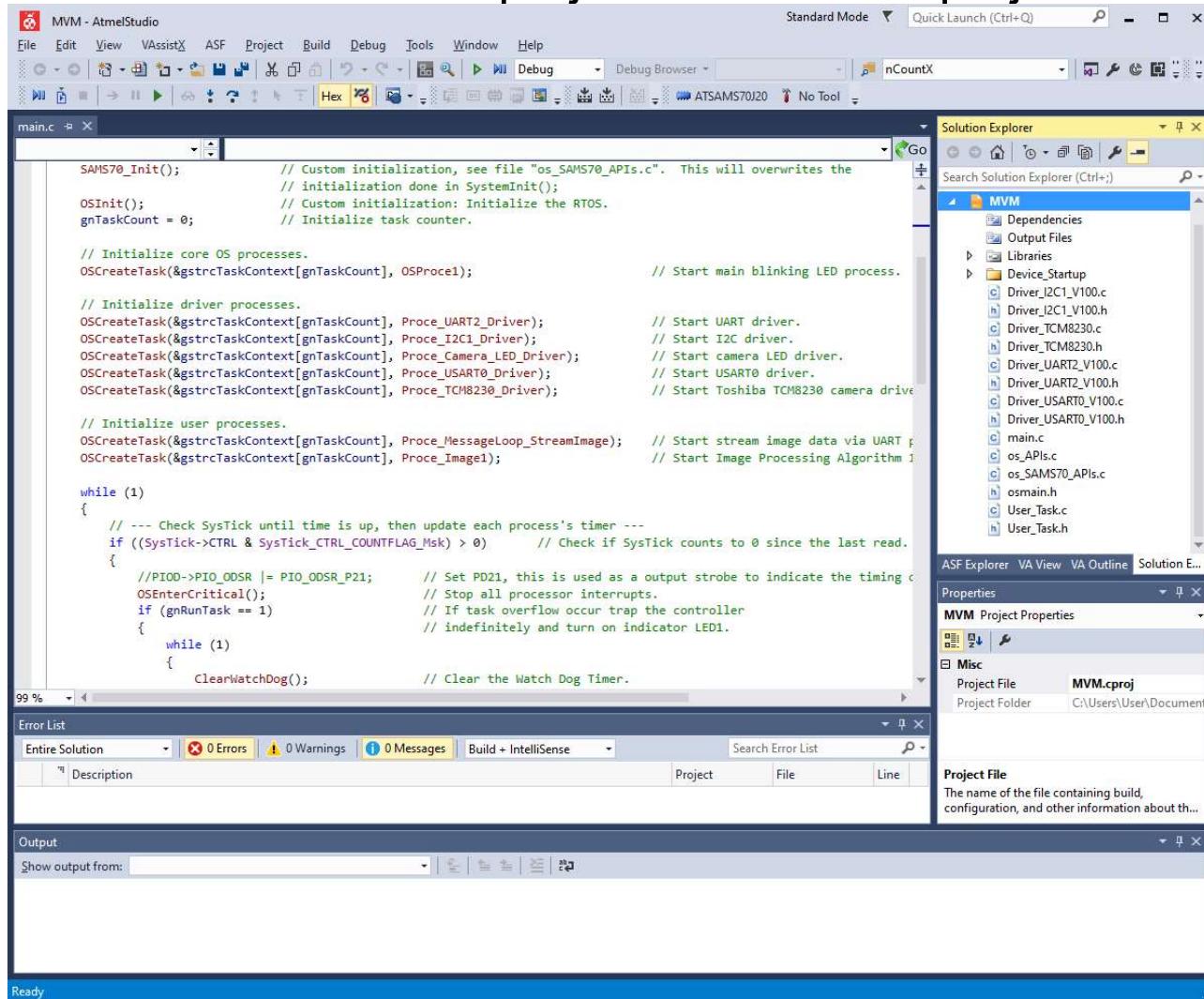
Setting Up An Atmel Studio 7 Project [8 of 10]

- Right click the folder “MVM” in the Solution Explorer, and select Add Existing Item...



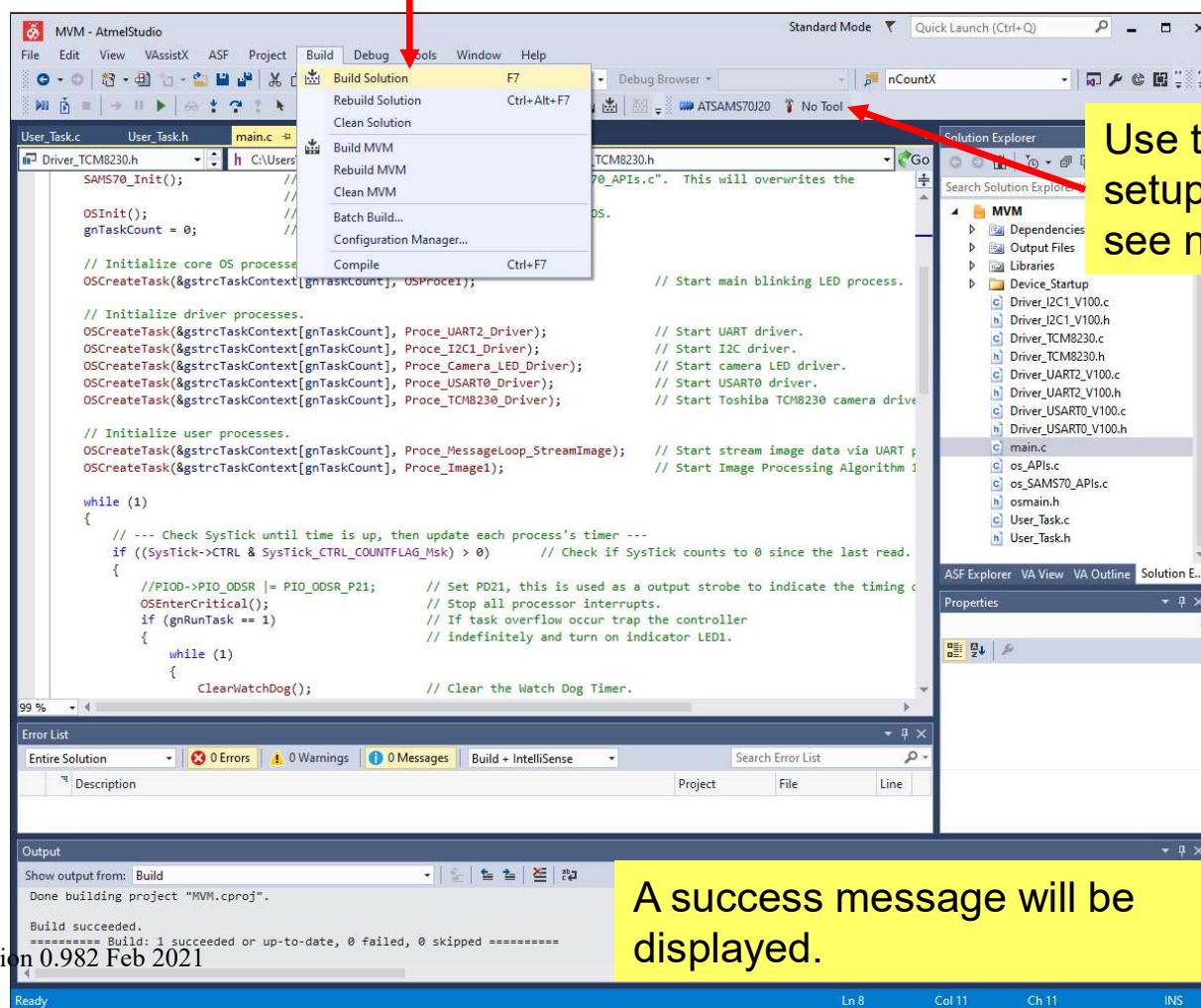
Setting Up An Atmel Studio 7 Project [9 of 10]

- Add all the *.c and *.h files in the project folder to the project.



Setting Up An Atmel Studio 7 Project [10 of 10]

- Now you can build or compile the project.

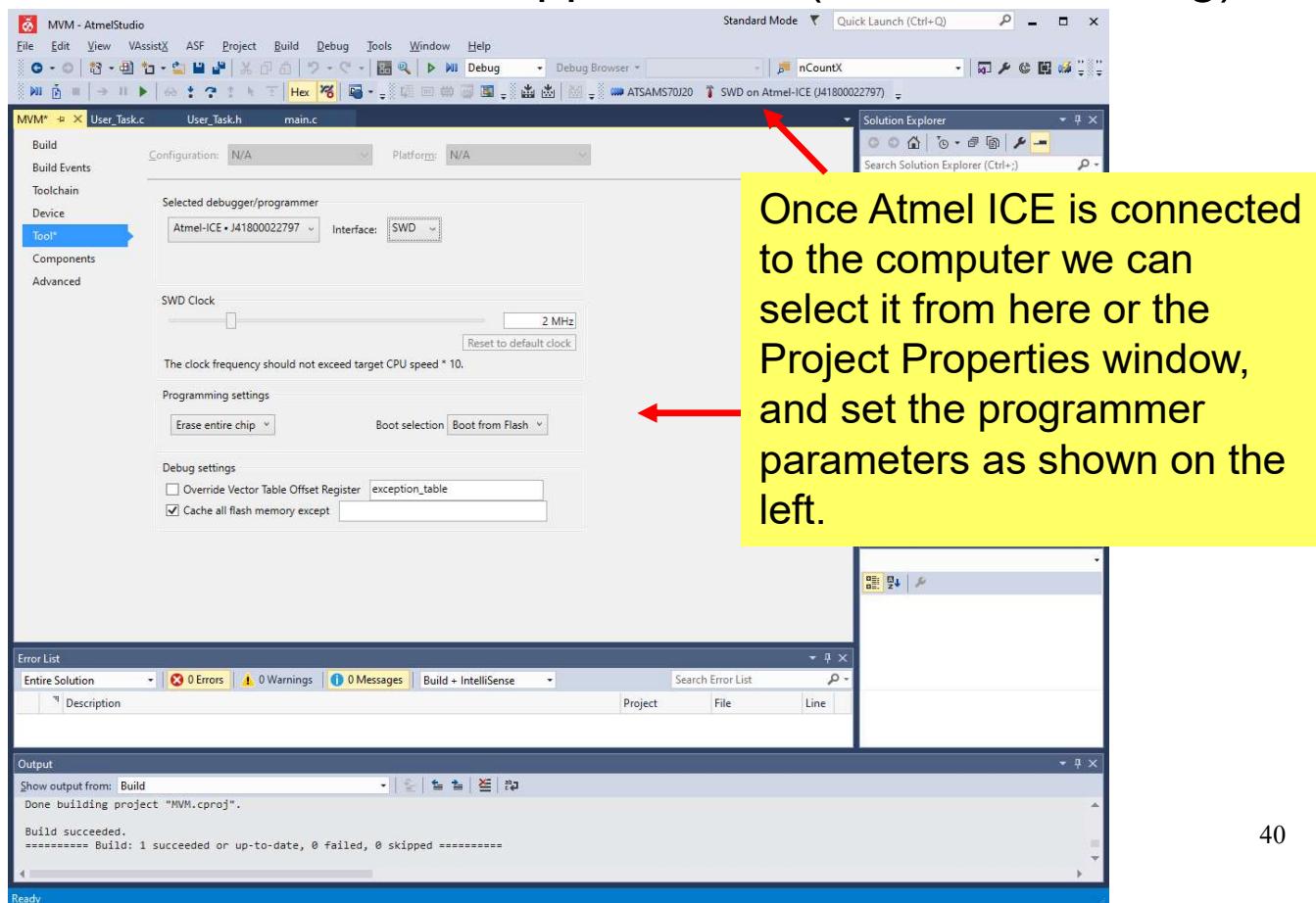


Use this tab to select and setup the programming tool, see next slide.

A success message will be displayed.

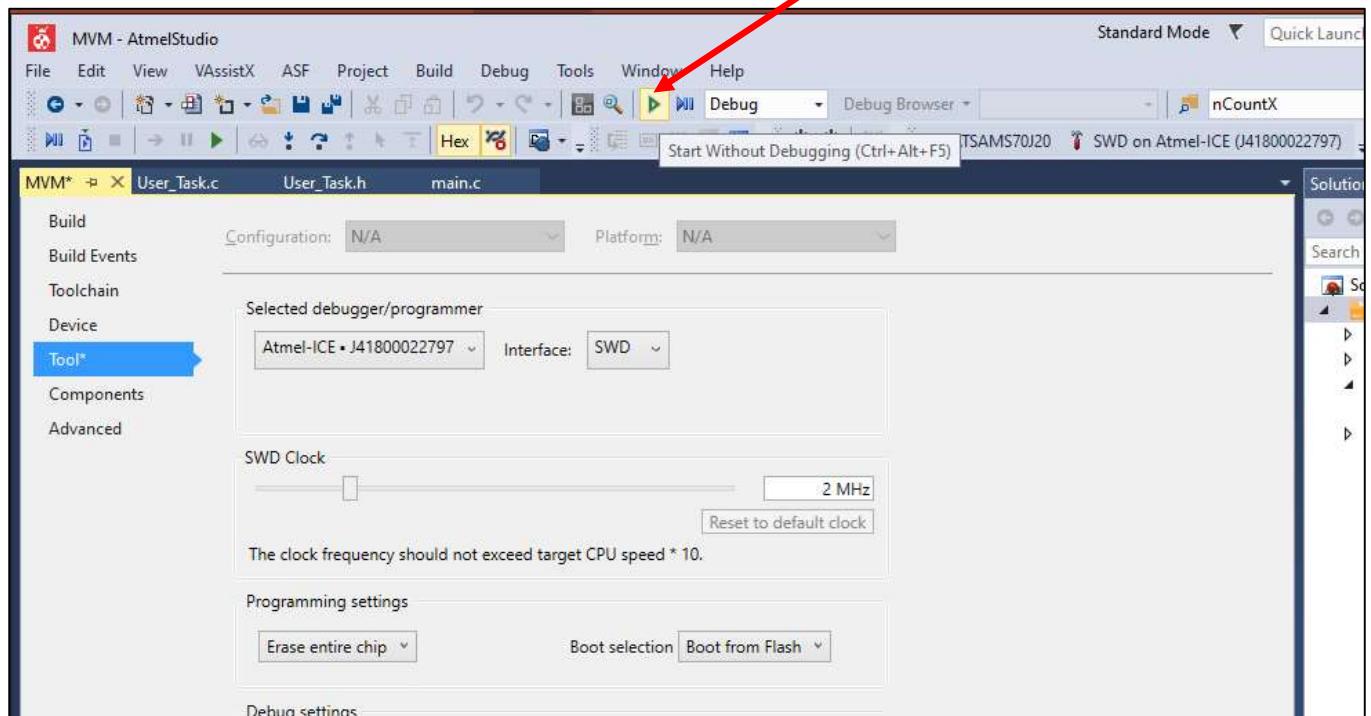
Setting Up the Programming Tool – Atmel ICE

- Now you can load the firmware into the micro-controller with a suitable programmer. Here we are using Atmel ICE, but any programmer compatible with Atmel Studio 7 and support SWD (serial wire debug) mode is fine.



Flashing the Micro-Controller 1

- Connect the MVM to Atmel ICE. Power up the MVM and click this button to program the flash memory.
- See **Appendix** on the pin assignment on the 2x3 ways receptacle that comes with Atmel ICE.



Flashing the Micro-Controller 2

- Finally you need to setup the TCM (tightly coupled memory) size of Cortex M7 by setting the GPNVM (general purpose non-volatile memory) bits of SAMS70 as shown.

The screenshot shows the AtmelStudio interface with the 'Tool' tab selected. A red arrow points to the 'Device Programming' option in the 'Tools' menu. The main window displays the 'Atmel-ICE (J41800022797) - Device Programming' dialog. In the 'GPNVM Bits' section, two checkboxes are checked: 'GPNVMBITS.BOOT_MODE' (Value: checked) and 'GPNVMBITS.TCM_CONFIGURATION' (Value: 0x01). A yellow callout box with a red arrow points to the 'Apply' button at the top right of the dialog, with the text 'Click "Apply" button'. Below the dialog, another yellow callout box contains the text 'The Heartbeat LED of the MVM V1.5C should start blinking once all the GPNVM bits are programmed.' In the bottom right corner of the dialog, there is a 'Program' button with a red arrow pointing to it, and a yellow callout box with the text 'Hit the 'Program' button once the parameters are properly setup.'

Atmel-ICE (J41800022797) - Device Programming

Tool	Device	Interface	Device signature	Target Voltage
Atmel-ICE	ATSAMS70J20	SWD	0xA1120C01	3.3 V

Interface settings
Tool information
Device information
Memories
GPNVM Bits
Lock bits
Security

GPNVMBITS.BOOT_MODE
GPNVMBITS.TCM_CONFIGURATION

Register Value
GPNVMBITS 0x0182

Auto read
Verify after programming

Program Verify Read

Starting operation read registers
Reading register GPNVMBITS...OK
Read registers...OK

Read registers...OK

Version 0.982 Feb 2021

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Coding Your Own Routines

- The source files “**User_Task.c**” and “**User_Task.h**” contains the routines and declarations for **image processing task 1** that search for the brightest region in an image.
- Use this as the basis to add on your own routines. Do remember to use the state machine approach to code your tasks, and keep the total execution time for all tasks within 1 system ticks!
- For more information on the round-robin scheduler and basic structure of the C codes for Atmel/Microchip ARM Cortex-M see
<https://fkeng.blogspot.com/2016/02/atmel-arm-cortex-m4-microcontroller.html>

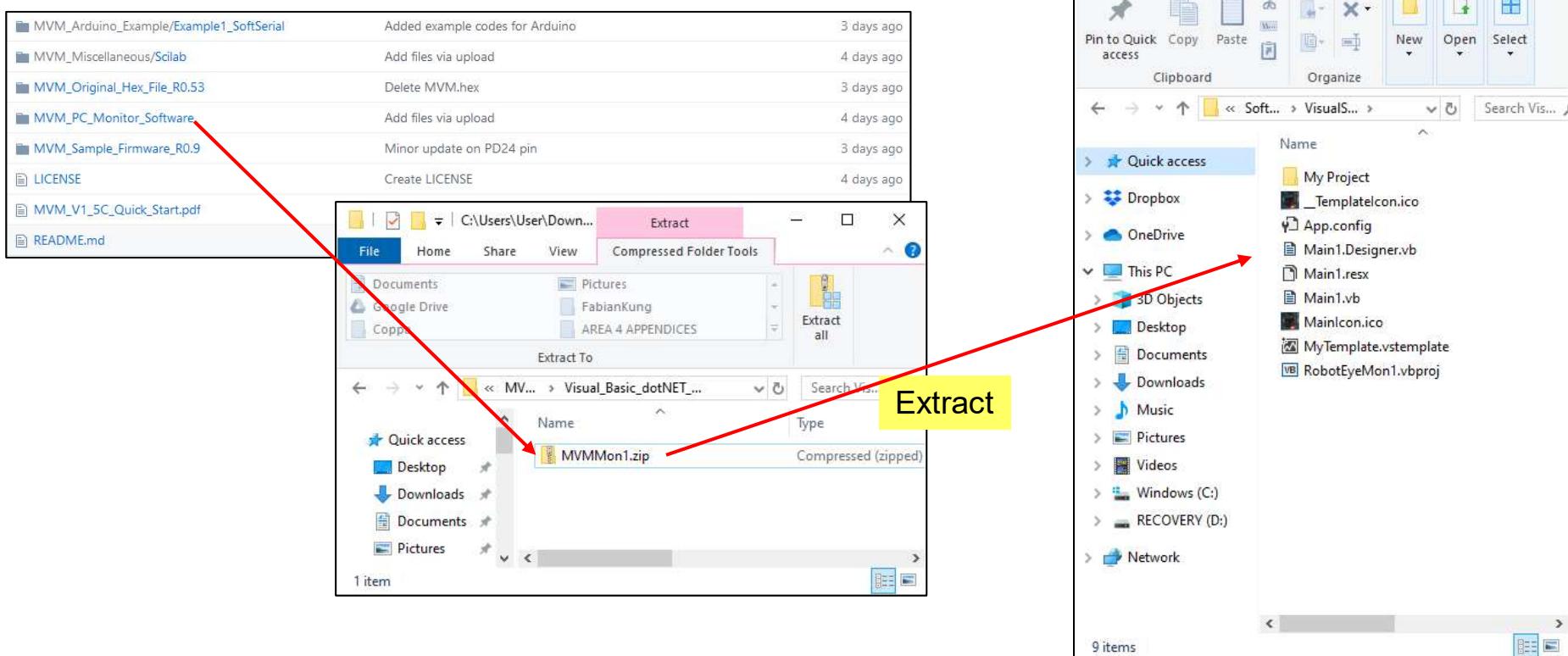
Compiling and Building the Machine Vision Monitor Software

Introduction

- The PC application (*.exe) to observe the image frames captured by the MVM and the corresponding source codes are also provided.
- If needed, you can rebuild the application using Visual Studio Community version and customize the software features.
- The following slides show how to setup the Visual Studio project from the source codes provided.

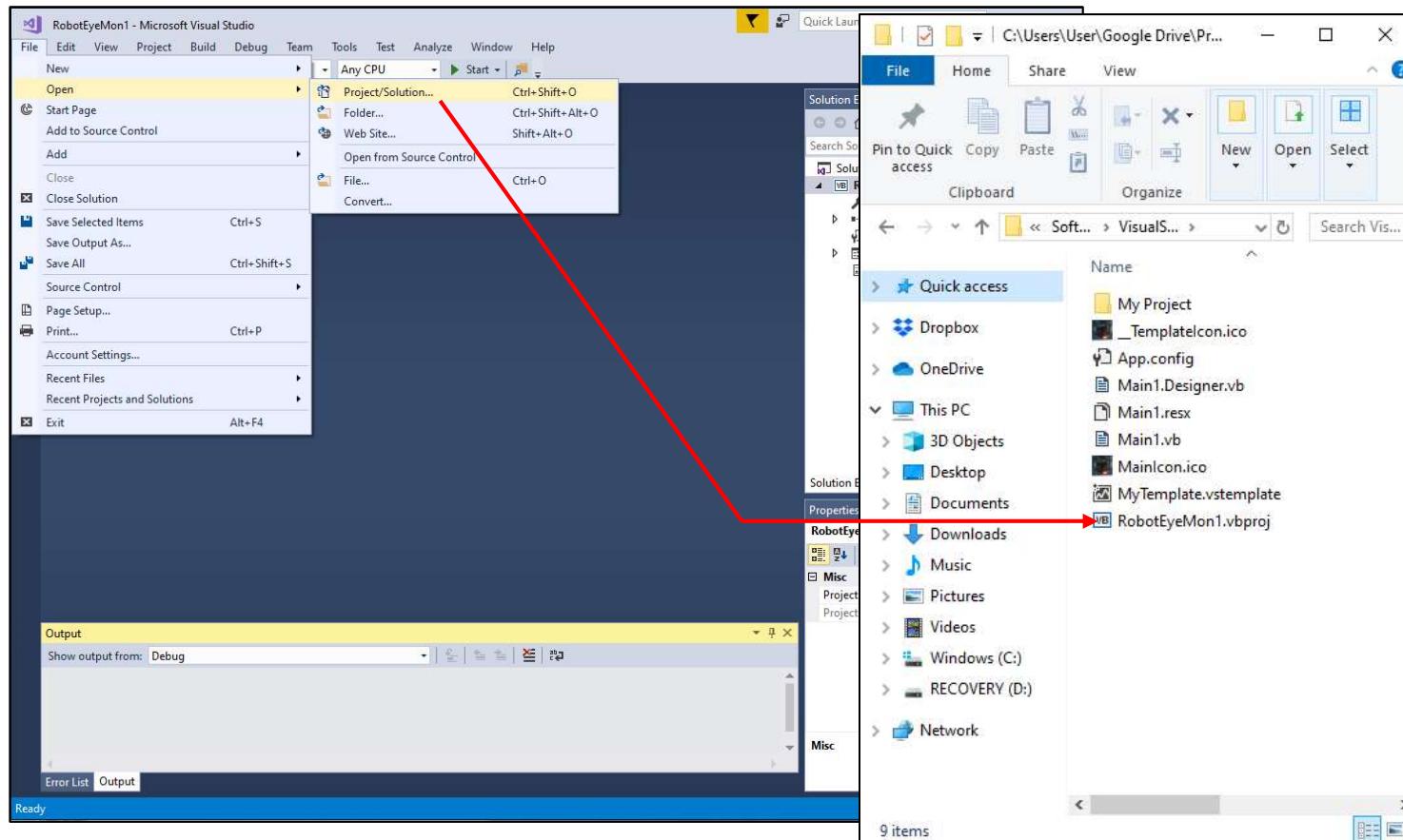
Setting Up Visual Studio Project [1 of 6]

- In the folder “MVM_PC_Monitor_Software” look for the file MVMMon1.zip.
- Decompress the file into a suitable project folder.



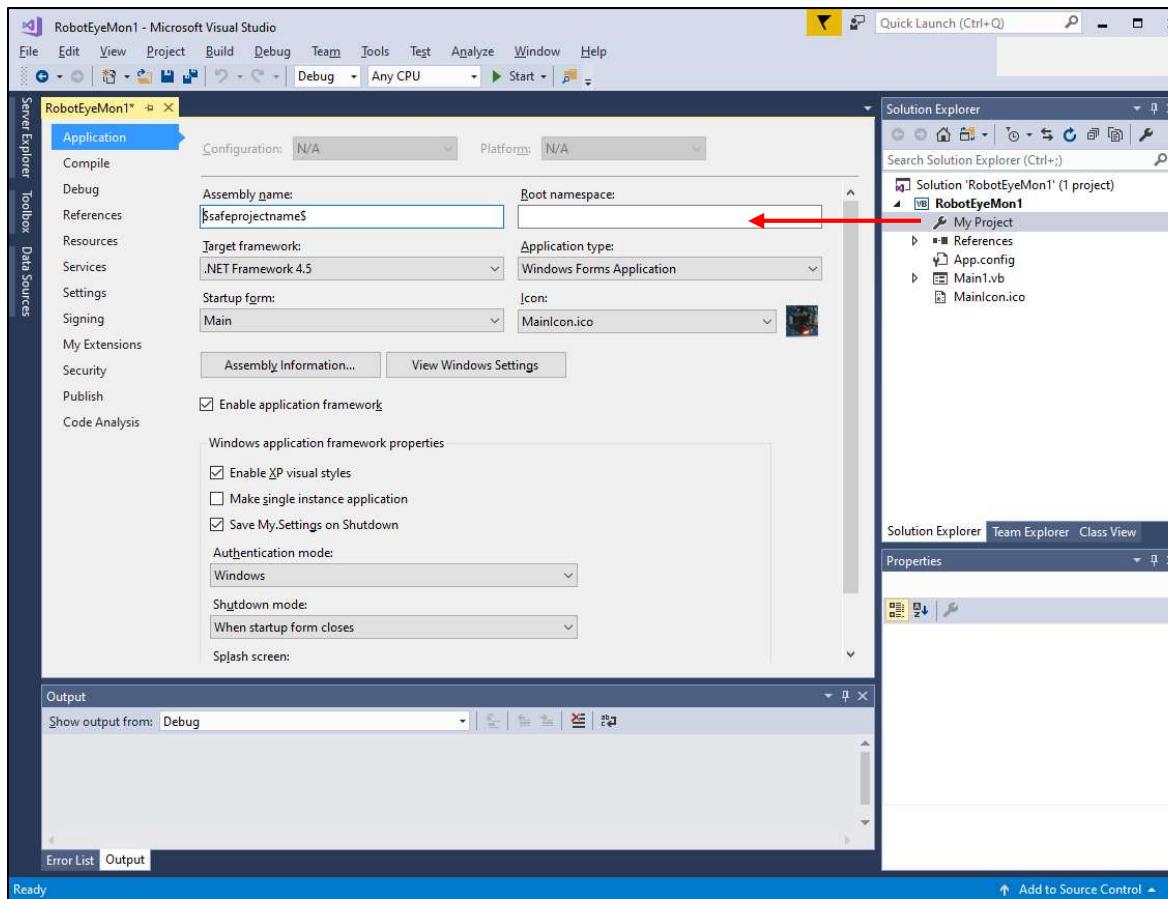
Setting Up Visual Studio Project [2 of 6]

- Open Visual Studio, and open the VB project (*.vbproj) as shown.



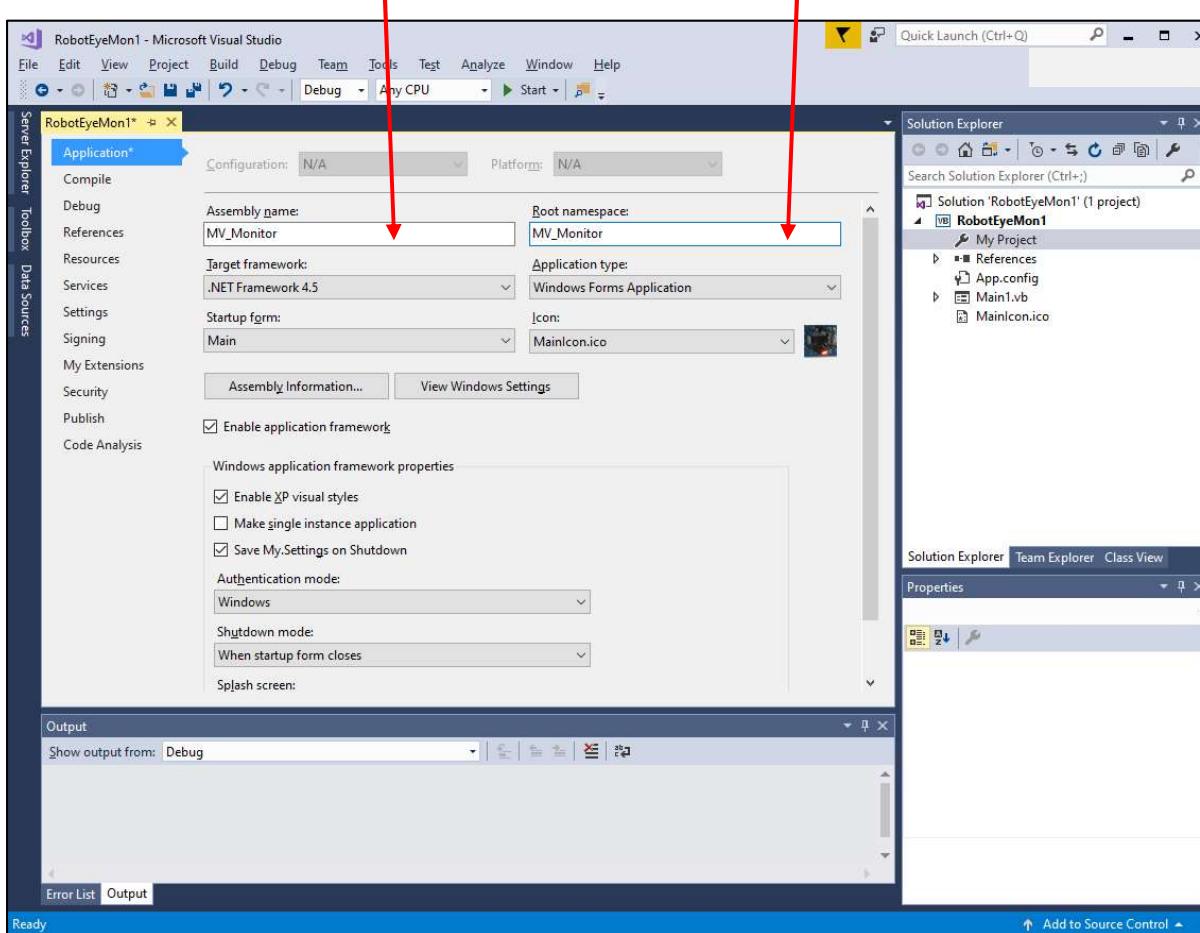
Setting Up Visual Studio Project [3 of 6]

- Double-click the MyProject icon to bring up the project setting.



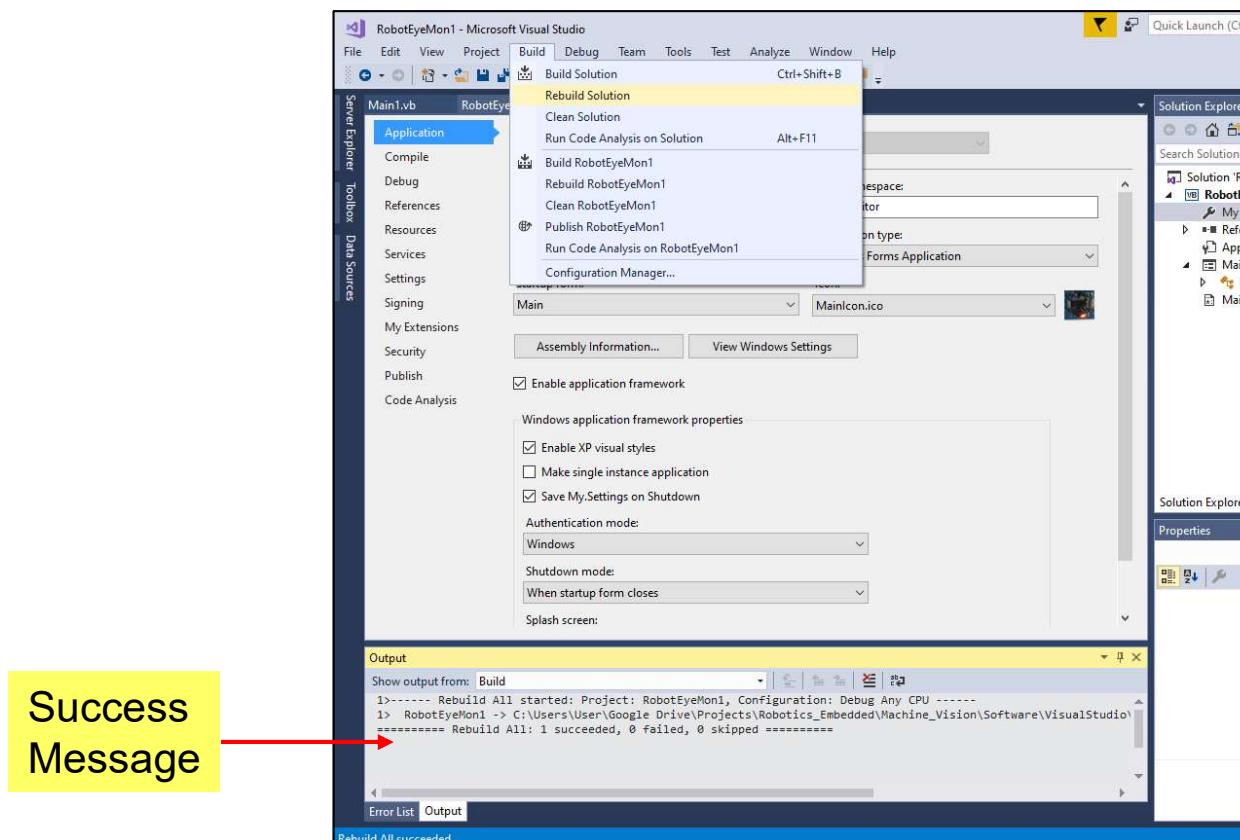
Setting Up Visual Studio Project [4 of 6]

- Type in the Assembly Name and Root Namespace as shown.



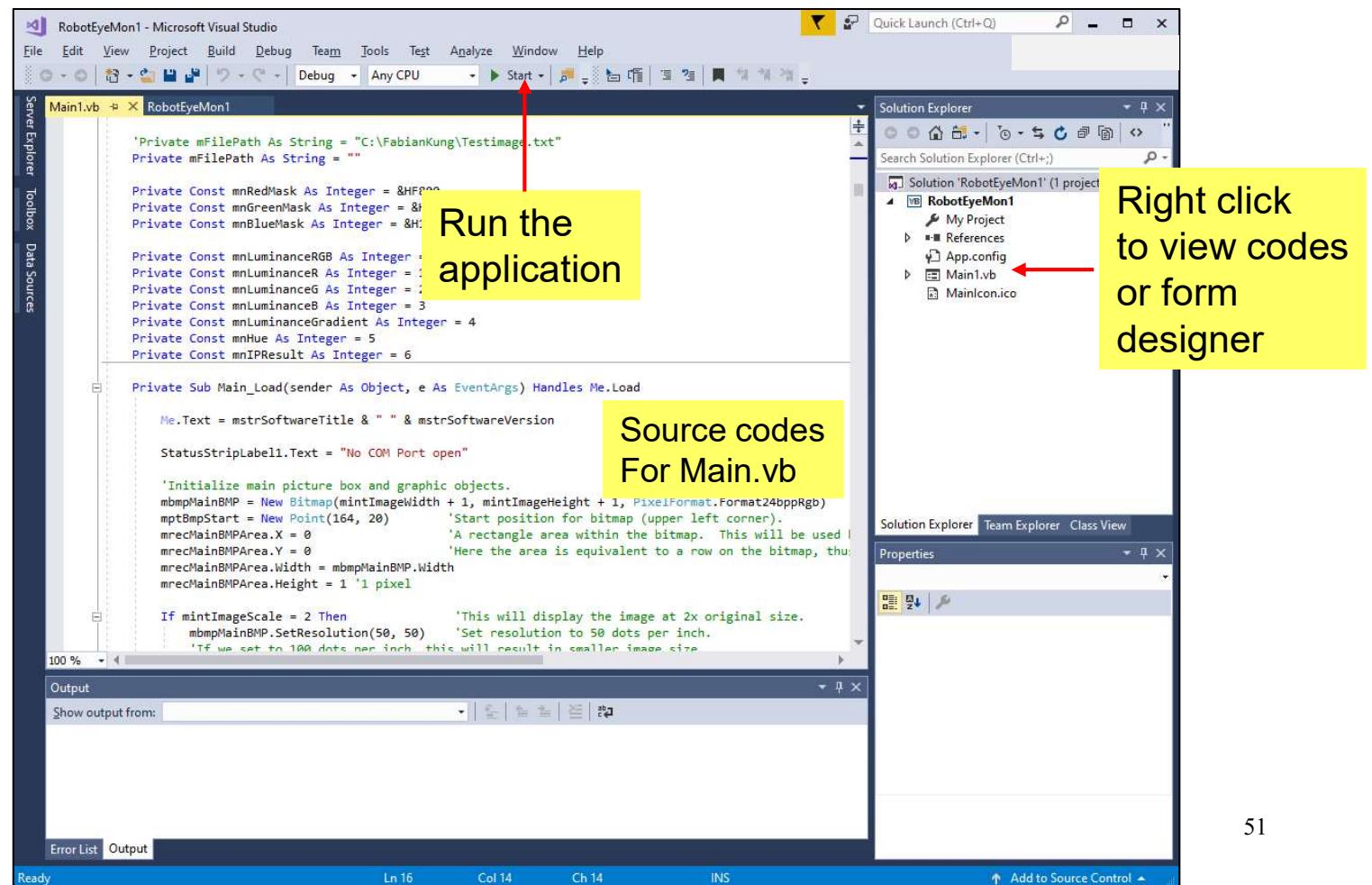
Setting Up Visual Studio Project [5 of 6]

- Now rebuild the project as shown and you should get a success message in the Output window.



Setting Up Visual Studio Project [6 of 6]

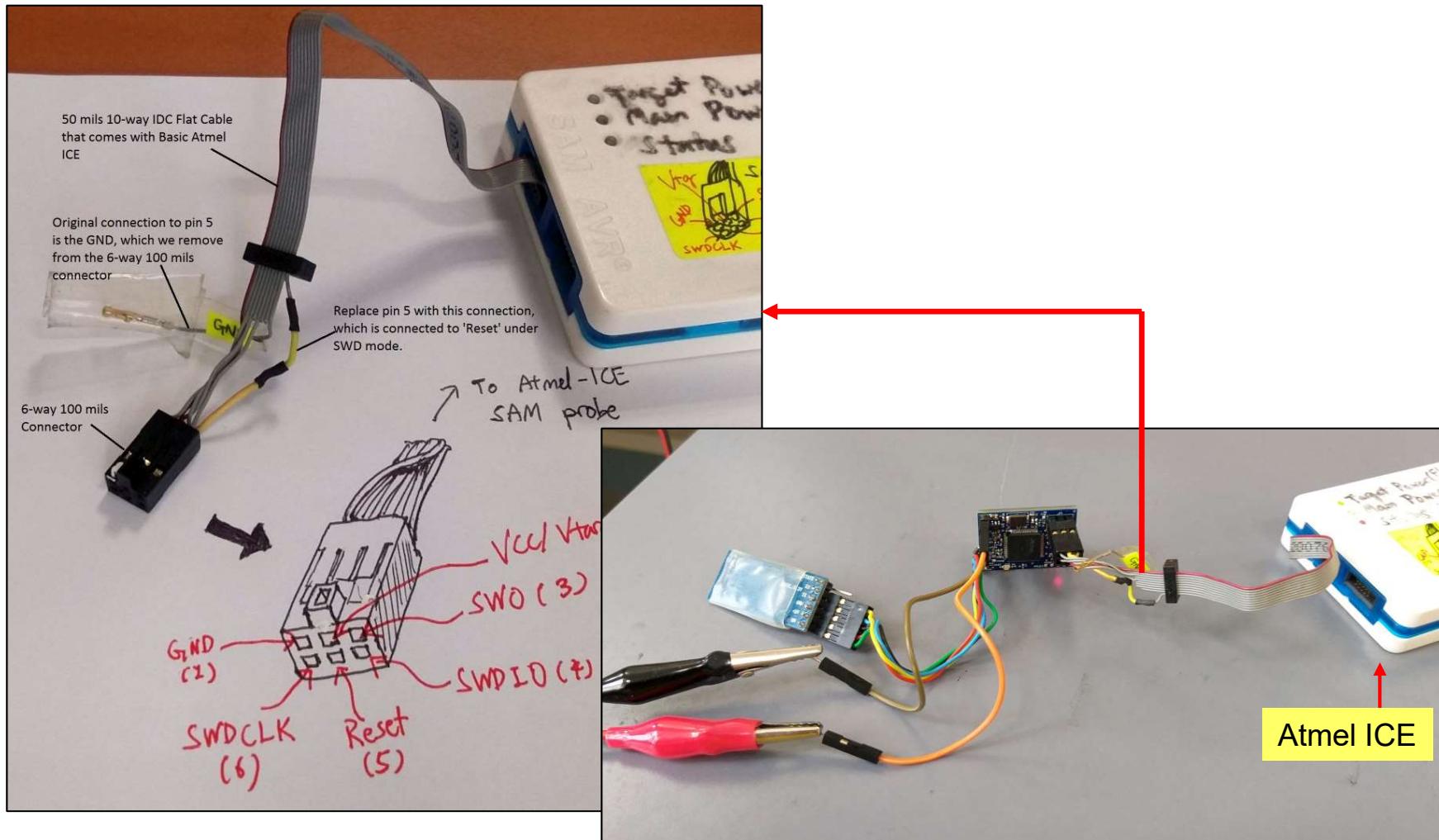
- You can now run the application, view/edit the source code and the main window form.



APPENDIX

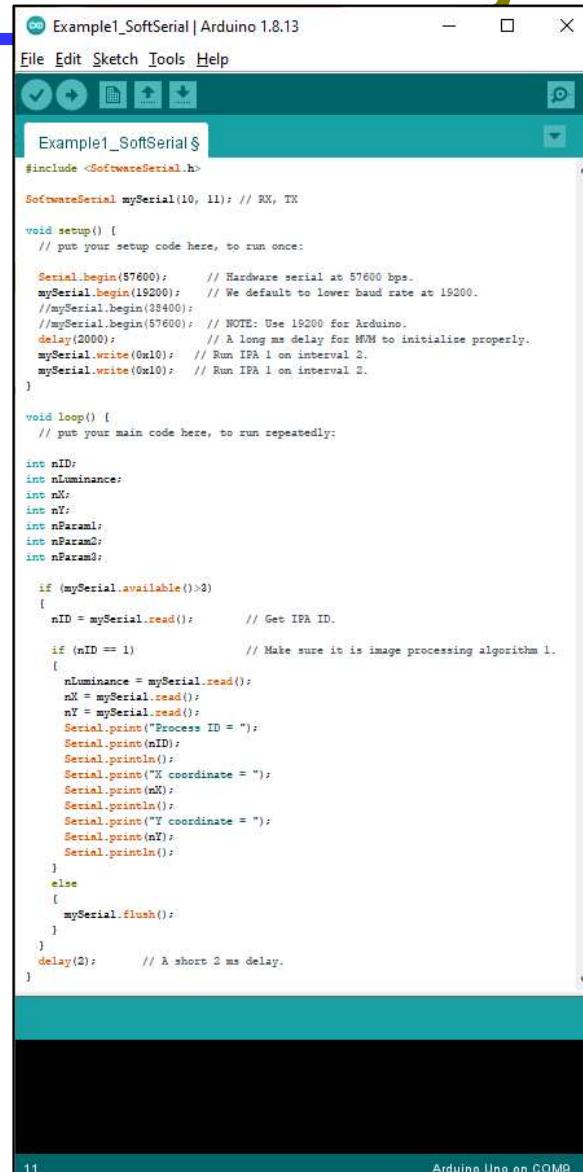
Programmer Connection, Examples and File Export

Connecting Atmel ICE to MVM V1.5C



Example 1 - Using MVM with Arduino Uno and SoftwareSerial Library

In this code we use SoftwareSerial port to communicate with MVM V1.5C, while the hardware serial is used in conjunction with Serial Terminal for debugging.



The screenshot shows the Arduino IDE interface with the title bar "Example1_SoftSerial | Arduino 1.8.13". The code editor contains the following sketch:

```
#include <SoftwareSerial.h>

SoftwareSerial mySerial(10, 11); // RX, TX

void setup() {
  // put your setup code here, to run once:

  Serial.begin(57600); // Hardware serial at 57600 bps.
  mySerial.begin(19200); // We defaults to lower baud rate at 19200.
  //mySerial.begin(38400);
  //mySerial.begin(57600); // NOTE: Use 19200 for Arduinos.
  delay(2000); // A long ms delay for MVM to initialize properly.
  mySerial.write(0x10); // Run IPA 1 on interval 2.
  mySerial.write(0x10); // Run IPA 1 on interval 2.
}

void loop() {
  // put your main code here, to run repeatedly:

  int nID;
  int nLuminance;
  int nX;
  int nY;
  int nParam1;
  int nParam2;
  int nParam3;

  if (mySerial.available()>2)
  {
    nID = mySerial.read(); // Get IPA ID.

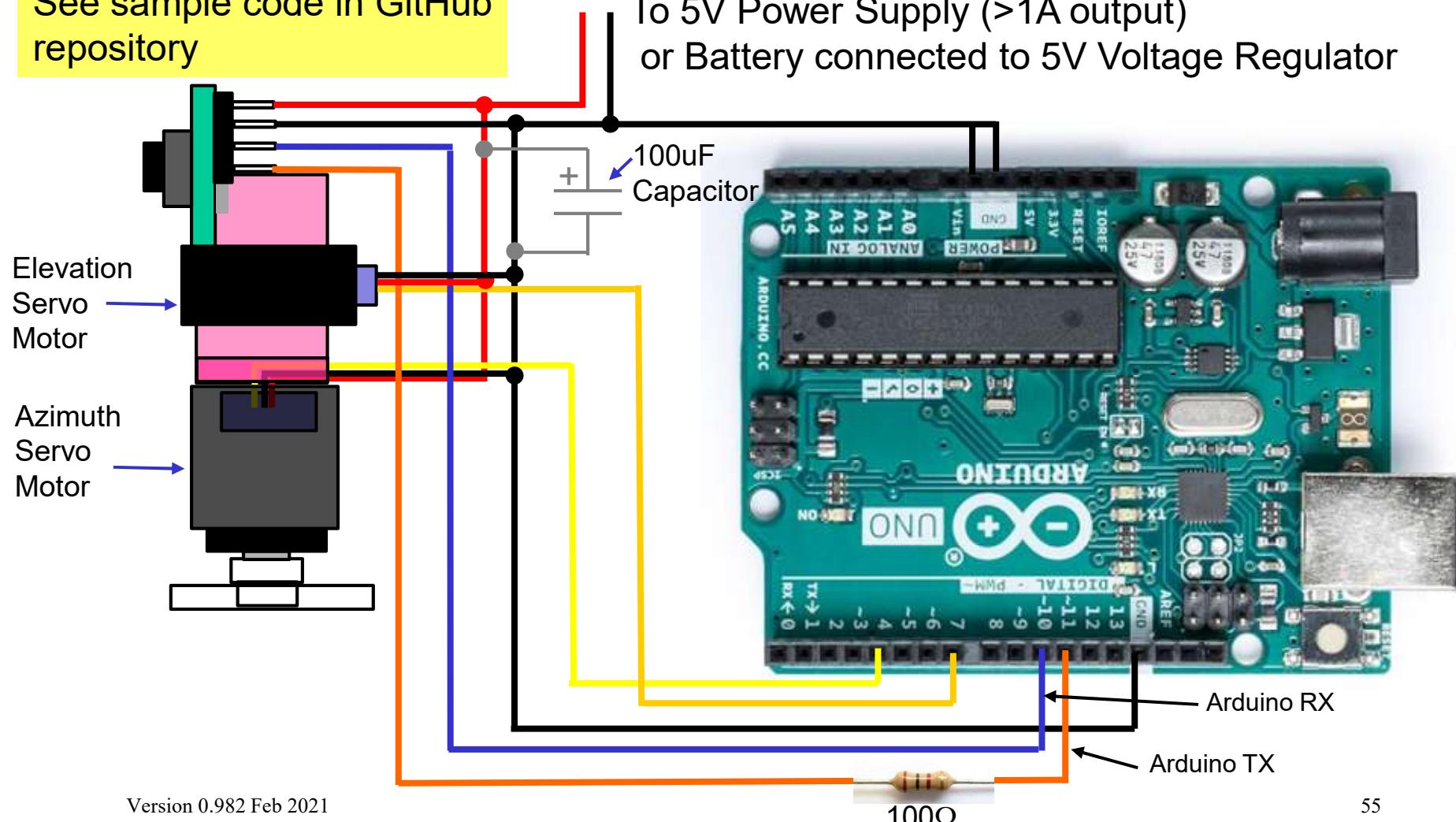
    if (nID == 1) // Make sure it is image processing algorithm 1.
    {
      nLuminance = mySerial.read();
      nX = mySerial.read();
      nY = mySerial.read();
      Serial.print("Process ID = ");
      Serial.print(nID);
      Serial.println();
      Serial.print("X coordinate = ");
      Serial.print(nX);
      Serial.print("\n");
      Serial.print("Y coordinate = ");
      Serial.print(nY);
      Serial.print("\n");
      Serial.println();
    }
    else
    {
      mySerial.flush();
    }
  }
  delay(2); // A short 2 ms delay.
}
```

The status bar at the bottom right shows "Arduino Uno on COM9".

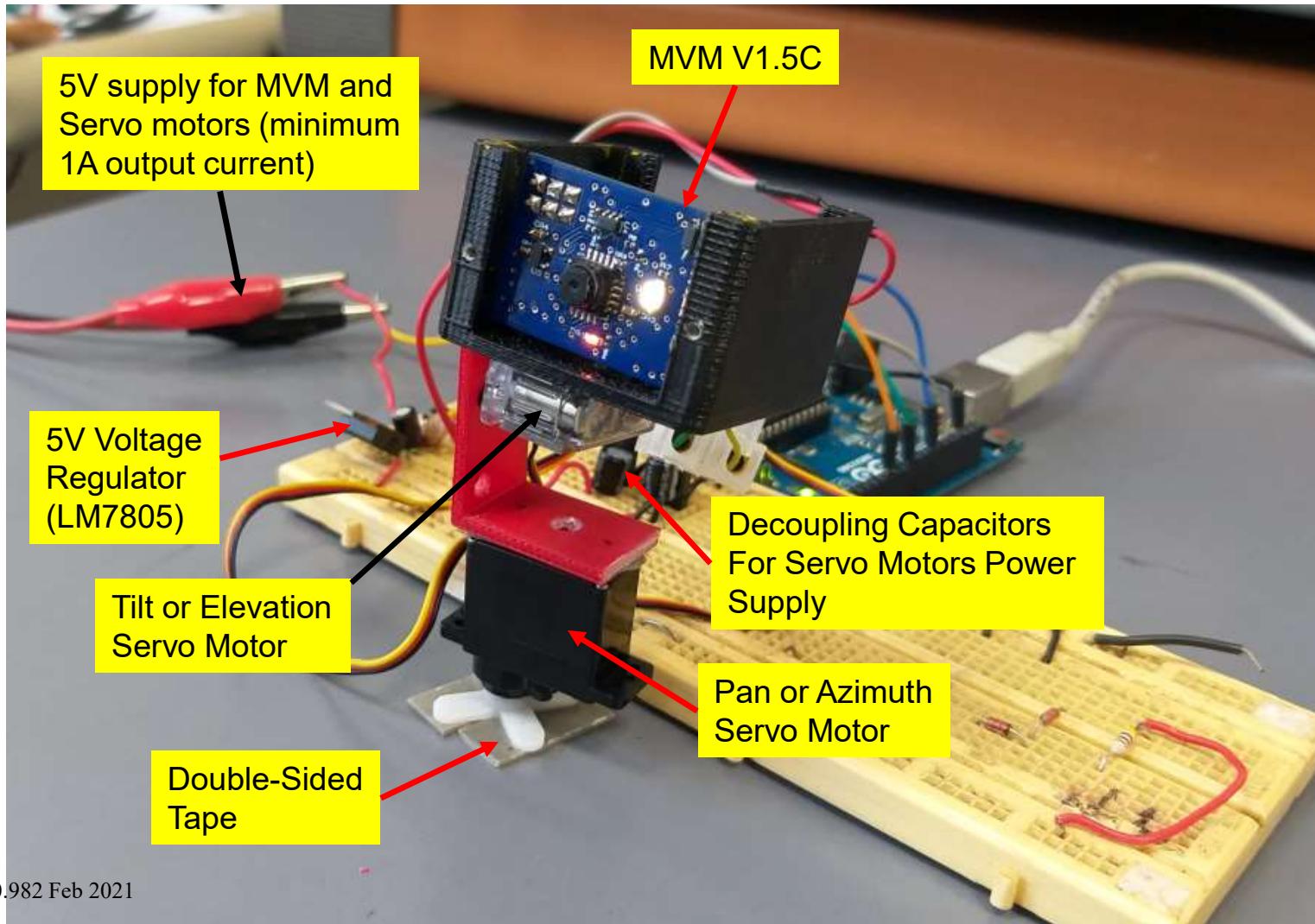
Example 3 - Color Object Tracking with Arduino Uno

See sample code in GitHub repository

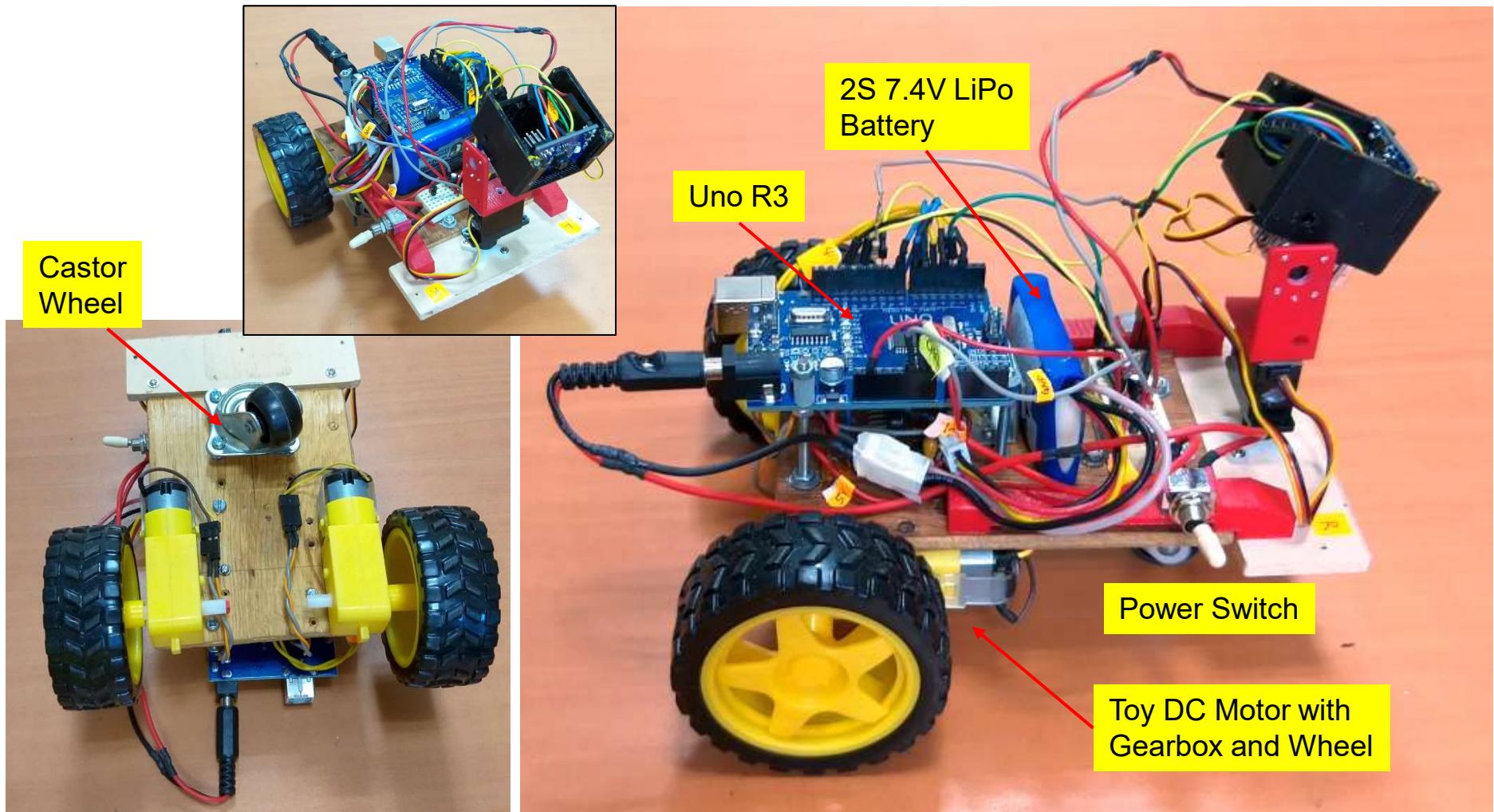
To 5V Power Supply (>1A output)
or Battery connected to 5V Voltage Regulator



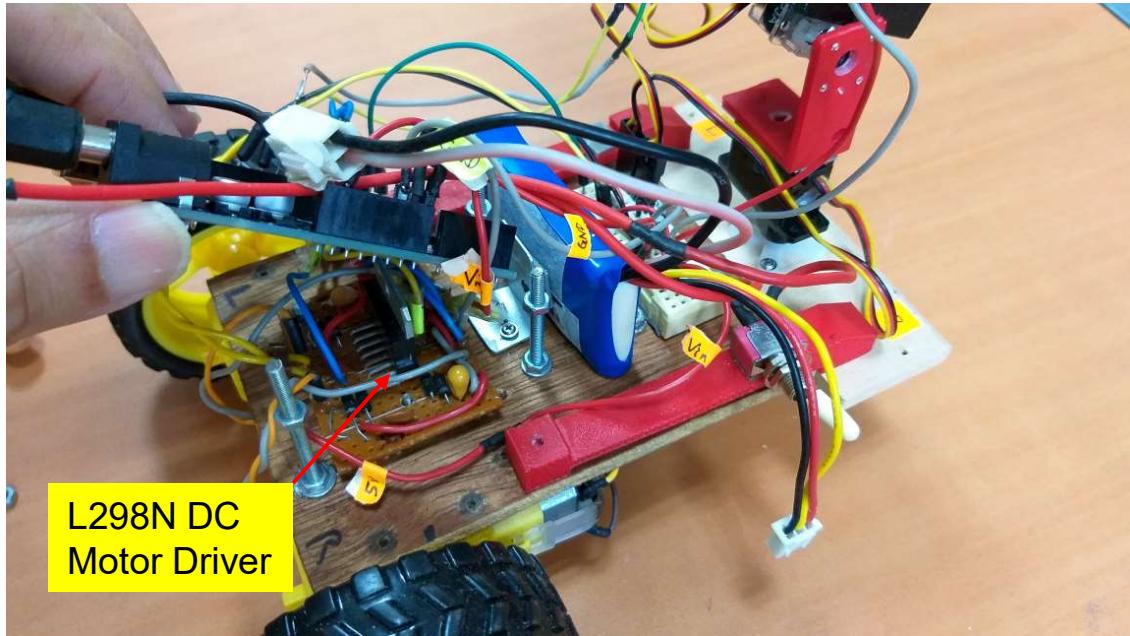
Example 3 - Mechanical Setup



Example 4 - Autonomous Navigation with Arduino Uno Based Robocar



Example 4 - Wiring Information of Robocar



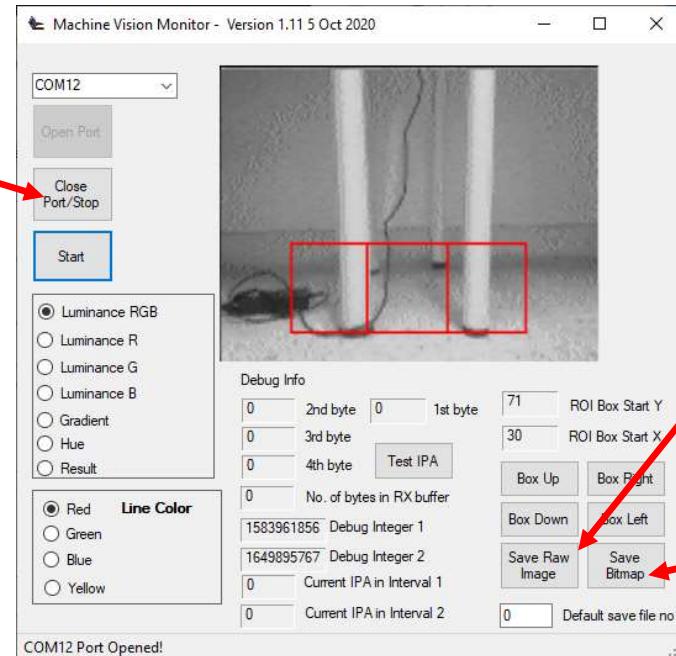
Arduino Uno R3

- Pin 2, 4 – Left DC motor direction control.
- Pin 7, 8 – Right DC motor direction control.
- Pin 5 – Left DC motor speed control.
- Pin 6 – Right DC motor speed control.
- Pin 10 – RX, to MVM TX pin.
- Pin 11 – TX, to MVM RX pin via 100Ω resistor.
- Optional: Pin 3 for azimuth servo motor control and Pin 12 for elevation servo motor control.

Saving the Image Frame onto Computer Hard Disk

- One can save the image displayed in the Machine Vision Monitor software onto hard disk. The image file can be saved as a raw binary file containing 2D array of luminance pixels or in Bitmap format.
- Scilab or MATLAB and python software can be used to read the file and display the image. This is useful when one is developing a new algorithm.
- Steps to do this are shown below.

1. Close the COM port to stop streaming image



2. Save the current display image as raw binary format on hard disk **OR**

3. Save the current display image as bitmap format on hard disk

Retrieving the Saved Raw Image using Scilab or MATLAB software

- The Scilab script to read the saved image file is also provided in the MVM_V1_5C folder. The script listing is shown below.

The screenshot shows the Scilab IDE interface. On the left is a code editor window titled "Basic_GrayScale_GrabImageCamera.sce" containing Scilab script code. A yellow callout box with a red arrow points to the line of code where the path to the image file is declared: "path = cd("C:\tmp");". The text in the callout box reads: "Make sure the path declaration matches your file path in the hard disk". On the right is a "Graphic window number 0" showing a grayscale image of two cylindrical objects, likely a sensor and a tube, with a pink arrow pointing from the script towards the window. The x-axis is labeled from 0 to 180 and the y-axis from 0 to 140.

```
Basic_GrayScale_GrabImageCamera.sce (C:\Users\User\Google Drive\Project\)
File Edit Format Options Window Execute ?
Basic_GrayScale_GrabImageCamera.sce (C:\Users\User\Google Drive\Project\)
*Basic_GrayScale_GrabImageCamera.sce [x]

1 // Author.....Fabian-Rung
2 // Last-modified...29-Oct-2016
3 // Purpose.....Basic code to load a 8-bit grayscale image from file
4
5 clear;
6 ImageWidth = 160; ..... // Set the size of the image. QQVGA.
7 ImageHeight = 120;
8 Hgraf = scf(); ..... // Get the handle to current graphic window.
9 path = cd("C:\tmp"); ..... // Path for the image file.
10 Hfile = mopen("testimage.txt",'rb'); ..... // Open a text file for reading
11 ..... // (don't skip 0xD, newline character)
12 M = zeros(ImageHeight+1,ImageWidth+1); ..... // Matrix to hold the gray scale image data
13 Mt = zeros(ImageWidth+1,ImageHeight+1); ..... // Another matrix also to hold the gray scale image data.
14 ..... // 't' indicate transpose.
15 for i=1:ImageHeight-1 ..... // ImageHeight-1 due to the last line is not
16 ..... // exported from the camera-monitor software
17 for j=1:ImageWidth
18 M(i,j) = mget(1,'c',Hfile); ..... // Read 1 pixel data, convert to double.
19 end
20 mget(1,'c',Hfile); ..... // Read the newline/carriage return character.
21 end
22
23 for i=1:ImageHeight-1 ..... // Transpose and flip the image so that
24 for j=1:ImageWidth ..... // it appear at the correct orientation.
25 Mt(j,ImageHeight-i) = M(i,j); ..... // The original format of Mt[] is:
26 ..... //-----> Column
27 end ..... //-
28 ..... //-
29 ..... //-
30 ..... //-----> V
31 ..... //-----> Rov
32
33 mclose(Hfile); ..... // Release file handle.
34
35 //Hgraf.color_map = graycolormap(127); ..... // Set current graphic window color map.
36 Hgraf.color_map = graycolormap(255); ..... // to gray scale, 127 or 255 levels.
37 row = 1:ImageWidth + 1;
38 col = 1:ImageHeight + 1;
39 grayplot(row,col,Mt); ..... // Plot the transpose and flip image.
40
```

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Retrieving the Saved Bitmap Image using Python

- The python script to read the saved bitmap file is also provided in the MVM_V1_5C folder. The script listing is shown below. Here the IDE Spyder is used.

A screenshot of the Spyder IDE (Python 3.7) showing a script named `MVM_LoadImageFile_Bmp.py`. A yellow callout box with a red arrow points from the text "Make sure the path declaration matches your file path in the hard disk" to the line `image = plt.imread('Img.bmp', format = 'BMP')`. The code reads a BMP image and displays it in grayscale. The image shows two cylindrical objects on a surface. The console output shows the command run and the resulting shape of the image.

```
# -*- coding: utf-8 -*-
"""
Created on Sat Jan 25 11:42:21 2020
@author: User
"""

import matplotlib.pyplot as plt

#Set the width and height of the image in pixels.
_imgwidth = 160
_imgheight = 120

#Load the BMP image, the image contains RGB channels, but here
#grayscale image so all R, G and B channels have similar value
#between 0-255.
print("Loading image...")
image = plt.imread('Img.bmp', format = 'BMP')

print("Shape of image is ", image.shape)
#Extract only 1 channel of the pixel, since all RGB channels have similar values.
image1 = image[0:_imgheight,0:_imgwidth,0]
plt.imshow(image1,cmap='gray')

In [1]: runfile('C:/Users/user/Google Drive/Projects/Robotics_EMBEDDED/Machine_Vision/Software/Python/MVM_LoadImageFile_Bmp.py', wdir='C:/Users/user/Google Drive/Projects/Robotics_EMBEDDED/Machine_Vision/Software/Python')
Loading image...
Shape of image is (120, 160, 3)

Figures now render in the Plots pane by default. To make them also appear inline in the Console, uncheck "Mute Inline Plotting" under the Plots pane options menu.

In [2]:
```