CmpE240
Section 1.

August 23rd (mon).

CmpE240
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Office Hours: M, W. 3:40-4:40 pm.

Advanced Microprocessor Systems
≠
Prototype System
with A CPU module

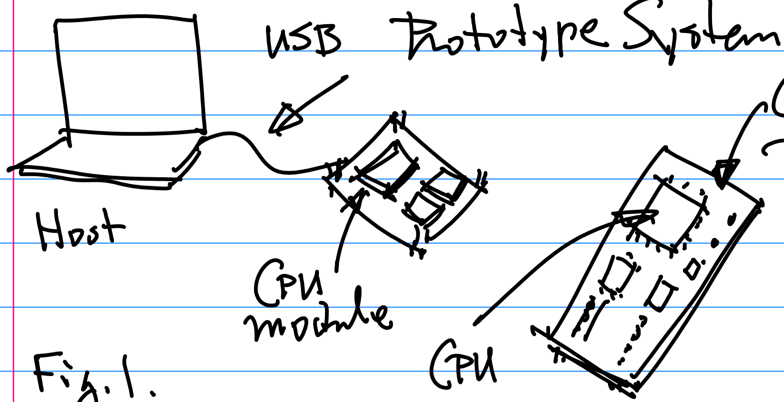


Fig. 1.

GPU (Graphics Processing Unit), Array of Processors, Machine Learning, AI. Autonomous Systems. Nvda Jetson Tx2.

Text Books, References

1° NXP LPC1769 CPU Datasheet
800+ pages

Homework: Down Load pdf. Before Next monday, Aug. 30th.

2. LPC1769 Schematics of the CPU module

3. Nvda Jetson NANO Datasheet on Tx2 (6 CPU + 256 GPU)
400+ pages.
(optional) 5% Bonus.

4. RISC-V. Open Source Architecture, A super set of ARM, FPGA, Verilog. SoC. +RTOS. (optional) +5%

A proposal (One Paragraph) By Sept. 1st (Wed). submit to my email;

Note: Buy LPC1769 CPU module.
digi-key.com,
mouser.com, etc.

Grading Policy & Projects

2 projects (phase I & II)

2D Graphics Processing Engine → 3D Graphics Processing Engine { a, b

2D Graphics Processing Engine 10% → 3D Graphics Processing Engine { a 3D shadow. 10% ; b Diffuse Reflection 10% } = 30pts, 30%.

Midterm: 30%, Final 40% (Comprehensive)

Option 1. (5%+) NVDA NANO
{ a. Likely Devices Drivers, O.S. C/C++, Python.
{ b. I/O Interface. "EdgeAI"
GPIO, SPI.

Option 2. (5%+) RISC-V Target SoC, FPGA Board,

Proposal (one paragraph), Submission By Sept 1st (Wed) via E-mail.

Policy ON Project Submission.

1°. Form 3-4 person Team.

2° No Source Code/Design material Can be Copied; All Course material has to be completed individually;

3° Late project, 10% per week;

August 25 (Wed)

Today's Topics:

1° Bill of material

Reference: github/hualili/Cmpe240/2018F

The B.O.M.

1. CPU module NXP LPC1769
↓
3rd Party (DigitalArt), module
To Distributors
Digikey.com, mouser.com
etc. Expecting Delays.
Lead Time over 8 weeks

Alternative { Re-use the previously used module
{ Team (4 person)

Each person will need to have his/her Board;

Option 1: NANO. a 4400+ pages Datasheet "firmware"

b Jetpack 4.3 or Higher (O.S. + Libs. + Packages)

Tool for Flashing the CPU module → (O.S. + Libs. + Packages)

c Coding in Both user & Kernel Spaces. → O.S. Distr.
Tool chain, Device Driver Debugging & Development;

Option 2. RISC-V, verilog, FPGA.

2. Power Regulator IC such as
7812, 7805 ... 1117

78xx

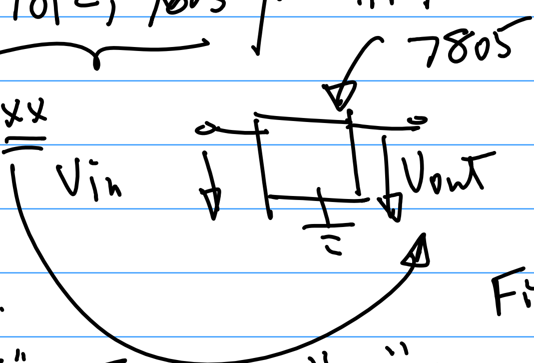
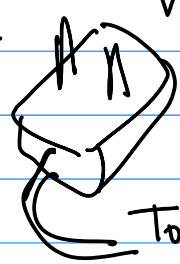


Fig.1.   Fig.

"05": 5.0 VDC, "12": 12VDC

Vin ≥ Vout + 1.5VDC ... (1)

DC Voltage Source   Wall mount Adaptor



a About 7805
1000 mW.

To Vin of 7805

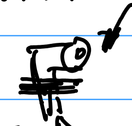
b 7.5VDC
OR
9.VDC @ 1000mW + 500 mW
= 1500mW

c Current ~~Reading~~ Rating

Why Do we use it?
→ Deploy the System.

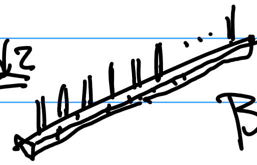
3. "Glue" Components / Resistors a

c LEDs. (Red, Green) for Debugging purpose, for PWR. (GPIO), $I_{LED} = 4 \sim 10mA$



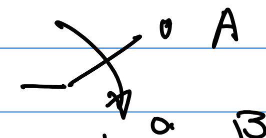
d Connectors.
d1 J1 for PWR Input 2 pin

d2



IN-Line pins.
Breakable
to mount CPU module.

e Switch. S/W1: to toggle PWR.
S/W2



f Wire for
Wire Wrapping / Soldering
28-30 AWG

4. Color LCD Display module
a SPI (Serial Peripheral Interface)
b Software Graphics (Driver) C/C++ Lib.
to Activate / Interface LCD.
MCU Xpresso (I.D.E.)
→ S.J. Lib.

5. "Other" thing.
RJ-45 Connector

Sept. 8 (W)

Topics: 1. "Hello, the world" program

Hardware Implementation: Prototype Board Build up: a. Wire Wrapping Board (LPC/NANO/Pie), b. Stand-offs.
External Power CKT (Red LED should be included)
GPP Testing CKT → Implementation/Design of the CKT.

NXP MCU Xpresso.

a. Installation of MCU Xpresso.

b. github/hualili/CMPE240/2018F LPC1769 patch, Import this patch to your Xpresso.

Architecture Aspects. CPU Architecture, M. Map.

https://github.com/hualili/CMPE240-Adv-Microprocessors/blob/master/1769%20patch.zip

Note: Wire Wrapping Board with "Stand-off's" (Legs)

Homework: Next Show-and-tell Wire Wrapping Board;

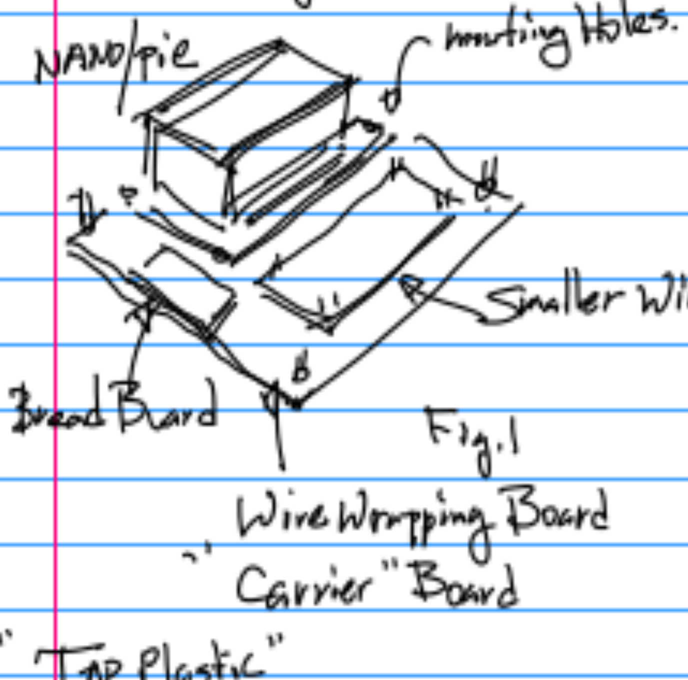


Fig. 1

"TAP Plastic"

On the Board: a. Stand-offs.

b. Connector(s) for External PWR → PWR IC (7805), with Red LED

CPU Architecture:

1. 32-bit Architecture

CPU Architecture

a. ALU 32 bit
Arithmetic/Logic Unit.

b. "Register File",
A Bank of Registers. 32 bits

GPRs
General Purpose Registers
Those Registers that can participate Any meaningful

Arithmetic/Logic Operations. To Define/Determine the Behavior of Peripheral Controllers.

Special purpose Registers.

SPRs 32 bit ← Naming Convension: 6 letters

Common Design for SPRS:

1° Control Register(s) per Each Peripheral Controller

CON ← Root (3 Letters)

2° Data Register, DAT

3° Pull-up/Down (Electric Characteristics)

C. Data Bus, "Bi-Directional" 32 bits

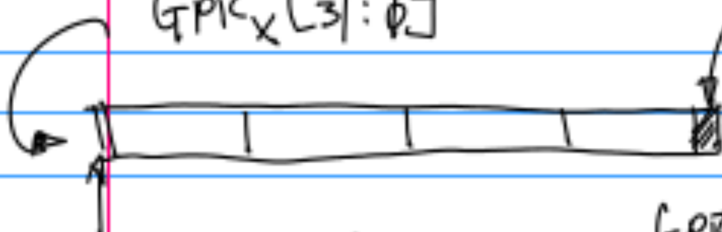
Information Flowing Both Directions.

Address, "Uni-directional" from CPU to the Outside. 32 bits

Notation: 32 bit Register

$GPR_x[31:0]$

LSB



$GPR_x[31]$ Fig.2 $GPR_x[0]$

For Address Bus, $Addr[31:0] =$

$a_{31} a_{30} \cdots a_1 a_0$

Note: "Little Endian"

LSB is at 0,

2. "Byte Addressable" machine

is a machine whose Smallest memory cell with an unique address is a single Byte.

Total memory:

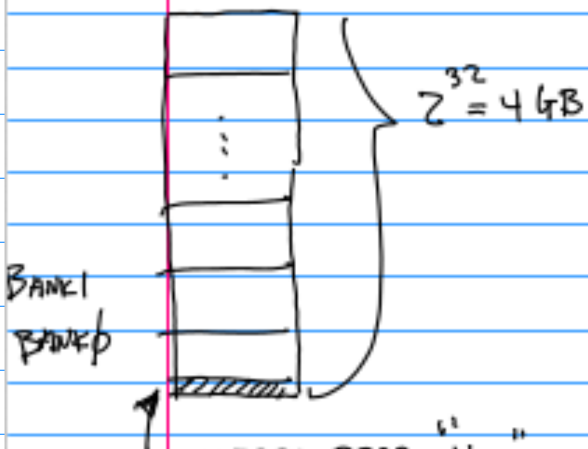
$2^{32} = 2^2 \cdot 2^{10} \cdot 2^{10} \cdot 2^{10}$ ...(1)

$2^{10} = 1K$, ...(2) $2^{20} = 2^{10} \cdot 2^{10} = 1M$ ...(3)

$2^{30} = 1M \cdot 1K = 1$ giga ...(4)

$2^{32} = 2^2 \cdot 2^{30} = 4$ GB

3. memory map.



0X0000_0000 "Hex" Fig3.

32 bits for the Address
8 bits for this memory

a. PWR-up Address:

CPU will fetch the 1st Executable from this memory Location.

→ 0X0000_0000 for ARM

Note: for x86, the PWR-up Address: 0XFFFF_FFFϕ

b. BANKS. $2^{32}/8 = 2^{32}/2^3$

$= 2^{29} = 2^9 \cdot 2^{20} = 512MB$

How many Bits Do we need to uniquely define Each Bank?

3 bits → $a_{31}\, a_{30}\, a_{29}$

Define Starting Addr. of Each Bank:

a_{31}	a_{30}	a_{29}	a_{28}	
0	0	0		BANKϕ
0	0	1		BANK1
0	1	0		BANK2
				⋮
1	1	1		BANK7

Write ~~the Address~~ for Each Bank. "Starting" (32 bit)

For BANKϕ: 0X0000_0000
BANK1: 0X2000_0000
" 2: 0X4000_0000

Example: CPU Datasheet pp. 13.

GPIO 0X2009_C000

a. Collection of SPRs are mapped to here, e.g. Addr. for SPRs are mapped to here

b Which memory Bank holds this GPIO? BANK1 whose starting Address is 0X2009_C000

Sept 13 (Mon)

1° Today's Topics: Integrate Architecture Discussion with Software Development IDE. Objectives: To write first C program for testing purpose

Example: Starting from CPU memory map → 8 BANKS
P913

↓

Populate 8 BANKS

1st 256 KB Flash
0x0000 0000,

Rest of the Devices, such as mem. Controller, Peripheral Controller

↓

Peripheral controllers on the mem map. → SSP1 (SPI) Peripheral Controller
APB0 & APB

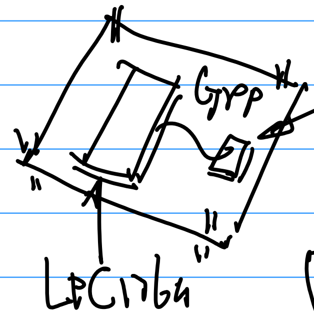
↓

S.P.R.s. ← 0x4003_0000 Size 4000

"CON" 3 Letter

b Definition: Are those SPRs for the init & Config of a Peripheral Controller.

Example. GPP



Output Testing CKT
Turn on/off LED
pin 16

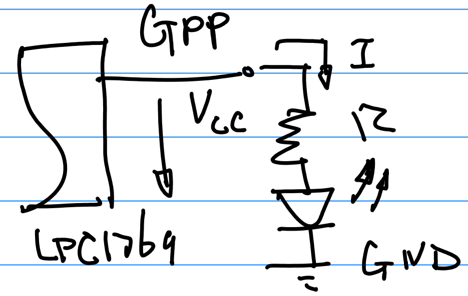


Fig 1.

$$V_{CC} = IR + V_{LED} \quad \cdots (1)$$

$I \simeq 8\,mA$, → $R \simeq 200$
$300\,\Omega$

$V_{LED} \simeq 1.8\,VDC$

GPPCON

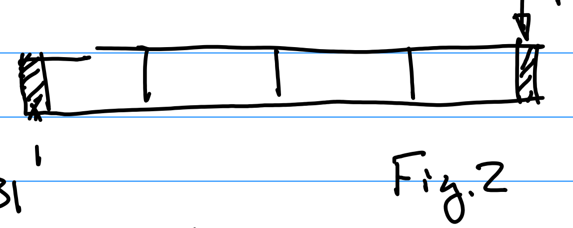


Fig. 2

Where to find GPPCON on the memory map? → Addr. of GPPCON is described on CPU Datasheet.

a Naming conversion : Prefix + Root + Postscript
3 Letters 3 Letters 3 letter

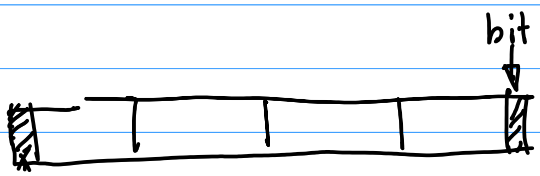
"SPICON" → "SPICON001" for Example → C Compiler / C Code

CmpE240

2^{32} Possible Combinations of Init & Config. Feature

GPP (General Purpose Port)
32 pins, Define pin 16 as output pin.

we have to use the following init + Config pattern:



0X F200_FF00

To make pin 16 as an output.

First, "port" the Architecture Compiler to the target

#define GPPCON — Addr. from the memory

then, Copy 0XF200_FF00 into this memory Location.

Homework: Show + Tell
By Next Week Installation of MCU + Import LPC1769.

Sept 15 (W) Architecture
Today's Topics: GPIO Design

Reference: 1° 2021F-105 ~ 10 ON GPIO

C-Code for Init & Config is required

Example: Make GPP for Input & Output Testing.

- Hardware
- Software
  - NXP MCU Xpresso
  - Import GPP Sample ".zip"

Design Step 1. Identify/select GPP/GPP-pins
P0.2, P0.3
(Connector → CPU Datasheet → Selection)

Step 2. Define P0.2 Output, P0.3 As Input.
Design the Hardware

Step 3. SPRs (Special Purpose Registers) for the GPP Peripheral Controller

Connector J2-21 ... → CPU pin P0.2 P0.3 → CPU Data Sheet → SPRs

Note: SPRs commonly defined/utilized are

GPx CON

where x = A, B, C, D, ...

GPFCON

GPFDAT (32 bits → 32 pins)

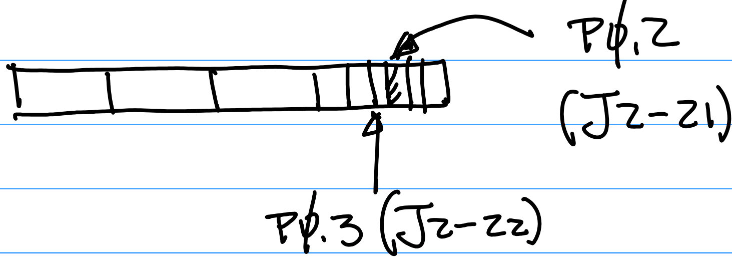
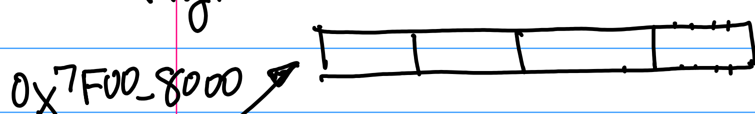


Fig. 1

Find Table on CPU Datasheet to to define P0.2 output, P0.3 as input.

Example, Samsung Arm11 Datasheet pp312

Fig 2



Question: Define Binary Pattern for Find GPA CON to make its pin 2 as an output?

Sept. 20 (mon) Topics: 1° GPIO SPRs, IDE, Sample Code; 2° 2D G.E.

Example: git (class) 2021F-105-GPP...

1. Naming Convention in C Compiler

```
LPC_GPIO0->FIODIR

LPC_GPIO0->FIOSET

LPC_GPIO0->FIOCLR
```

Target CPU (Family)

Peripheral Controller

Special Purpose Register

From the Example, git, 2021F-105

From CPU datasheet, GPIOs are configured using the following registers:
1. Power: always enabled.
2. Pins: See Section 8.3 for GPIO pins and their modes.
3. Wake-up: GPIO ports 0 and 2 can be used for wake-up if needed, see (Section 4.8.8).
4. Interrupts: Enable GPIO interrupts in IO0/2IntEnR (Table 115) or IO0/2IntEnF (Table 117). Interrupts are enabled in the NVIC using the appropriate Interrupt Set Enable register.

Chapter 9, pp 129

PINSEL[5:4] for P0.2

PINSEL[5:4] = 00 for GPP P0.2

PINSEL[5:4] = 01 for UART Tx

pp 133 FIODIR Example.

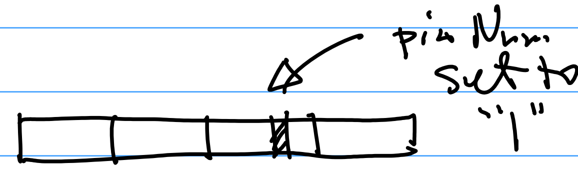
P0.3 output, Find SPR?

Define bit Value for the Output

Table Look up.

FIO0DIR0

FIOSET, CPU Datasheet Look up.




```
void GPIOinitOut(uint8_t portNum,
uint32_t pinNum)
{
if (portNum == 0)
{
LPC_GPIO0->FIODIR |= (1 <<
pinNum);
}
else if (portNum == 1)
{
LPC_GPIO1->FIODIR |= (1 <<
pinNum);
```

1 << pinNum // Set Direction to pinNum

Logic Operation { "|=" Bitwise "OR"; "&=" ?

Example: Set Pin

```
void setGPIO(uint8_t portNum,
uint32_t pinNum)
{
if (portNum == 0)
{
LPC_GPIO0->FIOSET = (1 <<
pinNum);    //1 as output
printf("Pin 0.%d has been set.\
n",pinNum);
}
```

Turn ON LED (Output "1")

$\vec{P}(x,y)$ Notation

$\vec{P}(x,y) = (x,y)$

$\vec{P_i} \to \vec{P_i}(x_i, y_i) \to (x_i, y_i)$

point(s), Vertex, Vectors

$\vec{P_i} = \vec{P_i}(x_i, y_i) = (x_i, y_i)$

Example: Clear the pin

```
void clearGPIO(uint8_t portNum, uint32_t
pinNum)
{
if (portNum == 0)
{
LPC_GPIO0->FIOCLR = (1 << pinNum);
printf("Pin 0.%d has been cleared.\n",
pinNum);
}
```

Formulation for a straight line

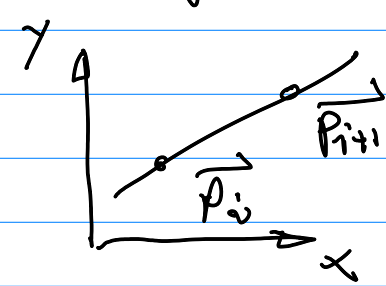


Fig. 2

Now, 2D Vector Graphics

$\vec{P}(x,y)$ a point, vertex, a vector

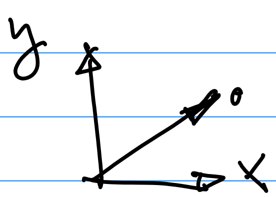


Fig. 1

Sept. 22 (W)

Graphics Engine
- 2D G.E.
- 3D G.E.
- Graphics Display Driver (Hardware)

Consider 2D G.E.

- Theory / Formulation
- Algorithms / Software
- Implementation / Hardware Prototyping

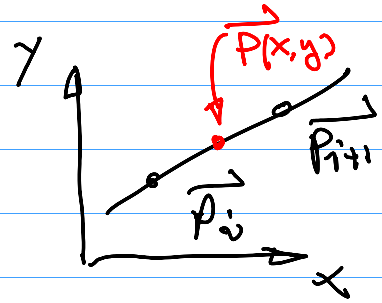


Fig.2

Note: Need 2 points $\overrightarrow{P_i}$, $\overrightarrow{P_{i+1}}$ to define a line

Let's define a direction vector

$$\vec{d}(x_d, y_d) = \overrightarrow{P_{i+1}} - \overrightarrow{P_i}$$

$$= \overrightarrow{P_{i+1}}(x_{i+1}, y_{i+1}) - \overrightarrow{P_i}(x_i, y_i) \quad \ldots (1)$$

Example: Suppose given a starting pt. $\overrightarrow{P_i}(x_i, y_i) = (3, 4.5)$

$\overrightarrow{P_{i+1}}(x_{i+1}, y_{i+1}) = (5.5, 6.3)$

Find direction vector ?

Sol. By Eqn(1), we have

$$\vec{d}(x_d, y_d) = \overrightarrow{P_{i+1}} - \overrightarrow{P_i}$$

$$= ((x_{i+1}, y_{i+1}) - (x_i, y_i))$$

$$= (x_{i+1} - x_i, y_{i+1} - y_i)$$

Sub. the given condition into the directional vector, we have

$$\vec{d} = ((5.5-3), (6.3-4.5))$$

$$= (2.5, 1.8) //$$

In C/C++ Coding, we use the following Equation, From Eqn (1), we have

$$\vec{d}(x_d, y_d) = (x_{i+1} - x_i, y_{i+1} - y_i) \quad \ldots (1b)$$

OR,

$$\begin{cases} x_d = x_{i+1} - x_i \\ y_d = y_{i+1} - y_i \end{cases} \quad \ldots (1c)$$

```
direction_x = x[i+1]-x[i];
direction_y = y[i+1]-y[i];
```

Let's uniquely define a line

Need a pt $\overrightarrow{P_i}$, or $\overrightarrow{P_{i+1}}$; and directional vector

$$\vec{P}(x,y) = \overrightarrow{P_i} + \lambda(\overrightarrow{P_{i+1}} - \overrightarrow{P_i}) \quad \ldots (2)$$

Starting pt   scalar   Directional vector

Let

$\lambda = 0$, then $\vec{P}(x,y) = \vec{P_i}(x_i, y_i)$ Starting pt.

$\lambda = 1$, then $\vec{P}(x,y) = \vec{P}_{i+1}(x_{i+1}, y_{i+1})$

$0 < \lambda < 1$, Any Point $\vec{P}(x,y)$ Between $\vec{P_i}$ and $\vec{P}_{i+1}$.

$\lambda > 1$ Any pt. $\vec{P}(x,y)$ Beyond $\vec{P}_{i+1}(x_{i+1}, y_{i+1})$.

$\lambda < 0$, Any point Beneath $\vec{P_i}(x_i, y_i)$.

Fig 3a

Fig. 3b

Screen Saver Design for LPC 2D G.E.

Rotating Squares And Trees.

Example: Design A Rotating Squares

Step 1. Define 4 vectors/pts

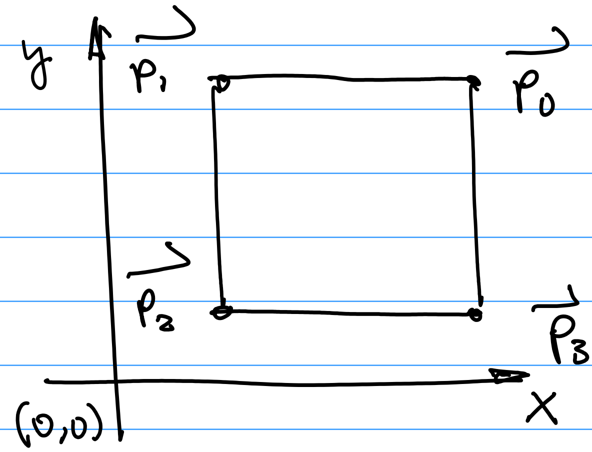
$\vec{P_i}$, $i = 0, 1, 2, 3$

$\vec{P_0}(x_0, y_0) = (60, 60)$, $\vec{P_1}(x_1, y_1) = (10, 60)$

$\vec{P_2}(x_2, y_2) = (10, 10)$, $\vec{P_3}(x_3, y_3) = (60, 10)$

Based on the physical display device

Fig 4



Note: Be sure to Arrange $\vec{P_i}$ in a Counter Clockwise direction. (for Later 3D Hidden Line/Surface Removal)

Step 2. use

$$\vec{P}(x,y) = \vec{P_i}(x_i, y_i) + \lambda\left(\vec{P}_{i+1}(x_{i+1}, y_{i+1}) - \vec{P_i}(x_i, y_i)\right) \quad \ldots (1)$$

Prepare: LCD Soldering ON the Wire-Wrapping Board, Import Single line Drawing project.

Sept. 27 (Mon)

Homework, 2pts. Due 1 week from Today

Topics: 2D Screen Saver Design

Requirements:

a. Build LCD Hardware Interface;

b. Import Sample code from github/hualili/Cmpe240 2018S-to-LCD-DrawLine.

Modify the code to Display 2D Rotating Squares Using 2D Vector equation;

Submission:

c. Project (Zip, Exported)

d. Screenphoto

Submission to CANVAS.

Announcement:

Office Hours — Tue 3:40-4:40pm. Due to SJSU off-Campus Program.

Example: Continued from pp15.

Step 2. Use Vector Equation to find 4 pts

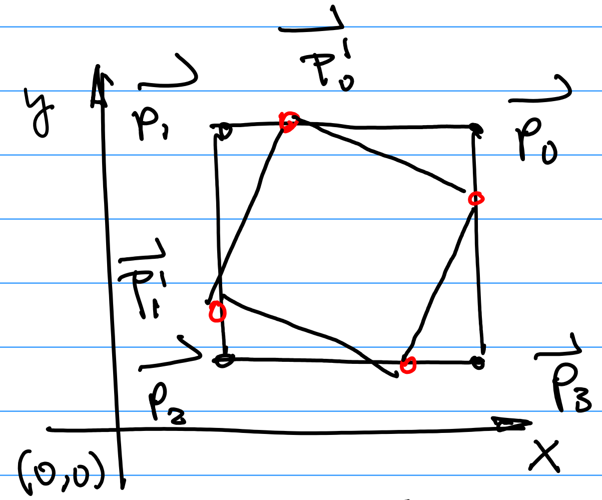


Fig. 1

Let $\lambda = 0.8$, for line 1 ($\vec{P_0}$ and $\vec{P_1}$): Eqn(1), pp15.

Calculate a point $\vec{P'_0}$

Superscript: the Level of iteration;

for line 2, 3, and 4, we do the Same.

line 2 ($\vec{P_1}$ & $\vec{P_2}$), line 3 ($\vec{P_2}$ & $\vec{P_3}$)

line 4 ($\vec{P_3}$ & $\vec{P_0}$)

In Homework, level ≥ 10.

Coding:

$$\begin{cases} x = x_i + \lambda (x_{i+1} - x_i) & \ldots (1a) \\ y = y_i + \lambda (y_{i+1} - y_i) & \ldots (1b) \end{cases}$$

CmpE240

Hardware Implementation of LCD Interface.

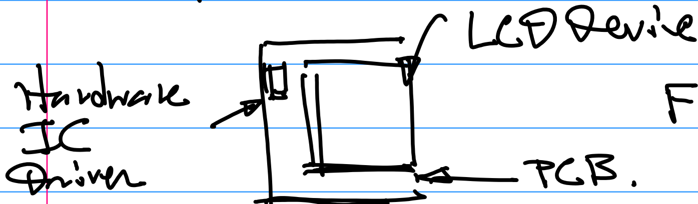
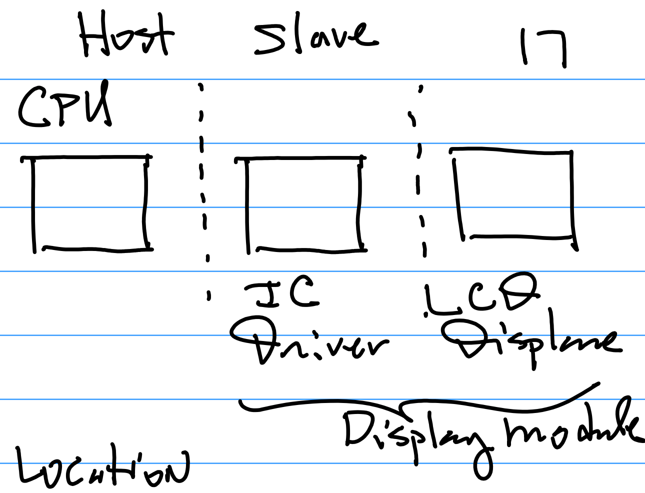


Fig.2



a. To Drive LCD Display.
   To Display a pixel { (x, y) Location
   I(x, y) Intensity, and color
b. To provide feedBack and Interface to CPU module.
   (SPI Interface)

To Establish Interface, SPI (Serial Peripheral Interface)

Hardware pins of SPI : 3+1.

- MOSI (Master Output Slave Input)
- MISO (Master Input Slave Output)
- SCK (SPI clock)
- SSELx (SPI Enable)

Now, Consider the I/F to LCD module.

Ref: github/hualili/cmpe240 2018S-9-SPILCD ...

SCH

LPC-1769	
Label	Pin
MOSI ✓	P 0.18
MISO ✓	P0.17
SCK ✓	P0.15
CS Enable	P0.16
GPIO-DC (Data / command)	P0.21
GPIO-Reset	P0.22
3.3V	
GND	

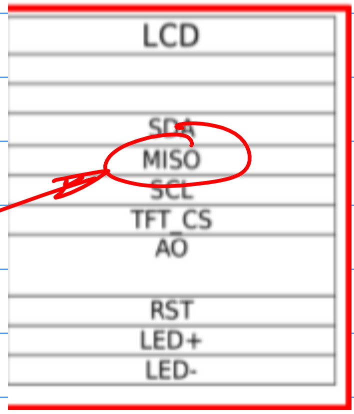
Fig.3.

Note: Mark the Direction of the Signal

a Identify all pins on CPU for SPI I/F;

b Identify all pins on LCD for SPI I/F, Correct matching the host/master and Slave.

Labels from the LCD Display.



"SO"

SPI pins: SDA, MOSI.
MISO
⋮

Typo: Change MISO on LCD to SO.
etc.

Note: In Addition to SPI interface, Identify Command / Data Toggle Control pin, the Label should be C/$\overline{D}$ Depending on the Signal Level, the Communication From CPU to LCD is interpreted by LCD either as a Command or Data.

Now, Software Part
github/hualili/Cmpe240
2018S-10-DrawLine

Identify module @ Line 285
Parameters (x_0, y_0), (x_1, y_1) and Color
P_0 or P_i — P_1 or P_{i+1}

Example: Draw A Line Code
1. Color Definition. hex Digits
2 hexs for Each primitive color
(red, green, blue)

Match to Eqn (14) & (16) to Build a Square one Line at time.

Primitive Colors: r, g, b

2 hex Digits: min. 0, max: 255

$2 \text{ hex} \Rightarrow 8 \text{ bit} \Rightarrow 2^8 = 256$

Sept. 29 (Wed)
Project 1. (10 pts) Due Oct. 18th Before the Class.
Requirements:
1° All work including prototype Board, Programs, Report

2° Bit Arrangement for the primitive Colors: RGB = (2 hex)(2 hex)(2 hex)

However Team work is encouraged.

2° Implement Hardware LCD Display. a Rotation of sets of Squares, b Create trees to forest; c 3D World Coordinate System Visualization;

Submission:

1° Formal written Requirements

Rubrics will be posted on Line.

2° Submission on CANVAS.

3° Source code/Binary have to Exported project, in Zip.

4° Project Report (5 pages) in IEEE format;

5° 5 Seconds video

a Entire System Setting, Host + Prototype Board.

b Screen of the Animated Display; c Show the Prototype Board.

2D Transforms

Mathematical Formulation

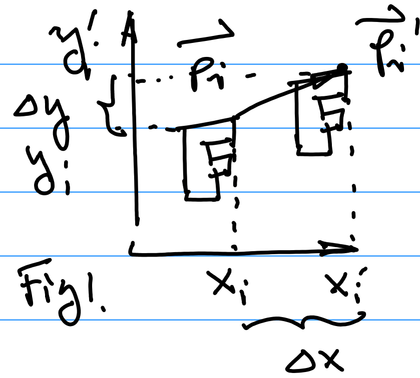


Fig 1.

Given 2D pattern $\{\vec{P}_i(x_i, y_i) \mid i = 0, 1, \ldots N-1\}$

Establish Translation Matrix T.

$\vec{P}_i(x_i, y_i)$ Before ; $\vec{P}'_i(x'_i, y'_i)$ After

$$\underset{\text{After}}{x'_i} \overset{?}{=} \underset{\text{Before}}{x_i} + \Delta x \quad \ldots (1)$$

Similarly

$$y'_i = y_i + \Delta y \quad \ldots (2)$$

After Before

$$\begin{pmatrix} x'_i \\ y'_i \\ 1 \end{pmatrix} = \begin{pmatrix} 1 & 0 & \Delta x \\ 0 & 1 & \Delta y \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} x_i \\ y_i \\ 1 \end{pmatrix} \quad \ldots (3)$$

Let's consider Rotation

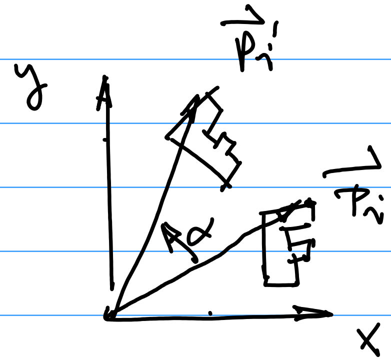


Fig. 2

Note: Counter Clockwise Rotation
"Positive" Angle α

After Before

$$\begin{pmatrix} x_i' \\ y_i' \\ 1 \end{pmatrix} = \begin{pmatrix} \cos\alpha & -\sin\alpha & 0 \\ \sin\alpha & \cos\alpha & 0 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} x_i \\ y_i \\ 1 \end{pmatrix} \quad \ldots(4)$$

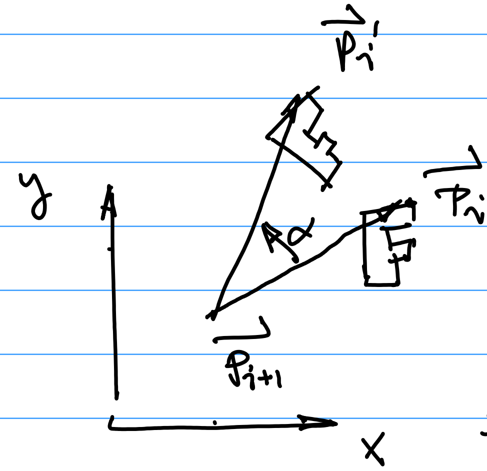


Fig 4.

Note: for Rotations in Fig 4, we will have to conduct

Pre-processing to Translate the reference point $\vec{P}_{i+1}$ to origin (0,0)

Then, perform Rotation;

Finally, post processing. Translate the rotated pattern Back to its Original Location

After Before

$$\begin{pmatrix} x_i' \\ y_i' \\ 1 \end{pmatrix} = T^{-1} R T \begin{pmatrix} x_i \\ y_i \\ 1 \end{pmatrix} \quad \ldots(6)$$

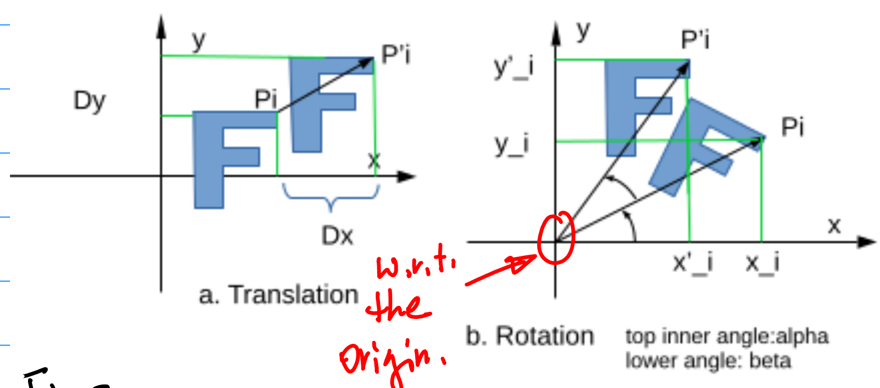


Fig.3

From Eqn (4)

$$\begin{cases} x_i' = x_i \cos\alpha - y_i \sin\alpha & \ldots(5a) \\ y_i' = x_i \sin\alpha + y_i \cos\alpha & \ldots(5b) \end{cases}$$

where

$$T^{-1} = \begin{pmatrix} 1 & 0 & -\Delta X \\ 0 & 1 & -\Delta Y \\ 0 & 0 & 1 \end{pmatrix} \quad \ldots(7)$$

Fig.5

Example: Use 2D Transforms to Create Trees shown Above

Step 1. Define Initial Pair of Points to give a tree trunk.

$\vec{P_0}(x_0, y_0)$, $\vec{P_1}(x_1, y_1)$

$\vec{P_0}(x_0, y_0) = (10,10)$, $\vec{P_1}(x_1, y_1) = (10,20)$

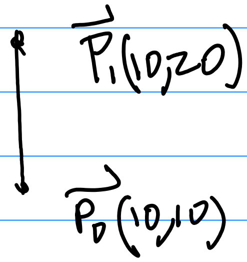


Fig.6

Step 2. Use Vector Eqn to Create next Level main/major Branch $\vec{P_1'}(x_1', y_1')$ as in Fig.

$$\vec{P_1'}(x_1', y_1') = P_0(x_0, y_0) + \lambda(\vec{P_1}(x_1, y_1) - \vec{P_0}(x_0, y_0))$$

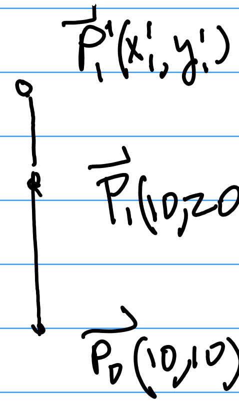


Fig.7

make $\lambda = 0.8$.

Step 3. Rotation of $\vec{P_1'}$ Counter clockwise to Create Left Branch.

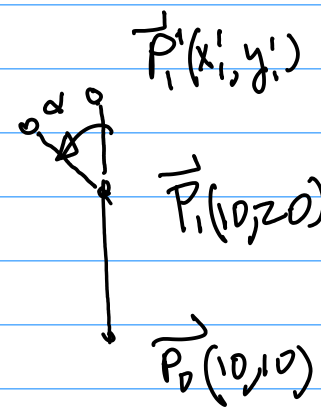


Fig.8

Oct.4 (Monday)

Topics: 1° 2D Example for trees

2° Virtual Display v.s. physical Display, Implementation

Example: Continued from Step 3.

First, Preprocess

CmpEato

$$T=\begin{pmatrix}1 & 0 & DX\\ 0 & 1 & DY\\ 0 & 0 & 1\end{pmatrix}=\begin{pmatrix}1 & 0 & -10\\ 0 & 1 & -20\\ 0 & 0 & 1\end{pmatrix}$$

$DX=-10$
$DY=-20$

Next Rotation,

$$R=\begin{pmatrix}\cos\alpha & -\sin\alpha & 0\\ \sin\alpha & \cos\alpha & 0\\ 0 & 0 & 1\end{pmatrix},\quad \alpha=30.$$

Post-Processing:

$$T^{-1}=\begin{pmatrix}1 & 0 & -DX\\ 0 & 1 & -DY\\ 0 & 0 & 1\end{pmatrix}=\begin{pmatrix}1 & 0 & 10\\ 0 & 1 & 20\\ 0 & 0 & 1\end{pmatrix}$$

From Eqn(5)-(7):

$$\begin{pmatrix}1 & 0 & 10\\ 0 & 1 & 20\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}\cos\alpha & -\sin\alpha & 0\\ \sin\alpha & \cos\alpha & 0\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}1 & 0 & -10\\ 0 & 1 & -20\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}10\\ 20\\ 1\end{pmatrix}$$

$$=\begin{pmatrix}1 & 0 & 10\\ 0 & 1 & 20\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}\cos\alpha & -\sin\alpha & 0\\ \sin\alpha & \cos\alpha & 0\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}0\\ 0\\ 1\end{pmatrix}$$

$$=\begin{pmatrix}1 & 0 & 10\\ 0 & 1 & 20\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}0\\ 0\\ 1\end{pmatrix}=\begin{pmatrix}10\\ 20\\ 1\end{pmatrix}$$

Then for $\vec{P_1}(10,36)$

Now, Similarly,

$$\begin{pmatrix}1 & 0 & -10\\ 0 & 1 & -20\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}10\\ 36\\ 1\end{pmatrix}$$

$$=\begin{pmatrix}1 & 0 & 10\\ 0 & 1 & 20\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}\cos\alpha & -\sin\alpha & 0\\ \sin\alpha & \cos\alpha & 0\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}0\\ 16\\ 1\end{pmatrix}$$

$$=\begin{pmatrix}1 & 0 & 10\\ 0 & 1 & 20\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}-16\sin\alpha\\ 16\cos\alpha\\ 1\end{pmatrix}$$

$$=\begin{pmatrix}-16\sin\alpha+10\\ 16\cos\alpha+20\\ 1\end{pmatrix}$$

New x

New y

Summary: Put Together Eqn (6) to form the Rotation Algorithm.

$$T^{-1}RT=$$

$$\begin{pmatrix}1 & 0 & -DX\\ 0 & 1 & -DY\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}\cos\alpha & -\sin\alpha & 0\\ \sin\alpha & \cos\alpha & 0\\ 0 & 0 & 1\end{pmatrix}\begin{pmatrix}1 & 0 & DX\\ 0 & 1 & DY\\ 0 & 0 & 1\end{pmatrix}$$

$$= \begin{pmatrix} 1 & 0 & -\Delta X \\ 0 & 1 & -\Delta Y \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} \cos\alpha & -\sin\alpha & \Delta X\cos\alpha - \Delta Y \sin\alpha \\ \sin\alpha & \cos\alpha & \Delta X \sin\alpha + \Delta Y \cos\alpha \\ 0 & 0 & 1 \end{pmatrix}$$

$$= \begin{pmatrix} \cos\alpha & -\sin\alpha & \Delta X\cos\alpha - \Delta Y \sin\alpha - \Delta X \\ \sin\alpha & \cos\alpha & \Delta X \sin\alpha + \Delta Y \cos\alpha - \Delta Y \\ 0 & 0 & 1 \end{pmatrix}$$

Therefore

$$\begin{pmatrix} x_i' \\ y_i' \\ 1 \end{pmatrix} = \begin{pmatrix} \cos\alpha & -\sin\alpha & \Delta X\cos\alpha - \Delta Y \sin\alpha - \Delta X \\ \sin\alpha & \cos\alpha & \Delta X \sin\alpha + \Delta Y \cos\alpha - \Delta Y \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} x_i \\ y_i \\ 1 \end{pmatrix}$$

C/C++ Implementation

$$\begin{cases} x_i' = \cos\alpha \cdot x_i - \sin\alpha \cdot y_i + \Delta X \cos\alpha - \Delta Y \sin\alpha - \Delta X \\ y_i' = \sin\alpha\, x_i + \cos\alpha\, y_i + \Delta X \sin\alpha + \Delta Y \cos\alpha - \Delta Y \end{cases} \quad \ldots (6*)$$

Suppose LCD Resolution is 120×100

120: Number of Pixels/Row

100: Rows.

X: Left To Right 0, 1, 2, …, M-1

y: (Top down) 0, 1, 2, …, N-1

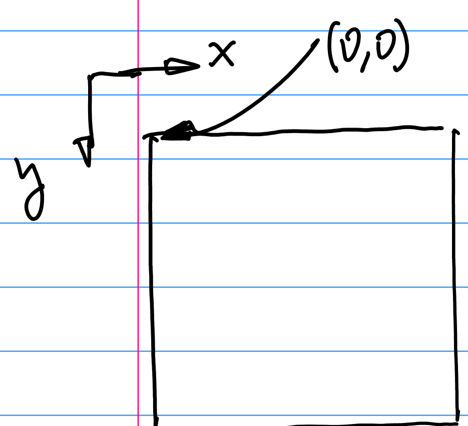
Limitation:

1° No Negative Value in the System.

2° Tied to the physical Device with Resolution M×N.

3° Not Portable

Physical Display Coordinate V.S. Virtual Display Coordinate



a. Origin (0,0) at Top left hand corner

b. Resolution is M×N

M×N

M: No. of Pixels/Row

N: No. of Rows/frame

Fig.1

Now, virtual Display Coordinate

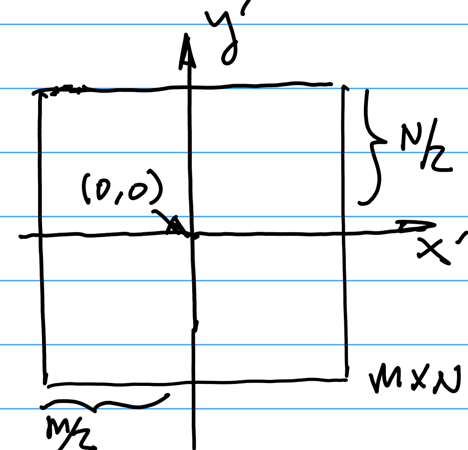


Fig.2

Set (0,0) at the center of the display device.

Transform physical Display to

Virtual Display.

$$\begin{cases} x = x' + M/2 & \ldots (1) \\ y = -y' + N/2 & \ldots (2) \end{cases}$$

Note: Verify Eqn (1) & (2).

How to use Eqn (1) and (2).

Conduct Computation in Virtual coordinate (x', y'), make sure to Scale the result in $x' \in [-\frac{M}{2}, \frac{M}{2}]$ M Total No. of Col.

$y' \in [-\frac{N}{2}, \frac{N}{2}]$, N: Total No. of Rows.

Then, use Eqn (1) & (2) map to your physical display.

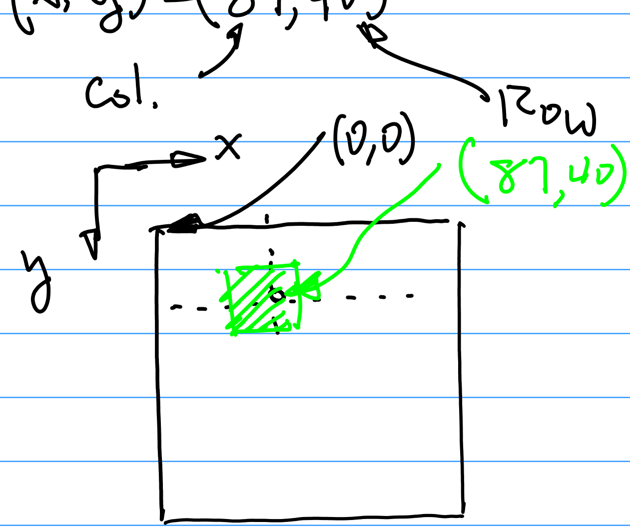
Homework (Due 1 week Oct. 11, Monday) Virtual to physical Transform.

1° Write C code to Realize Eqn (1) & (2).

2° Prompt the user for input (x, y) value in Virtual coordinate System,

Then you compute Eqn (1) & (2) to find physical display Coordinate, plot (Draw) 5x5 Patch with its center pixel Equal to the Computation Result.

Example: Computation Result $(x, y) = (87, 40)$



3D Graphics Processing Engine Introduction: World Coordinate System

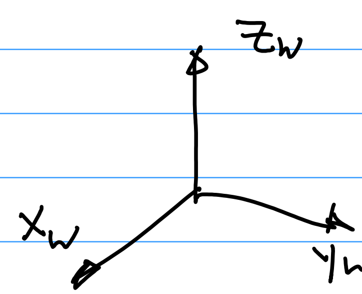


Fig. 1

Oct 6th (Wed)

Topics: 1° Transformation pipeline

Note:
1° Office Hour Update
Posted on Git;
2° Handout on GPIO Code, please read it, understand the code. It is required.

Continued ON 3D World-Coordinate System. X_w-Y_w-Z_w, Subscript "w" for world coordinate System.

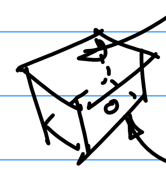
a Right Hand System.

X_w cross product with Y_w to produce Z_w.

b Everything is defined in the World Coordinate System.

Virtual Camera $\vec{E}(x_e, y_e, z_e)$ "Eye" location.

a "pin-Hole" model.
Diameter of the Lens ("Hole") is very small, $d \ll S$.
Enclose to form A virtual Camera.



$\vec{EO}$ fixation direction of the Virtual Camera

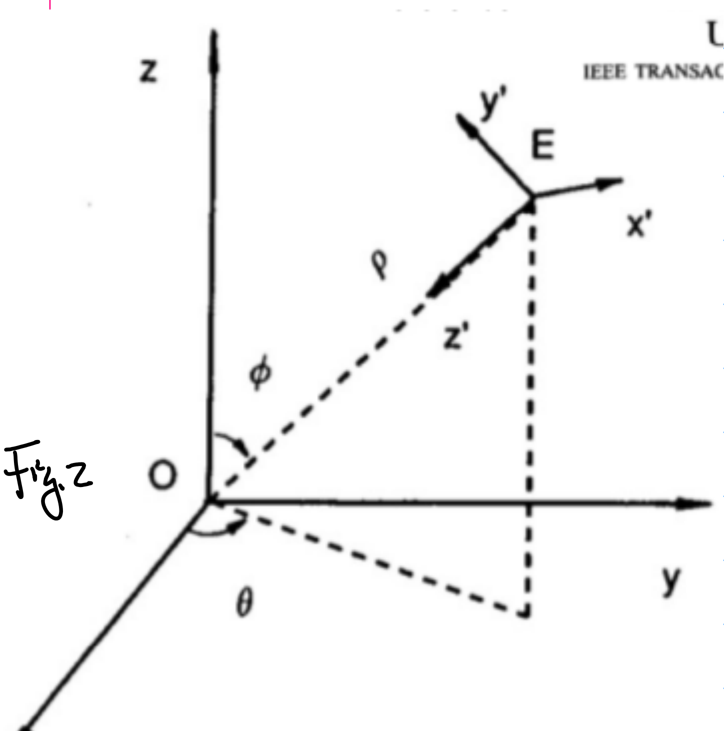
Note: This is just ONE formulation Among other 3 Additional Possible Formulations

1° Viewer Coordinate System X_e-Y_e-Z_e, Sub "e" for "Eye"/Camera Location;

2° Left Hand System.

Relationship B/W X_w-Y_w-Z_w and X_e-Y_e-Z_e Systems to Allow the Definition of Viewing 3D Objects in a different perspective.

Fig. 2



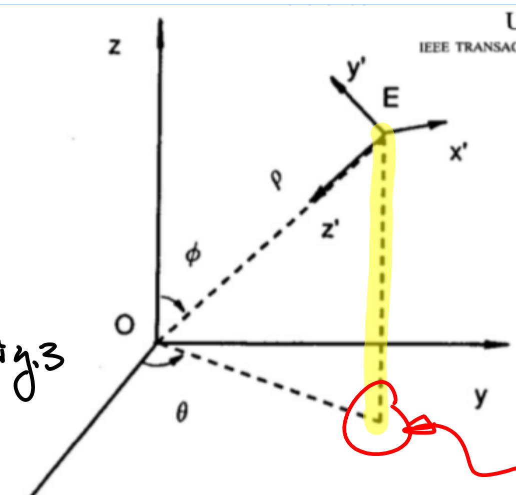
Example: Draw A line, passes $E(x_e, y_e, z_e)$ Perpendicular to X_w-y_w plane

Angle ϕ (phi): Formed Between $\overrightarrow{OE}$ (Not Exactly the $\overrightarrow{EO}$) and Z_w

Distance ρ (rho): from $\overrightarrow{E}(x_e, y_e, z_e)$ to the origin $(0,0,0)$:

$$\rho = \sqrt{x_e^2 + y_e^2 + z_e^2} \quad \ldots (1)$$

Fig.3



Step 1. World-to-viewer tra

Intersection pt. $\overrightarrow{E'}$

Example: A cube given in the following figure:

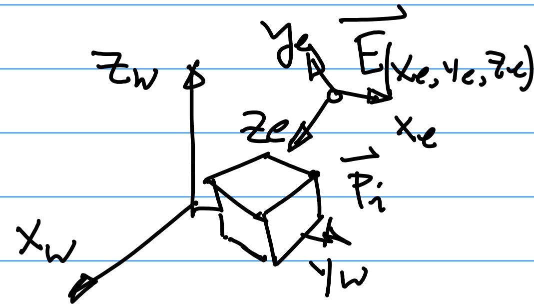
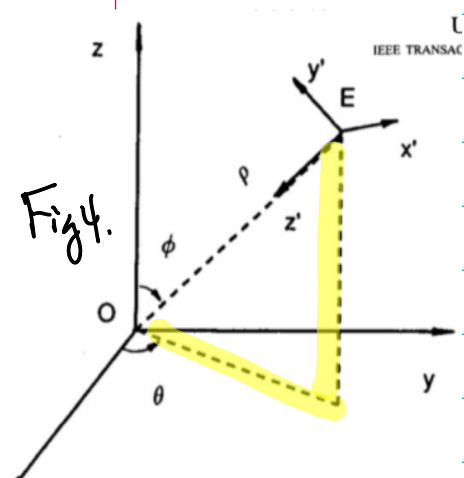


Fig.5

Draw 2nd Line, passes E' (on X_w-y_w) to connect to the origin $(0,0,0)$ of X_w-y_w-Z_w. as in Fig

Fig4.



Step 1. World-to-viewer tra

$$\mathbf{T} = \begin{bmatrix} -\sin\theta & \cos\theta & 0 & 0 \\ -\cos\phi\cos\theta & -\cos\phi\sin\theta & \sin\phi & 0 \\ -\sin\phi\cos\theta & -\sin\phi\cos\theta & -\cos\phi & \rho \\ 0 & 0 & 0 & 1 \end{bmatrix} \quad \ldots (2)$$

Angle θ: (Theta) formed Between the 2nd Line and X_w.

$\overrightarrow{P_i}$ defined in the X_w-y_w-Z_w

$\overrightarrow{P_i'}$ defined in the X_e-y_e-Z_e

$$\begin{pmatrix} x_i' \\ y_i' \\ z_i' \\ 1\end{pmatrix} = \begin{bmatrix} -\sin\theta & \cos\theta & 0 & 0 \\ -\cos\phi\cos\theta & -\cos\phi\sin\theta & \sin\phi & 0\\ -\sin\phi\cos\theta & -\sin\phi\cos\theta & -\cos\phi & \rho \\ 0 & 0 & 0 & 1\end{bmatrix}\begin{pmatrix} x_i \\ y_i \\ z_i \\ 1\end{pmatrix}$$

$\vec{P_i}'$ After "in X_e-Y_e-Z_e System" Camera

$\vec{P_i}$ Before "In X_w-Y_w-Z_w" World

Example: Given A Virtual Camera E(200,200,200) Find Transformation Matrix T (World-To-Viewer) Transform Matrix.

Sol. For θ (theta) Angle

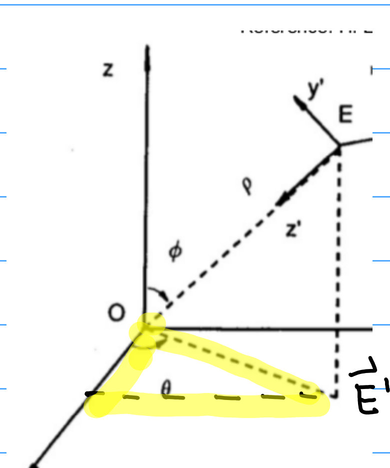
$$\cos\theta = \frac{x_e}{\sqrt{x_e^2+y_e^2}} = \frac{200}{200\sqrt{2}} = \sqrt{2}/2 \quad \ldots(3)$$

(From Fig4, pp.26)

$$\sin\theta = \frac{y_e}{\sqrt{x_e^2+y_e^2}} = \frac{200}{200\sqrt{2}} = \sqrt{2}/2 \quad \ldots(4)$$

Consider $\sin\phi$

Draw A Line Passing $\vec{E}'$ Perpendicular to x_w to form A Triangle



Step 1. World-to-vie