

# Exercise 4: Real Time Continuous Media

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## Problem 1

### USB hot-plug proof

Here is the dmesg showing the uvc driver pulling up the device.

```
root@cyclonev:~# dmesg | grep video
[  0.267413] Linux video capture interface: v2.00
[ 921.138970] uvcvideo: Found UVC 1.00 device <unnamed> (046d:0802)
[ 921.181972] usbcore: registered new interface driver uvcvideo
root@cyclonev:~#
```

Figure 1: As you can see dmesg shows the uvc driver recognize that the camera was plugged in

### UVC driver verify

Here is a screenshot showing that we got the UVC driver installed on teh DE1 board.

```
root@cyclonev:~# lsusb | grep C200
Bus 001 Device 006: ID 046d:0802 Logitech, Inc. Webcam C200
root@cyclonev:~# lsmod | grep video
uvcvideo                63506  0
videobuf2_core          26500  1 uvcvideo
videobuf2_vmalloc       2731   1 uvcvideo
videobuf2_memops        1845   1 videobuf2_vmalloc
root@cyclonev:~#
```

Figure 2: As you can see the Logitech webcam appears as does the driver

## Problem 2

### Use of tools such as camorama

Here, we have taken a screenshot of camorama running and some settings being adjusted.

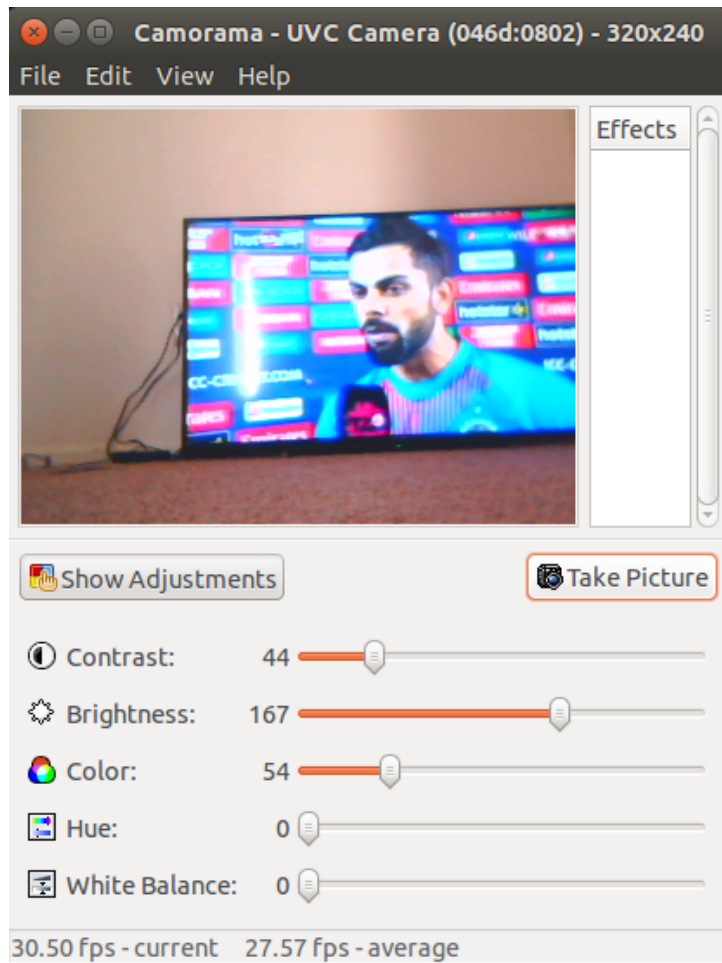


Figure 3: The camorama application running with a captured photo

## Problem 3

### Build and Test

We did install openCV on the DE1, but since we are using a laptop we should verify it is installed here. I used the official arch repositories for the installation.

```
[zap@WIN exercise_4]$ yaourt -Q | grep opencv
extra/opencv 2.4.12.3-1
extra/opencv-samples 2.4.12.3-1
[zap@WIN exercise_4]$ pkg-config --libs opencv
-l/lib64 -lopencv_calib3d -lopencv_contrib -lopencv_core -lopencv_features2d -lopencv_flann -lopencv_gpu -lopencv_highgui -lopencv_imgproc -lop
v_nonfree -lopencv_objdetect -lopencv_ocl -lopencv_photo -lopencv_stitching -lopencv_superres -lopencv_ts -lopencv_video -lopencv_videostab -lt
m -ldl
```

Figure 4: Proof opencv is installed on the system

### Streaming Verification

Here, we have 2 examples of capture in progress.



Figure 5: An example of capture

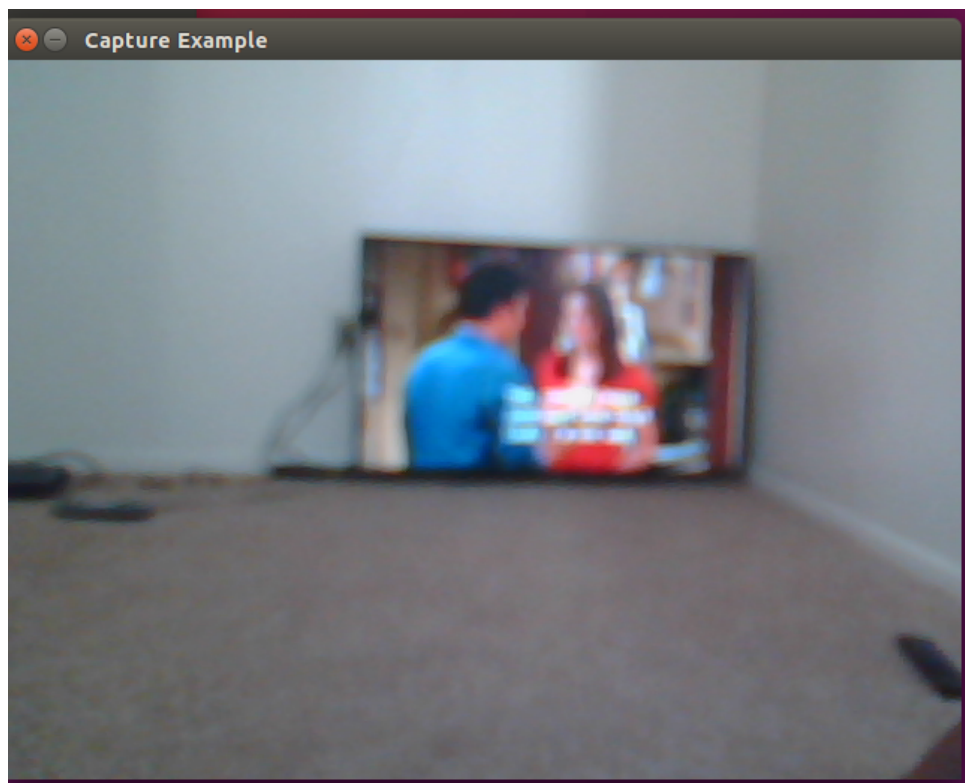


Figure 6: An example of capture

## Problem 4

### Demonstration of Tests

Here we have a demonstration that we ran the canny transformation example code.

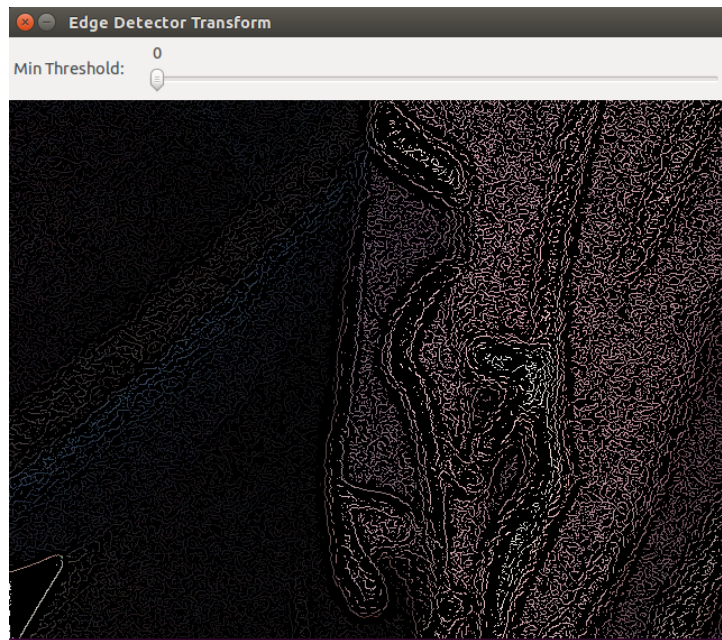


Figure 7: An example of the canny transformation code running

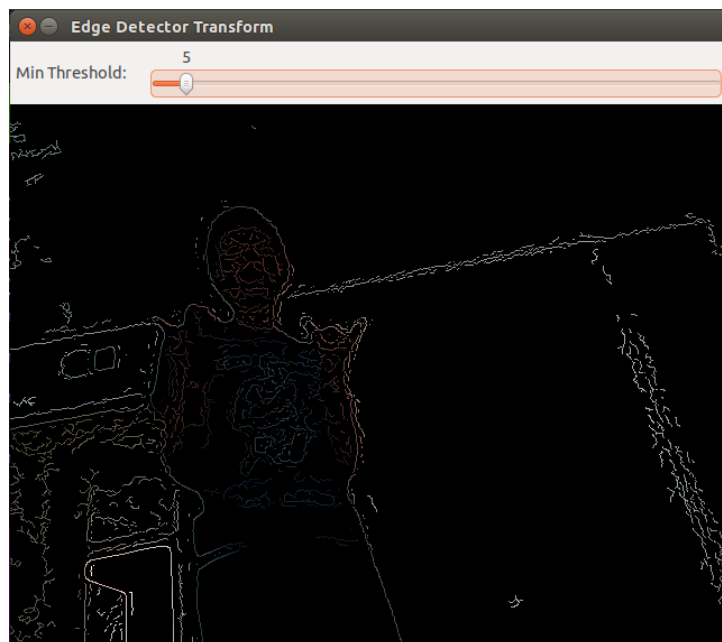


Figure 8: An example of the same code, but using the slideruler for different results

### Description of Tests

The Canny Edge Detector is an edge detection operation that uses a multi-stage algorithm to detect a wide range of edges in images. It is the first derivative of a Gaussian and closely approximates the operator that optimizes the product of signal-to-noise ratio and localization. Canny Transform is known as the optimal detector and aims to satisfy three main criteria:

- Low error rate: Meaning a good detection of only existent edges.
- Good localization: The distance between edge pixels detected and real edge pixels have to be minimized.
- Minimal response: Only one detector response per edge

```
int lowThreshold=0;
int const max_lowThreshold = 100;
int kernel_size = 3;
int edgeThresh = 1;
int ratio = 3;
```

First, we declare some variables. The variable ratio defines the lower:upper threshold as 3:1. The kernel size is set to 3. The initial value of the lower threshold is set to 0 and the maximum value that it can take is set to 100.

```
vCapture* capture;
int dev=0;
if(argc > 1)
{
    sscanf(argv[1], "%d", &dev);
    printf("using %s\n", argv[1]);
}
else if(argc == 1)
    printf("using default\n");
else
{
    printf("usage: %s capture [dev]\n");
    exit(-1);
}
```

All of this code prepares a capture for the camera.

```
namedWindow( timg_window_name , CV_WINDOW_AUTOSIZE );
```

Third, we create a window to display the results.

```
createTrackbar( "Min Threshold:", timg_window_name , &lowThreshold, max_lowThreshold
```

Then we create a Trackbar to adjust the canny transformation variables dynamically.

```
capture=(CvCapture *)cvCreateCameraCapture(dev);
cvSetCaptureProperty(capture,CV_CAP_PROP_FRAME_WIDTH,HRES);
cvSetCaptureProperty(capture,CV_CAP_PROP_FRAME_HEIGHT,VRES);
```

Now we actually start the capture and set the width and height.

```
cvtColor(mat_frame, timg_gray, CV_RGB2GRAY);
blur( timg_gray, canny_frame, Size(3,3) );
Canny( canny_frame, canny_frame, lowThreshold, lowThreshold*ratio,kernel_size );
timg_grad = Scalar::all(0);
mat_frame.copyTo( timg_grad, canny_frame);
imshow( timg_window_name, timg_grad );
```

Finally we do the actual Canny transform. First, we move to a grayscale frame because that's what the canny transform works with. Then, we reduce noise by high pass filtering with blur(). The third thing is to run the actual canny transform. The arguments are:

- canny\_frame: Source image grayscale
- canny\_frame: destination image grayscale
- lowThreshold: Is a low threshold variable for the transform
- ratio\*lowThreshold: This is actually the high threshold for the transform
- defined to be 3

Then we call a copy to throw the canny results onto the timg\_grad. Finally, we display the image.

## Problem 5

### Design Concepts

### Algorithm Analysis

Here we see the table of normal frame rates on Zach's Archlinux installation, with a 1.8GHz processor, and a built in webcam for the hough transform, the canny interactive and the hough-elliptical transforms.

Resolutions	160X120	320X240	640X480	960X720	1280X960
Canny-Interactive (fps)	29.15	27.35	22.63	18.97	14.75
Deadline and 1/fps in parenthesis	38ms(34ms)	41ms(36ms)	50ms(44ms)	58ms(53ms)	74ms(67ms)
Hough-Elliptical (fps)	30.50	30.20	30.11	26.75	16.01
Deadline and 1/fps in parenthesis	36ms(33ms)	37ms(33ms)	39ms(33ms)	43ms(37ms)	67ms(62ms)
Hough (fps)	30.50	30.15	27.20	18.30	13.49
Deadline and 1/fps in parenthesis	36ms(33ms)	38ms(33ms)	43ms(37ms)	60ms(55ms)	80ms(74ms)

### Prototype Analysis

### Final Predictable Response Jitter Analysis