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Research Article

Automatic Generation of Spatial and Temporal Memory Architectures for Embedded Video Processing Systems

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This paper presents a tool for automatic generation of the memory management implementation for spatial and temporal real-time video processing systems targeting field programmable gate arrays (FPGAs). The generator creates all the necessary memory and control functionality for a functional spatio-temporal video processing system. The required memory architecture is automatically optimized and mapped to the FPGAs' memory resources thus producing an efficient implementation in terms of used internal resources. The results in this paper show that the tool is able to efficiently and automatically generate all required memory management modules for both spatial and temporal real-time video processing systems.

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1. INTRODUCTION

In today's society it is apparent that video systems are generally becoming standard applications. These systems are playing a central role in the daily life of the majority of homes. Embedded video applications contained in home entertainment systems are becoming more and more complex as is the processing required. Real-time streamed video is common and this places significant constraints on the processing applications as the data rates increase towards high-definition television (HDTV). Surveillance application is one of the most rapidly developing areas. Video monitoring is now present in almost every store or public place. The amount of video data produced by these systems requires them to be able to efficiently derive features or events that are present in the scene. This, in turn, has led to an increased requirement to enable more complex operations such as prefiltering, object recognition, or compression to be performed as close as possible to the video source. This advance has led to the rapid development of smart cameras which have the ability to fulfill these requirements. Complex reconfigurable embedded systems with advanced image processing functions must be rapidly developed which are also available at a low cost [1].

Video processing systems required in the broadcast and postprocessing market are typically in the low-volume and high-cost segment. These are systems performing real-time high-resolution (2048 $\times$ 2048@24 fps) high-performance computation with complex motion compensating spatio-temporal filters [2]. The trend is for the algorithm complexity to increase over time. This increased complexity is often reflected in the memory usage. One example involves the memory usage required by algorithms with temporal data dependencies. In order to manage the increased complexity and the requirement for a shorter period of time-to-market, efficient toolsets are required. Effective development tools can abstract the hardware layer and ease the development by enabling the systems designer to perform actual hardware implementation without extensive hardware knowledge.

Attempts at reducing the time-to-market of modern electronic systems have, in general, increased the motivation to develop automation tools for system modeling [3–8], optimization [9], simulations [3, 10, 11], and synthesis [9, 12–17]. The main objective of these automation tools is to empower the designer not to only have the ability to cope with increasing design complexity but also to generate efficient designs as quickly as possible. In this paper, we present a design suite for generating the architecture for real-time spatial and temporal image/video filters targeting field programmable gate arrays (FPGAs) thus enabling designers to cope with design complexities and time-to-market constraints.

The outline of this paper is as follows. Firstly, related work is presented and then the background and the scope of this paper are stated. We then present the real-time video processing system (RTVPS) synthesis and limitations in

Section 4. The results are presented in Section 5 followed by the discussions and conclusions in Section 6 and Section 7, respectively.

2. RELATED WORK

This work is built on the success of many previous works in the area of memory estimation, optimization, mapping, memory accessing, and interfacing for both on- and off-chip memory allocations. However, there is a rather limited selection in the literature of work relating to homogenous tools which unify the management of on- and off-chip memories in a seamless manner and, additionally, of tools able to handle boundary conditions for real-time video processing systems.

Reference [18] presents the design and implementation of a high-level core generator for 2D convolution operations, which contains the parameters and ability to scale in terms of the convolution window size and coefficients, the input pixel word length, and the image size. The work has been extended to be generic and automatically implemented. The allocation of line buffers required by the convolution cores has also been investigated. The work by Schmit and Thomas [19] performs array grouping (vertically and horizontally) and dimensional transformation (array widening and array narrowing). Array widening is useful for read-only arrays and those accessed in loops with an unrolled number of iterations. Jha and Dutt [20] presented two algorithms for memory mapping. The first, linear memory mapping, approximates target memory word-count to the largest power-of-two that is less than or equal to the source memory word-count. The second, exhaustive memory mapping, assumes that the target memory module may have a larger bit-width and word count. Lawal et al. [21] presented a heuristics-based algorithm for allocating FPGA block RAMs for the implementation of RTVPS. To achieve optimal results, dual port capabilities of block RAMs were exploited and vertical grouping of the line buffers as well as dynamic allocation of memory objects to multiple block RAMs were utilised. The effectiveness of the algorithm was shown through the implementation of realistic image processing systems.

With reference to background memory management, Thörnberg et al. [22] proposed a methodology for background memory estimation and optimization. A tool implementing the methodology to generate optimized estimates of the memory requirements of an RTVPS was also presented. Weinhardt and Luk [23] present a technique that optimally allocates memory objects to a set of background memory banks using integer linear programming (ILP). The technique achieved optimisation by parallelisation of data accesses through pipelining. Diniz and Park [24] addressed the problems associated with external memory interfacing by exploiting target memory architecture and the application memory access pattern.

We have taken advantage of these, and other notable works, in developing the work presented in this paper. To use the architecture generator presented in this paper, the designer is only required to specify the memory requirements of a neighbourhood oriented RTVPS and continue with the development of the core RTVPS. This work will implement data storage to both on- and off-chip memories and provide interface for the pixel data required by the filter. FlexFilm [2] and Imagine [25] are the closest related research works at the present time. FlexFilm is a top-end multi-FPGA hardware/software architecture, for computation intensive, high-resolution real-time digital film processing. The architecture implements the external memories and achieved record performance. However, very little was reported concerning the allocation to on-chip memory. Our work differs from the Imagine Stream Architecture since our core processing technology is FPGA.

3. BACKGROUND

This work was developed as part of the IMEM-IMapper design tool [8, 10]. The primary objective is to assist designers in a seamless implementation of neighbourhood-oriented RTVPS filters by handling the memory requirements and boundary conditions of a filter. IMEM is a system description dataflow graph that generates a fully synthesisable real-time register-transfer level (RTL) model of a RTVPS. Its basis lies in the knowledge that the filter kernel and the interface and memory model of a real-time video processing system can be described separately [10]. Parameters extracted from IMEM include image size, kernel size, colour-model, and data dependencies. Naturally, an RTVPS will consist of several such filters, which may possibly contain varying values.

Each set of parameters is the interface and memory model generated for each of the filters in RTVPS. The full model also includes interfaces and operators relative to each other. The IMEM model can be imported into our automatic synthesis tool IMapper which generates the target-specific implementation of the interface and memory model. A manually refined filter kernel is then merged with the automatically generated interface and memory model into target-specific RTL-code. This video system implementation can be further transformed into gate-level code using a target-specific synthesis tool. Figure 1 shows the relationship between IMEM and IMapper.

This work implements the interface and memory model and the filter boundary conditions thus freeing up the designer to implement the filter. The presented tool includes the following work.

(i) Automatic allocation of line buffers and frame buffers for embedded block RAMs and external RAMs, respectively.
(ii) Automatic address generation and interfaces for the two memory hierarchies (off and on-chip memory).
(iii) Automatic implementation of boundary conditions.
(iv) Implementation of parallel access to all pixel data required in a neighbourhood (spatial or temporal).
(v) Provision of a test-bench with valid image streaming and image capturing for efficient simulation and verification of a customized video processing algorithm.

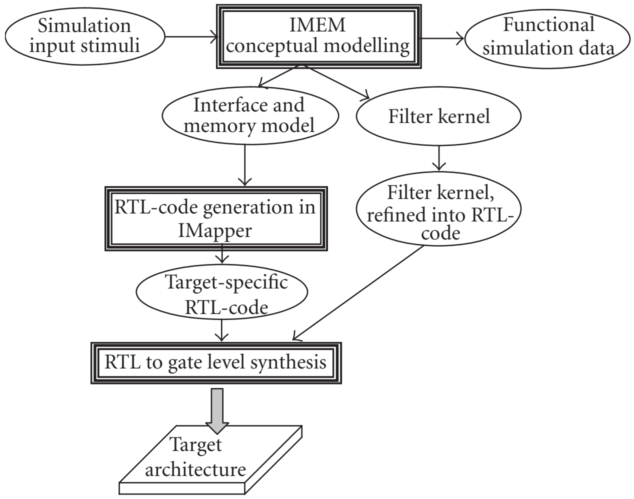


Figure 1: The IMEM workflow.

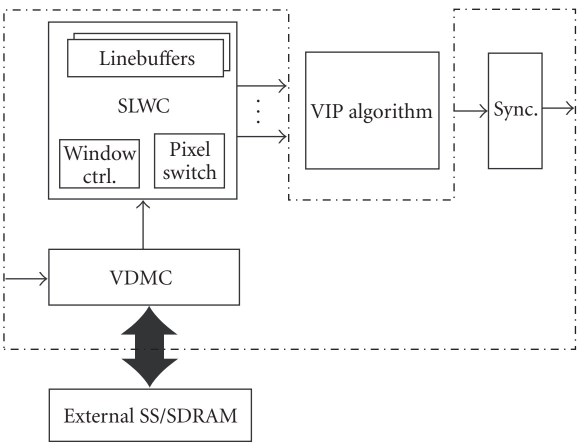


Figure 2: Architectural overview.

4. RVTPS SYNTHESIS

As described in the previous section, the designer specifies the required system parameters derived from either the IMEM environments or with parameters derived from another source. From these parameters, the IMapper creates the required hardware structure as depicted in Figure 2. The architecture is derived from three major parts, the sliding window controller (SLWC), video data memory controller (VDMC), and the synchronisation block. To ease the implementation of a custom filter function, an HDL template providing the necessary interface for seamless integration in the design flow is generated. To illustrate the architecture in detail, each of the subparts is presented in the following sections.

4.1. Memory allocation

Almost all image neighbourhood operations using either a continuous or block wise pixel flow are processed by using a sliding window. Line buffers are required to store the necessary data in the spatial neighbourhood.

They are implemented using global memory object (GMO) architecture [26]. For each operator in the neighbourhood-oriented RTVPS, GMO can be achieved through

$$W_{Ri} = n_{\text{lines}} \cdot w_p, \tag{1}$$

where W_{Ri} is the width of the GMO, n_{lines} is the number of required memory objects for an operator, and w_p is the bit width representing a pixel.

The length of the GMO is equal to that of the memory objects forming it [26]. GMOs require a minimal number of memory entities in comparison to the direct mapping architecture. Consequently, the number of memory accesses for an RTVPS operation is minimal for a GMO.

Implementing GMOs and their allocation to block RAMs requires an efficient algorithm so that accessing the allocated data and reconstructing the line buffers occurs in a seamless manner with minimal overhead resource and low latency. Two allocation algorithms (one optimized for heuristics [21] and the other for ILP [22]) have been developed and implemented for this purpose. The algorithm in [21] creates the GMOs based on (1). It partitions the GMOs to ensure that their widths conform to those specified by the FPGA thus ensuring optimal usage of the block RAMs. The algorithm takes advantage of the dual port capabilities of the block RAMs to achieve optimal allocations and the possibility of allocating a GMO to as many block RAMs as required. Figure 3 depicts the method used by the algorithm to allocate four memory objects according to the GMO architecture. In Figure 3(a), the four line buffers were grouped together to form one GMO. Assuming the GMO is 640-pixel wide, then if it were to be allocated on a Xilinx Spartan 3 FPGA, it would require partitioning into two segments, of widths 32 and 16, as it is not possible to have a data path width of 48 on a Xilinx Spartan 3 FPGA. In addition, since each block RAM is 16 Kibit (excluding parity feature), the first segment, of width 32, would require 2 block RAMs, thus creating two partitions. The second segment would require a single partition on a block RAM. Figure 3(b) illustrates the partitioning of the GMO while Figure 3(c) shows how the GMO is allocated to two block RAMs using a data path of 32 bits and 16 bits. The main objective of the allocation algorithm is to minimise block RAM usage. This is achieved in Figure 3 since two block RAMs were used as opposed to the four block RAMs required for the direct mapping of the four line buffers. With direct mapping, we refer to memory mapping in which each line buffer is allocated to one block RAM, without resource sharing. In the figure op, seg, par, and BR represent the operator, segment, partition, and block RAM numbers, respectively, and where Ports A and B are the two io-ports available on a block RAM configured as a dual port (BR2). In this case only Port A is used on a block RAM configured as single port (BR1). In [27], two possible approaches for accessing and reconstructing the allocated memory objects were presented and compared.

The implemented GMO takes the form of a circular buffer allocated to a set of memory locations. The example

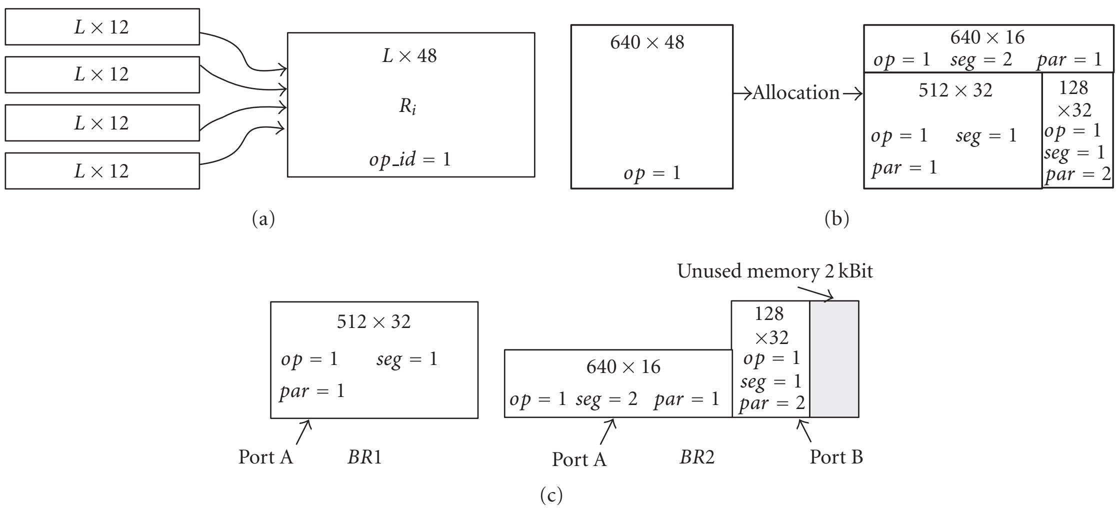


Figure 3: Implementation of memory architecture.

in Figure 4 depicts a set of eight memory locations, $n-8$ to $n-1$, which are indexed by a pointer in a modulus-8 order. For every pointer position, pixel data P_{n-8} is firstly read and then pixel data P_n is written. The benefit of the Xilinx block RAM is that it allows first-read-then-write operation to be executed in one single clock cycle. In the continuous case of a sliding window the mask window will overlap the image under processing when the border is reached, creating a boundary condition, as shown in Figure 5.

For each mask window, b possible numbers of boundary sets are required to be handled, depending on how many mask positions fall outside the image perimeter. An example of a boundary set is shown as a dark grey shaded area in Figure 5:

$$b = 4 \cdot \left[\frac{(\omega - 1)^2}{2} - \frac{\omega - 1}{2} \right]. \quad (2)$$

Equation (2) holds true, provided that $\omega \leq \text{width}(I)$ and ω is an odd number, where ω is the window width and I the image under processing, according to Figure 5.

For each separate boundary, care has to be taken in order to prevent the introduction of nonvalid data. With nonvalid data, we refer to undefined or extreme values that would corrupt or bias the following processing functions. Positions in the window not filled by correct data can be expressed as a set, $B \in W \cap I^C$, where W is the desired processing window and I the image under processing, according to Figure 5.

For each boundary, the set B is filled with pixels according to $B \leftarrow w_c$, where w_c can be configured to originate from the valid central spatial pixel, inside the image, of the window W, defined in (3), or for the processing function suitable value:

$$w_c = W\left(\frac{\omega + 1}{2}, \frac{\omega + 1}{2}\right). \quad (3)$$

From these boundary conditions, a boundary state controller (BSC) is generated, which provides the necessary control signals for the spatial or temporal window buffers. The controller monitors the inputted vertical and horizontal synchronisation signals and keeps track of the window position relative to the image boundary. If a boundary is within the window, each pixel, falling outside the image, is replaced. The controller and the required line buffers form the temporal architecture. An example of an architecture which has a temporal depth of n frames is depicted in Figure 6.

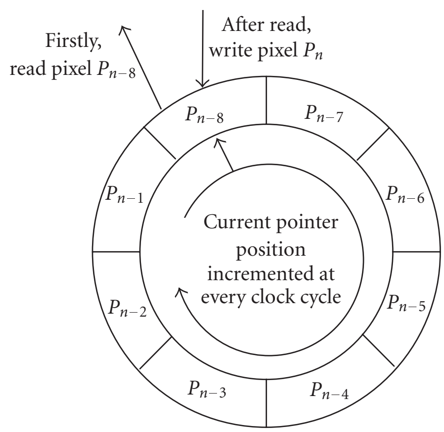


Figure 4: Read-write cycle.

The structure of the line buffers that provide the sliding window is created by block RAMs, allocated according to the method previously described. Line buffers are instantiated according to the requirement in the specification and form the spatial pixel buffer which has two lines in the example depicted in Figure 7.

The BSC is generated from generic expressions which contain the rules for the operations requiring to be performed when an image boundary is reached. At this point, the controller determines which positions in the filter mask must be replaced.

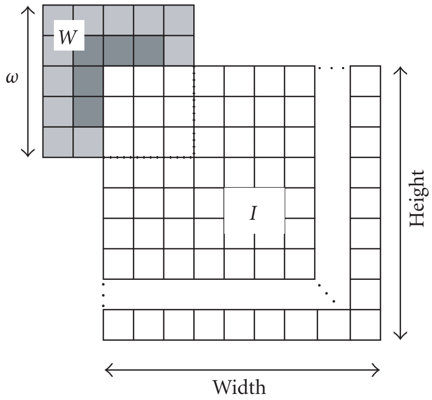
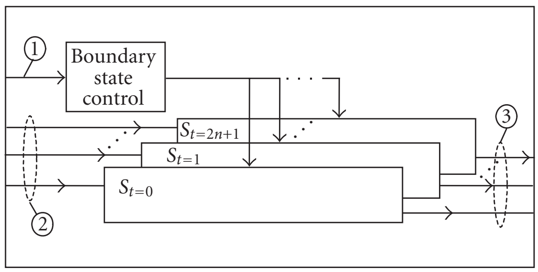


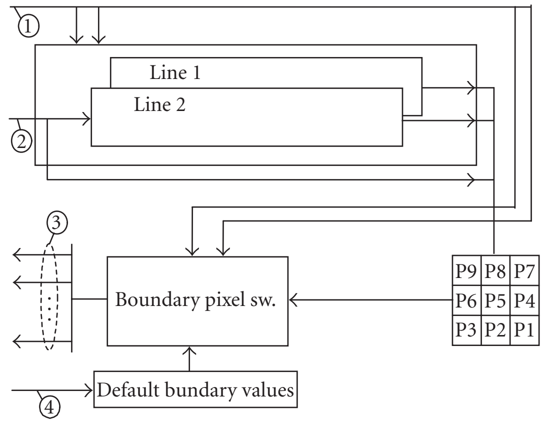
FIGURE 5: Illustration of boundary condition.



1. Synchronization and control
2. Temporal pixel data
3. Temporal windows

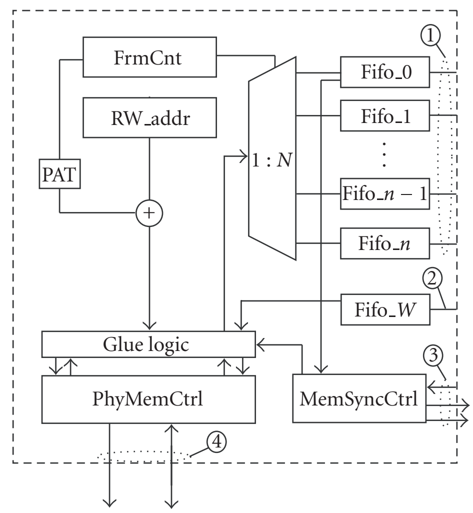
FIGURE 6: Temporal buffer architecture for n frames.

The control signals generated in the BSC are fed into the line buffer and are utilized by a pixel switch. The replacement is performed in the boundary pixel switch, at which the default boundary values can be chosen to originate from either an external constant or an existing mask position as depicted in Figure 7.



1. Mask and line control
2. Serial pixel data
3. Window mask
4. Default boundary input

FIGURE 7: Line buffer architecture.



1. Temporal pixel data
2. Processed data
3. Syncronization
4. Physical memory interface

FIGURE 8: Video data memory controller (VDMC).

4.2. Temporal memory controller architecture

The architecture generator supports static random access memories (SRAMs) in addition to synchronous dynamic random access memories (SDRAMs). The choice of memory technology is mainly dependent on the type of system to be implemented. SRAMs are suitable for video processing systems with a nonpredictable read-write access pattern, for example, block search, due to the internal design that eliminates latency between read and write cycles. For stream-oriented applications, such as filter applications with regular read and write patterns, SDRAMs are suitable.

Read and write accesses can be performed in burst mode and scheduled to optimize the related penalties. Limitations associated with the two memory types are presented in Section 4.3. The physical memory controller is interchangeable with the memory controller generated by the memory interface generator MIG from Xilinx [12]. This enables simple and seamless migration to other memory types if required. The read and write patterns stored in the physical address table (PAT) can be configured during compile time. Address generation is managed by configurable counters. The address space is derived from the input video stream characteristics, image width and height. In order to synchronise data, a FIFO buffer is implemented for each required temporal level. The size of each buffer depends on the read-write pattern and the number of temporal levels used. The described architecture is depicted in Figure 8.

The total amount of block RAM available is 432 Kibit distributed on 24 18 Kibit blocks for a Spartan 3 1000. Using

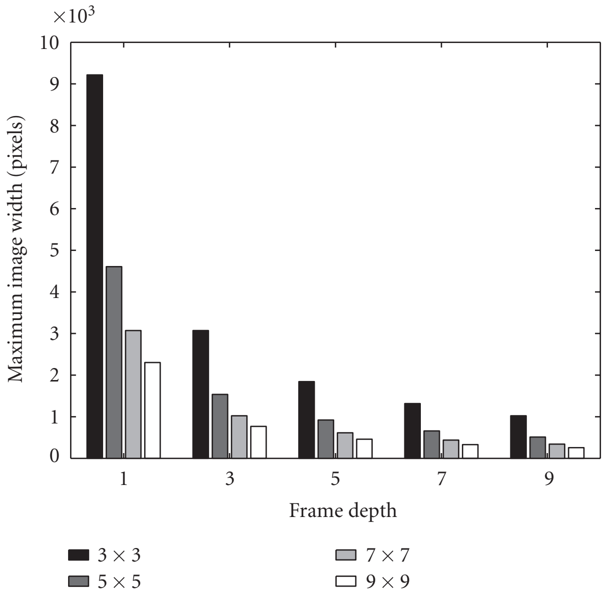


Figure 9: Maximum buffer length.

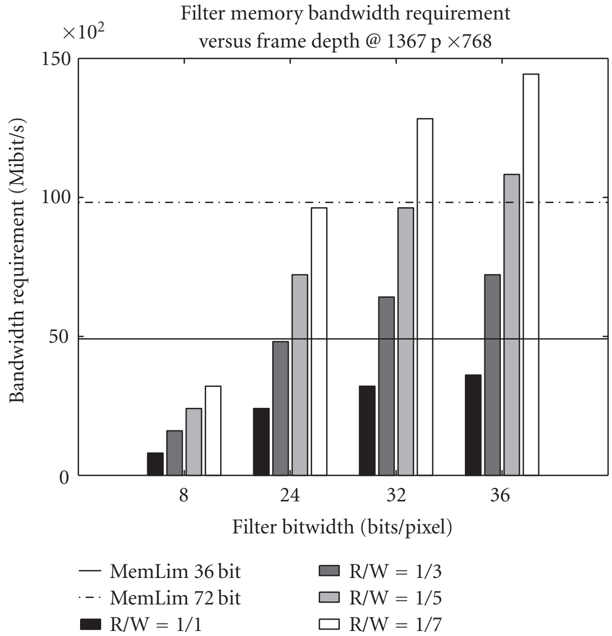


Figure 10: Bandwidth requirements.

(6) and the presented amount of block RAM yields a design space ranging from 3 × 3 spatial neighbourhoods with an image width exceeding 9 k pixels to a 9 × 9 9 frame spatio-temporal neighbourhood 256-pixel width. The design set is depicted in Figure 9. It should be noted that the architecture generator is only limited by the available resources present in the FPGA [26, 28]:

$$f_s = F_r \cdot I_{\text{width}} \cdot I_{\text{height}}, \quad (4)$$

$$I_{\text{width max}} = \frac{\text{BRAM}_{\text{size}}}{n \cdot (\omega - 1) \cdot \text{bitwidth}}. \quad (5)$$

4.3. Memory I/O performance limitations

Video processing in general has reasonably high requirements in relation to the bandwidth. A system utilizing one frame for processing, in general, does not require any external buffering and can be implemented using only line buffers placed on-chip. For spatio-temporal systems, several frames may require storage off-chip with on-chip line buffers. This requires an efficient memory usage in order to handle the amount of data requiring to be transferred.

Figure 10 illustrates the bandwidth requirements for different temporal depths and bit widths as well as memory interface limits for a 153 MHz ZBT RAM memory. The graph illustrates the filter bandwidth requirement for a specified number of read/write (R/W) operations performed for each input data. Two memory bandwidth limits are provided, 36- and 72-bit access, to illustrate the maximum interface performance.

Given the specified pixel rate f_s, the minimum speed required for SDRAM and SRAM memory, $f_{\text{Mem}_{\text{SD}}}$ and $f_{\text{Mem}_{\text{zbt}}}$, can be derived from (6) and (7), respectively. In this case, *Bl* is the burst length, w_{op} and r_{op} are the read and write operation, n is the number of the temporal frame depth, *CAS* is the column address strobe latency, t_{REF} is the time between refresh, and w_{op} and r_{op} are binary operators representing a read or write operation, respectively:

$$f_{\text{Mem}_{\text{SD}}} = f_s \cdot \left(\frac{\text{Bl} \cdot (w_{\text{op}} + n \cdot r_{\text{op}}) + \text{CAS}}{\text{Bl}} \right) + \frac{1}{t_{\text{REF}}}, \quad (6)$$

$$f_{\text{Mem}_{\text{zbt}}} = f_s \cdot (w_{\text{op}} + n \cdot r_{\text{op}}). \quad (7)$$

The system performance in terms of processed frames per second is limited by the memory I/O performance due to the large number of frames requiring to be transferred to-and-from the FPGA. To provide the designer with a road-map for the maximum image size, the system can perform up to a given SRAM memory bandwidth, it is possible to use the expression in (8). It is derived by inserting (7) into (4) and multiplying by the bit width of the respective interface. A similar operation is possible for SRAMs using (6).

An example is provided in Figure 11 depicting the image height for temporal depths ranging from 1 to 9 frames using a SRAM and SDRAM at 150 MHz speed. The figure also illustrates the influence of the CAS latency on the performance for SDRAMs using a burst length (Bl) of 8. This latency can be thought of as the difference between each of the five line pairs (the dashed line is the SRAM and the marked line is the SDRAM). The graph shows that the performance exceeds the HDTV performance 1367 × 768 progressive mode for a temporal depth of 3 frames:

$$I_{\text{height max}} = \frac{f_{\text{Mem}} \cdot \text{bitwidth}_{\text{Mem}}}{I_{\text{width}} \cdot F_r \cdot (w_{\text{op}} + n \cdot r_{\text{op}}) \cdot \text{bitwidth}_{\text{Pixel}}}. \quad (8)$$

In Figure 12 the solid line in each line pair describes the burst length of 8 and the dot marked line is the burst length of one.

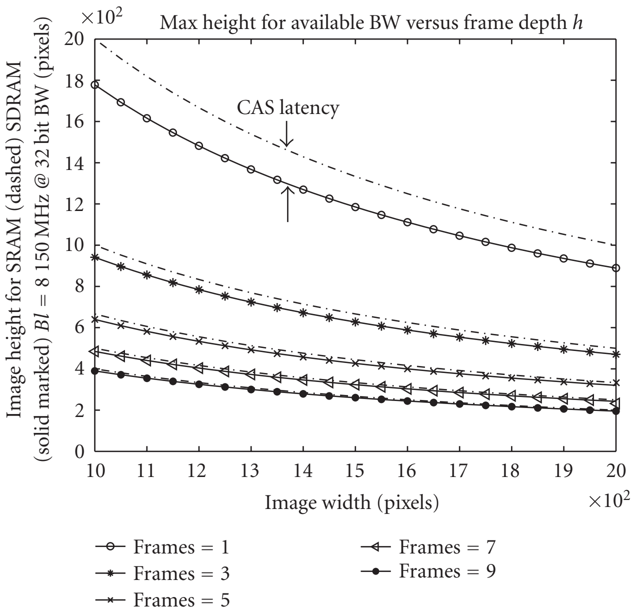


Figure 11: Image height versus temporal depth.

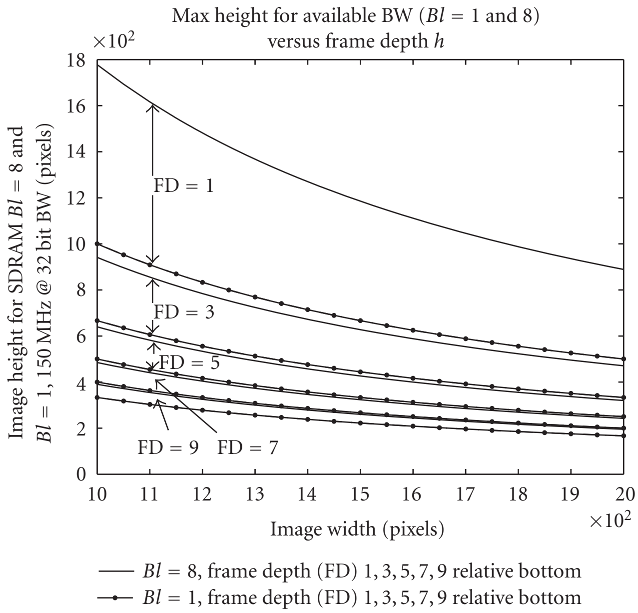


Figure 12: Burst length influence.

This shows that a low-burst length severely degrades the performance for low-frame depths. The selected type of memory mainly depends on the application. Generally static memories have a low density compared to that of the corresponding dynamic, which implies a high cost (area).

5. IMPLEMENTATION RESULTS

All parts of the architecture depicted in Figure 2 and Figures 13–15 have been implemented and the synthesis results using Xilinx integrated software environment (ISE) version 8.1i targeting the Xilinx Spartan 3 1000 FPGA are shown. Several results exceeded the resources available on one FPGA chip and hence led to the use of multiple chips. The figures show the results for 3×3, 5×5, and 7×7 spatial neighbourhoods implemented on 1-, 3-, 5-, 7-, and 9-frame temporal neighbourhoods. Figure 13 shows the number of slices and flip-flops. Figures 14 and 15 display the number of required block RAMs and maximum frequency, respectively. The results were obtained for a resolution of 1367×768, with 24 bits per pixel. Table 1 shows the resources required by all the components in Figure 2 apart from the filter core and the external SDRAM used to support the implementation of a filter with 3×3 spatial and a 7-frame temporal neighbourhood.

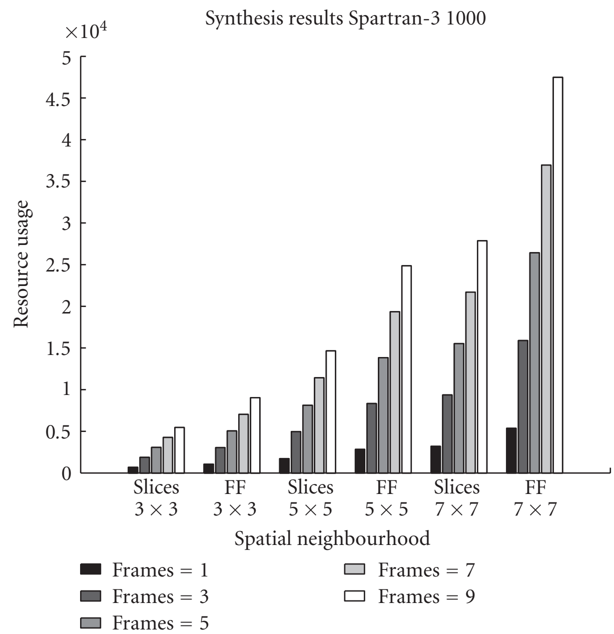


Figure 13: Synthesis results.

6. DISCUSSION

The results show that resources increase linearly with the dimensions of the spatial and temporal neighbourhoods and that the maximum frequency decreases with the dimensions. This architecture greatly reduces the designer's development time, increasing productivity and reducing time-to-market, while, at the same time, providing efficient hardware modules. The generic nature of this architecture makes it subjective to the core filter algorithm rather than constraining it. Hence it is only necessary for the designers to define the interfaces required by the filter, implement the filter, and specify the required memory parameter. The architecture generator then generates the modules (as indicated in Figure 2) necessary to manage the filter data requirements.

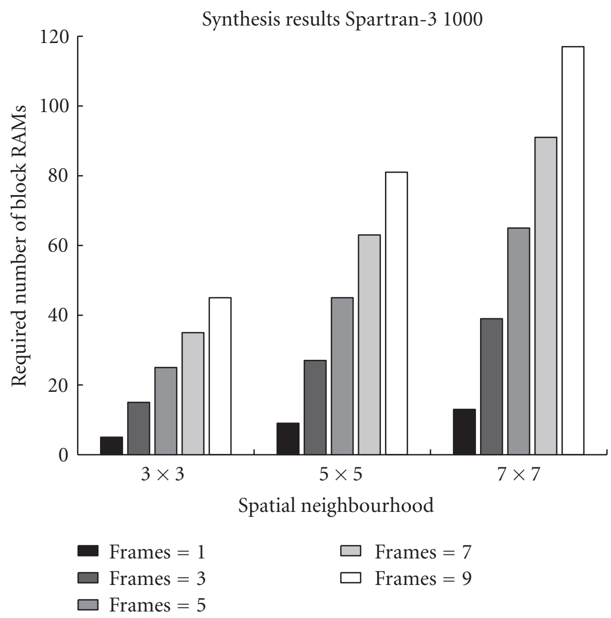


Figure 14: Block RAM requirements.

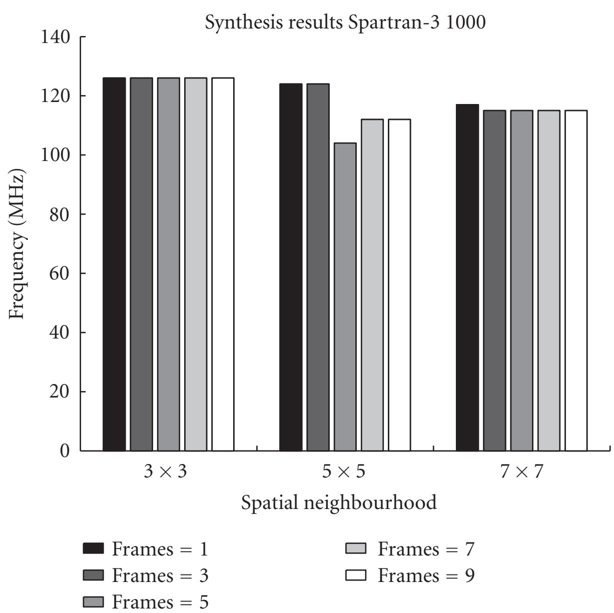


Figure 15: Implementation frequency.

This significantly increases the possibility of rapid and simple implementation of embedded video systems. The included block RAM allocation and optimization method provide an automatic resource minimisation that would not have been available to the designer without using this presented architecture generator.

The results in this paper show that the implementation speed is close to the physical limitations of the block RAMs. Thus, there are only limited possibilities for manual optimisations. With regards to the cost aspects, the automatic memory allocation, based on heuristics, produces a near optimal solution which is almost impossible to achieve manually. This implies that the tool is able, in fractions of a second, to generate an implementation with comparable performance and lower block RAM costs compared to a manual implementation. When this is taken into consideration, the proposed architecture generator efficiently generates architectures for video systems utilizing sliding windows. For example, the design time involved in implementing a simple 3 × 3 neighbourhood would require a significant budget, but the complexities involved for a larger 9 × 9 system are too complex, for several designs, to be handled manually. The results also provide the designer with a road map illustrating the limits involved for physical implementation. Comparisons with previous works are discussed below.

Table 1: Synthesis results for a spartan 3 1000.

	3 × 3 SLWC	Output sync.	7-frame neighborhood		Total
			ADR CTRL	ZBT SRAM CTRL	
Number of slices	4262	41	98	74	4475
Number of slice Flip-flops	7035	50	115	75	7275
Number of 4-input LUTs	392	65	132	37	626
Number of block RAMs	35	3	—	—	38

With regards to boundary condition implementation

In [18], implementation of a pixel neighbourhood at the boundaries was not considered. In this work, we have implemented how it is possible to correct pixel data affected by boundary conditions.

With regards to on-chip memory management

We have adopted the approach in [21] over [19] and [20] since it exploits true dual port capabilities of block RAMs and performs vertical grouping of line buffers and dynamic allocation of memory objects to multiple block RAMs to achieve optimal results.

With regards to background memory management

We used an IP core from Xilinx to allocate and retrieve video frames from background memory. The core is very close to [24] since a memory access pattern was exploited. Our work can integrate with [22, 23] or any other background memory management tool available to the designer.

With regards to video processing platforms

The goal for our IMEM-IMAPPER software tool is to manage (on- and off-chip) memory requirements and complexities and provide interfaces for the required data thus enabling designers to focus on core RTVPS algorithms. The synthesizable VHDL code generated by our tool is capable of performances in speed and video resolution comparable to FlexFilm [2] and Imagine [25].

7. CONCLUSIONS

A fully automatic spatio-temporal video processing architecture generator has been presented. It provides the designer with a unique degree of flexibility in terms of both spatial and temporal behaviour. Memory-optimized systems spanning from a 3×3 spatial neighbourhood up to a 9 frame spatio-temporal 7×7 pixel neighbourhood with off-chip memory storage have been presented. However, it is easily possible to generate larger designs if they are required. Usage of the proposed architecture generator will greatly reduce the design time and provide the designer with a powerful, efficient, and fully automatic design tool suitable for embedded video processing systems.

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