

# Technical Note

## MT9V022 Parallel and Serial Stereo Operation

### Introduction

Aptina's MT9V022 CMOS image sensor is designed to support stereo operations. Two sensors can be used in either lockstep operation or in asynchronous mode (where the sensors have different clock domains).

For lockstep operation, if two sensors are provided with the same clock, the same reset, and the same two-wire serial interface stimulus at the device inputs, they will effectively operate in tandem (clock by clock). Therefore, two connected MT9V022 sensors can provide synchronized stereo output.

For asynchronous operation, one MT9V022 acts as a master, controlling the output for a slave sensor.

This technical note describes the topology and configuration for the following operational modes:

- parallel stereo
- serial stereo
- asynchronous stereo

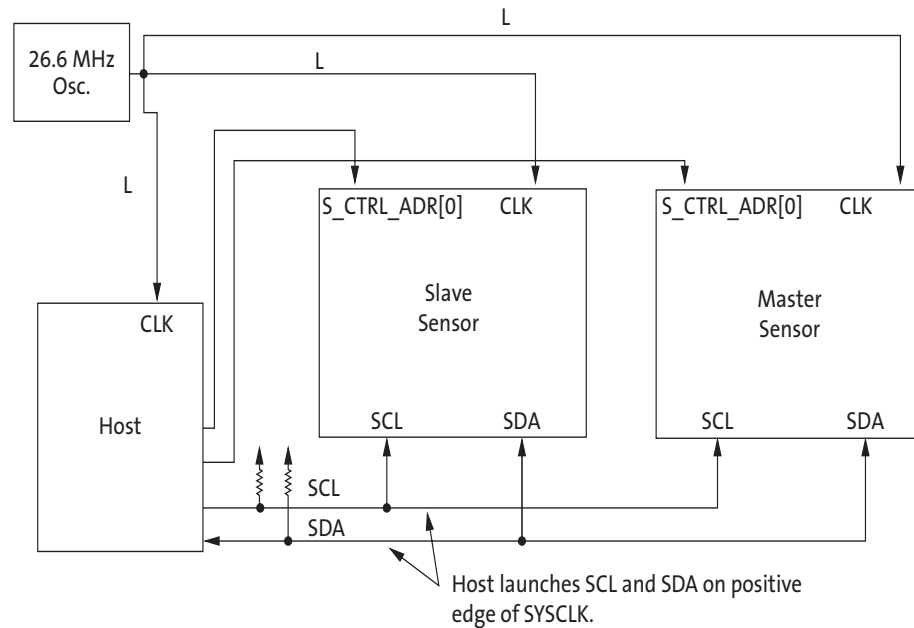
### Synchronous Stereoscopic Operation

In stereoscopic mode, the two cameras are required to run in lockstep mode. This implies that control logic in each sensor will be in exactly the same state on every clock as its pair sensor. To ensure this, all inputs that affect control logic must be identical and arrive at the same time at each sensor. This configuration is shown in Figure 1 on page 2.

These inputs include:

- system clock
- system reset
- two-wire serial interface clock—SCL
- two-wire serial interface data—SDA

Figure 1: Two-Wire Serial Interface Configuration in Stereoscopic Mode



- Notes: 1. All system clock lengths (L) must be equal. SCL and SDA lengths to each sensor (from the host) must also be equal.

## Individual WRITES

The setup in Figure 1 shows how the two sensors can maintain lockstep when their configuration registers are written through the two-wire serial interface. A WRITE to configuration registers would either be broadcast (simultaneous WRITES to both sensors) or individual (WRITE to just one sensor at a time). READs from configuration registers would be individual (READs from one sensor at a time).

One of the two serial interface slave address bits of the sensor is hardwired; the other is controlled by the host, allowing the host to perform either a broadcast or a one-to-one access.

## Broadcast WRITES

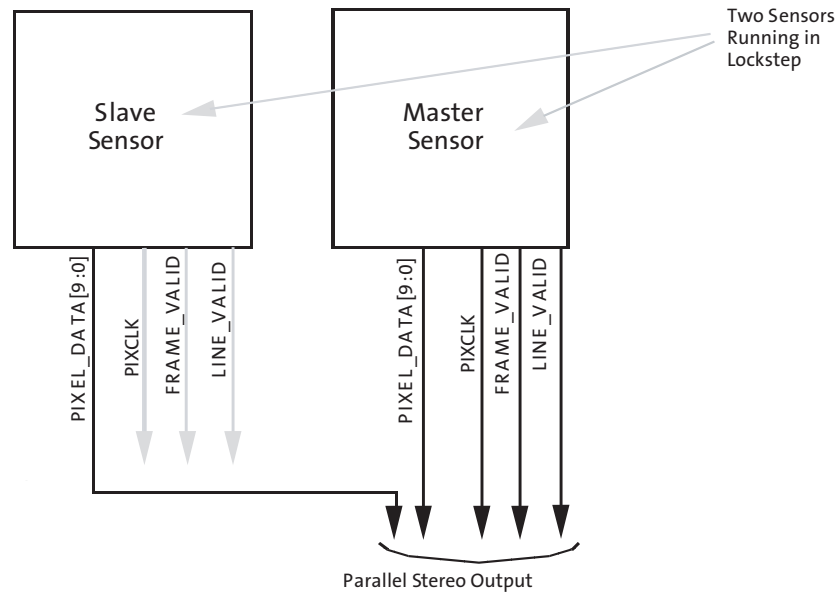
Broadcast WRITES are performed by setting the S\_CTRL\_ADR input pin for the slave and master sensors to the same state. Individual WRITES are performed by setting the S\_CTRL\_ADR input pin for the slave and master sensors to opposite states. Similarly, individual READs are performed by setting the S\_CTRL\_ADR input pin for the slave and master sensors to opposite states.

- Note:** The clock signal in Figure 1 must be attached to the host and to the two MT9V022 sensors—this guarantees the strict timing requirements of the system. The system may not work properly if the clock signal is not configured as shown.

## Stereo Parallel Operation

This is the simpler of the two topologies. As long as the two sensors are in lockstep mode following the topology of Figure 2, the parallel output of each sensor device will be in sync with the other.

Figure 2: Parallel Stereo Operation Topology



## Stereo Serial Operation

The LVDS interface allows the serial streaming of sensor data to a standard off-the-shelf deserializer up to 5 meters from the MT9V022 sensor. The pixel data and controls are packeted into 18-bit packets for stereoscopy mode. All serial signaling (clock and data) is LVDS. The LVDS serial output is stream-merged data from two sensors (itself and its stereoscopic pair).

The deserializer used in the stereoscopic configuration reproduces 8-bit parallel pixel data from each sensor with embedded LINE\_VALID (LV), FRAME\_VALID (FV), and PIXCLK. Additional logic is required to extract LV and FV from the serial data stream.

Since the two sensors are required to run in lockstep in stereoscopy mode, configuration WRITES through the two-wire serial interface are done in such a way that both sensors can get their configuration updates simultaneously.

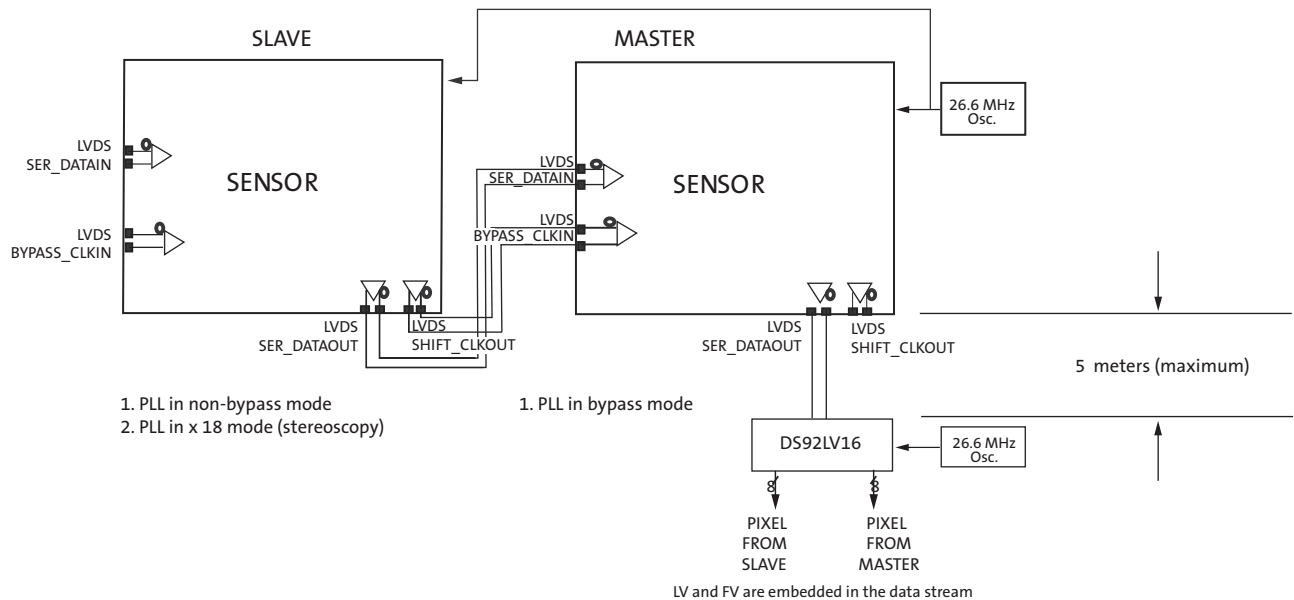
The inter-sensor serial link is designed in such a way that once the data delay (R0xB3[2:0]), shift-clk delay (R0xB2[2:0]), and stream latency select (R0xB4[1:0]) are configured (upon lock of the slave PLL), the master sensor will stream good stereo content regardless of any variation in supply voltage or temperature as long as they are within specification. Register parameters data delay, shift\_clk delay, and stream latency select are either predetermined from the board layout or can be empirically determined by reading back the stereo-error flag. This flag gets asserted when the two merged sensor streams are not in sync. The combo register (R0xB9[15:0]) is used for the diagnosis of out-of-sync streams.

In stereo serial operation, the internal PLL generates the SHIFT\_CLKOUT (x18) output in phase with the system clock. The LVDS signal SER\_DATAOUT must be connected to a deserializer clocked at approximately the same system clock frequency.

### Topology

Figure 3 shows how a standard off-the-shelf deserializer can be used to retrieve PIXEL\_DATA[9:2]. Additional logic will be required to extract LV and FV embedded within the pixel\_data stream.

Figure 3: Stereoscopy Topology





## Stereo Serial Configuration

The typical configuration of the master and slave sensors is as follows:

1. Power up the sensors.
2. Broadcast WRITE to de-assert LVDS power-down (set R0xB1[1] = 0).
3. Individual WRITE to master sensor putting its internal PLL into bypass mode (set R0xB1[0] = 1).
4. Broadcast WRITE to both sensors to set the stereoscopy bit (set R0x07[5] = 1).
5. Make sure all resolution, vertical blanking, horizontal blanking, window size, and AEC/AGC configurations are done through broadcast WRITE to maintain lockstep.
6. Broadcast WRITE to enable LVDS serial driver (set R0xB3[4] = 0).
7. Broadcast WRITE to enable LVDS receiver (set R0xB2[4] = 0).
8. Individual WRITE to master sensor, putting its internal PLL into bypass mode (set R0xB1[0] = 1).
9. Individual WRITE to slave sensor, enabling its internal PLL (set R0xB1[0] = 0).
10. Individual WRITE to slave sensor, setting it as a stereo slave (set R0x07[6] = 1).
11. Individual WRITES to master sensor to minimize the inter-sensor skew (set R0xB2[2:0], R0xB3[2:0], and R0xB4[1:0] appropriately). Use R0xB7 and R0xB8 to get lockstep feedback from stereo\_error\_flag.
12. Broadcast WRITE to issue a soft reset (set R0x0C[0] = 1 followed by R0x0C[0] = 0).

**Note:** The stereo\_error\_flag is set if a mismatch has occurred at a reserved byte (slave and master sensor's codes at this reserved byte must match). If the flag is set, steps 11 and 12 are repeated until the stereo\_error\_flag remains cleared.

## LVDS Output Format

In stereoscopic mode, the packet size is 18 bits (2 frame bits and 16 payload bits). The packet consists of a start bit, the master pixel byte (with sync codes), the slave byte (with sync codes), and the end bit.

**Table 1: LVDS Packet Format in Stereoscropy Mode (Stereoscropy Mode Bit Asserted)**

18-Bit Packet	Function
Packet[0]	HIGH (Start bit)
Packet[1]	MasterSensorPixelData[2]
Packet[2]	MasterSensorPixelData[3]
Packet[3]	MasterSensorPixelData[4]
Packet[4]	MasterSensorPixelData[5]
Packet[5]	MasterSensorPixelData[6]
Packet[6]	MasterSensorPixelData[7]
Packet[7]	MasterSensorPixelData[8]
Packet[8]	MasterSensorPixelData[9]
Packet[9]	SlaveSensorPixelData[2]
Packet[10]	SlaveSensorPixelData[3]
Packet[11]	SlaveSensorPixelData[4]
Packet[12]	SlaveSensorPixelData[5]
Packet[13]	SlaveSensorPixelData[6]
Packet[14]	SlaveSensorPixelData[7]
Packet[15]	SlaveSensorPixelData[8]
Packet[16]	SlaveSensorPixelData[9]
Packet[17]	LOW (Stop bit)

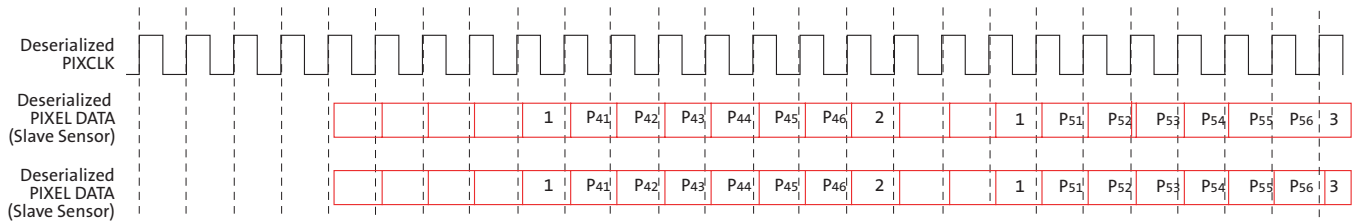
Control signals LV and FV can be reconstructed from their respective preceding and succeeding flags that are always embedded within the pixel data in the form of reserved words.

**Table 2: Reserved Words in the Pixel Data Stream**

Pixel Data Reserved Word	Flag
0	Precedes FV assertion
1	Precedes LV assertion
2	Succeeds LV De-assertion
3	Succeeds FV De-assertion

If the sensor provides a pixel whose value is 0, 1, 2, or 3 (that is, the same as a reserved word), then the outgoing serial pixel value is switched to 4.

**Figure 4: Serial Stereo Output Format for a 6 x 2 Frame**



Notes: 1. External pixel values of 0, 1, 2, 3 are reserved (they only convey control information). Any raw pixel of value 0, 1, 2, and 3 will be substituted with 4.

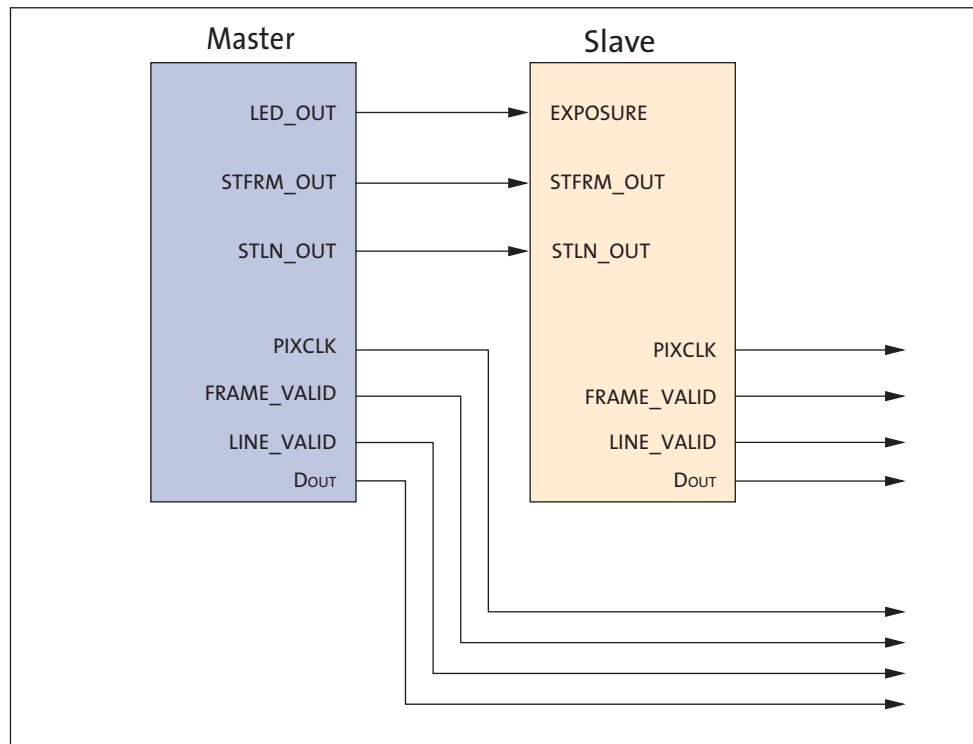
With the LVDS serial video output, the deserializer can be up to 5 meters from the sensor. The serial link can save on the cabling cost of 14 wires (DOUT[9:0], LV, FV, PIXCLK, GND). Instead, three wires (two serial LVDS, one GND) are sufficient to carry the video signal.

### Asynchronous Stereoscopic Mode

In addition to lockstep LVDS and parallel stereoscopy operation as described in this technical note, two MT9V022 Rev3 sensors with different clock domains can be synchronized using the connections illustrated in Figure 5.

The LED\_OUT, STFRM\_OUT, and STLN\_OUT signals from the master sensor control the EXPOSURE, STFRM\_OUT, and STLN\_OUT signals of the slave sensor.

**Figure 5: Master and Slave Connection for Asynchronous Stereoscopic Mode**





## Latency Between the Master and Slave Sensors

In asynchronous stereoscopic mode, there is a one-row-time latency between the master and slave sensors, that is, the exposure of slave sensor begins one row time after the master sensor does. The readout of the slave sensor also begins one row time after the master sensor readout.

## Conclusion

The MT9V022 sensors support three modes of operation: parallel stereoscopy, serial stereoscopy, and asynchronous stereoscopy. In both parallel stereoscopy and serial stereoscopy modes, the two sensor devices are required to run in lockstep mode for a pixel-synchronous stereo stream. In asynchronous-stereoscopy mode there is a one-row time latency between the two sensors.

For further information and assistance on this feature, contact your local AptinaFAE or refer to our Web site at [www.aptna.com](http://www.aptna.com).





## Revision History

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• Updated to Aptina template	
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• Made several minor edits to bring document in line with MarCom standard.	
• Updated metadata.	
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• Fixed minor typos, updated format.	
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• Updated "Stereo Serial Operation" on page 3	
• Updated "Stereo Serial Configuration" on page 5	
• Updated Figure 3, Stereoscopic Topology, on page 4	
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