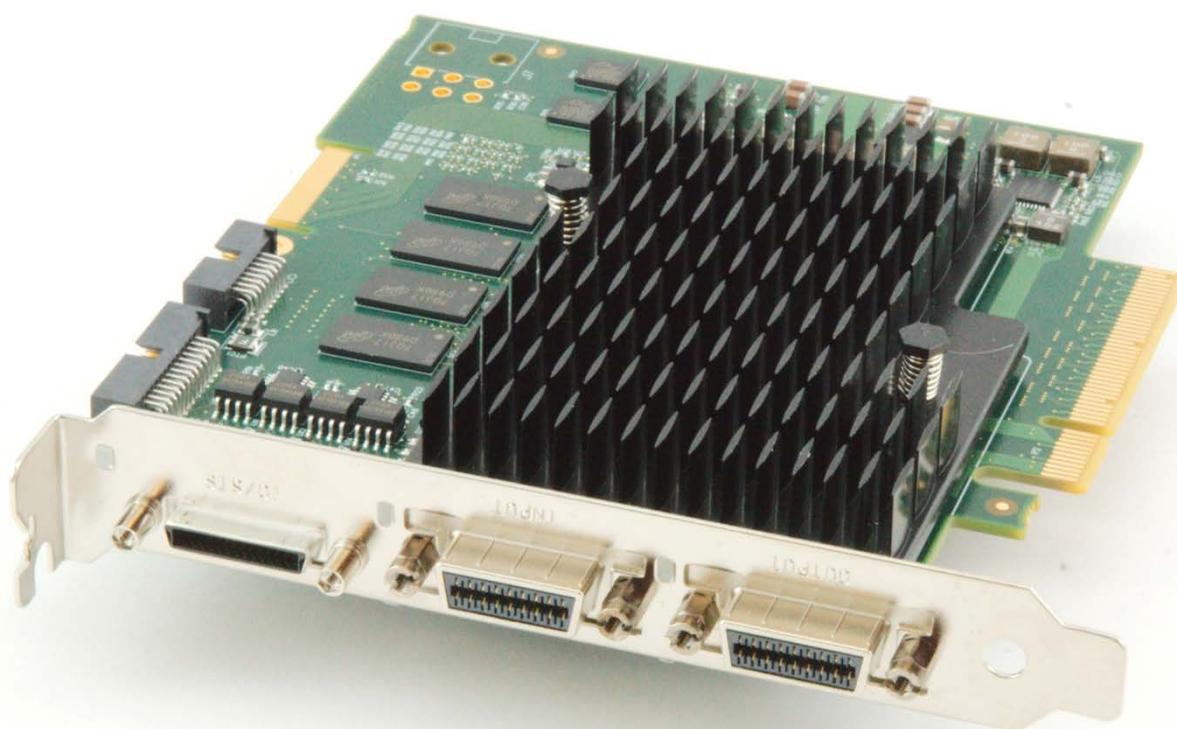


Xtium2-CLHS PX8™

User's Manual

Edition 1.30

sensors | cameras | **frame grabbers** | processors | software | vision solutions



P/N: OC-A8SM-PX8U0

Revision: 03

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About Teledyne DALSA

Teledyne DALSA, a business unit of Teledyne Digital Imaging, Inc., is an international high performance semiconductor and Electronics Company that designs, develops, manufactures, and markets digital imaging products and solutions, in addition to providing wafer foundry services.

Teledyne DALSA Digital Imaging offers the widest range of machine vision components in the world. From industry-leading image sensors through powerful and sophisticated cameras, frame grabbers, vision processors and software to easy-to-use vision appliances and custom vision modules.

Contents

OVERVIEW	6
PRODUCT PART NUMBERS	6
ABOUT THE XTNUM2-CLHS PX8 FRAME GRABBER	7
<i>Model Key Features</i>	7
<i>Series Key Features</i>	7
<i>User Programmable Configurations</i>	8
<i>ACUPlus: Acquisition Control Unit</i>	8
<i>DTE: Intelligent Data Transfer Engine</i>	9
<i>PCI Express x8 Gen3 Interface</i>	9
<i>Advanced Controls Overview</i>	9
DEVELOPMENT SOFTWARE OVERVIEW	10
<i>Sapera++ LT Library</i>	10
<i>Sapera Processing Library</i>	10
QUICK START SETUP & INSTALLATION	11
INSTALLING XTNUM2-CLHS PX8	15
WARNING! (GROUNDING INSTRUCTIONS)	15
INSTALLATION	15
<i>Hardware Installation</i>	15
Multi-board Data Forwarding Hardware Setup	15
Multi-board Sync & I/O Setup	15
<i>Sapera LT Library & Xtium2-CLHS PX8 Driver Installation</i>	16
Teledyne DALSA Device Drivers	16
Installation Procedure	16
<i>Xtium2-CLHS PX8 Firmware Loader</i>	17
Firmware Update: Automatic Mode	17
Firmware Update: Manual Mode	18
Executing the Firmware Loader from the Start Menu	19
UPGRADING SAPERA OR BOARD DRIVER	20
<i>Board Driver Upgrade Only</i>	20
<i>Upgrading both Sapera and Board Driver</i>	20
<i>Preserving Board Parameters during Driver Upgrade</i>	21
PRESERVING BOARD PARAMETERS DURING BOARD REPLACEMENT OR SYSTEM CLONING	22
DISPLAYING XTNUM2-CLHS PX8 BOARD INFORMATION	23
<i>Device Manager – Board Viewer</i>	23
<i>Information Field Description</i>	24
<i>Changing Device Settings</i>	26
<i>Device Information Report</i>	26
CONFIGURING SAPERA	27
<i>Viewing Installed Sapera Servers</i>	27
<i>Increasing Contiguous Memory for Sapera Resources</i>	27
Contiguous Memory for Sapera Messaging	28
CAMEXPRT QUICK START	29
INTERFACING CLHS CAMERAS WITH CAMEXPRT	29
SAPERA CAMERA CONFIGURATION FILES	31
<i>Camera Types & Files</i>	31
<i>Overview of Sapera Acquisition Parameter Files (*.ccf or *.cca/*.cvi)</i>	31
<i>Saving a Camera File</i>	32
<i>Camera Interfacing Check List</i>	32
USING CAMEXPRT WITH XTNUM2-CLHS PX8	33
BASIC TIMING CATEGORY	34

<i>Parameter Descriptions</i>	34
ADVANCED CONTROL CATEGORY	36
<i>Parameter Descriptions</i>	36
EXTERNAL TRIGGER CATEGORY	38
<i>Parameter Descriptions</i>	38
IMAGE BUFFER AND ROI CATEGORY	40
<i>Parameter Descriptions</i>	40
SAPERA DEMO APPLICATIONS	42
<i>Grab Demo Overview</i>	42
<i>Grab Demo Workspace Details</i>	42
<i>Using the Grab Demo</i>	43
XTIUM2-CLHS PX8 REFERENCE	44
BLOCK DIAGRAM	44
XTIUM2-CLHS FLOW DIAGRAM	45
CLHS CAMERA IMPLEMENTATION	46
LINE TRIGGER SOURCE SELECTION FOR LINE SCAN APPLICATIONS	46
<i>CORACQ_PRM_EXT_LINE_TRIGGER_SOURCE – Parameter Values Specific to</i>	
<i>the Xtium2-CLHS PX8</i>	47
SHAFT ENCODER INTERFACE TIMING	47
VIRTUAL FRAME TRIGGER FOR LINE SCAN CAMERAS	49
<i>Virtual Frame Trigger Timing Diagram</i>	49
Synchronization Signals for a 10 Line Virtual Frame	49
Synchronization Signals for Fixed Frame Length Acquisition	50
Synchronization Signals for Variable Frame Length Acquisition	51
SAPERA ACQUISITION METHODS	52
TRIGGER TO IMAGE RELIABILITY	53
<i>Supported Events and Transfer Methods</i>	53
Acquisition Events	53
Trigger Signal Validity	55
Supported Transfer Cycling Methods	55
OUTPUT LUT AVAILABILITY	57
METADATA: THEORY OF OPERATION	58
<i>Metadata Data Structure</i>	58
FLAT FIELD CORRECTION: THEORY OF OPERATION	59
<i>Flat Field Correction Lists</i>	59
<i>Flat Field Correction Sets</i>	60
Xtium2-CLHS PX8 specific limitations	60
Programming the sets	60
XTIUM2-CLHS PX8 SUPPORTED PARAMETERS	61
<i>Camera Related Capabilities</i>	61
<i>Camera Related Parameters</i>	61
<i>VIC Related Parameters</i>	62
<i>ACQ Related Parameters</i>	67
<i>Transfer Related Capabilities</i>	68
<i>Transfer Related Parameters</i>	68
<i>General Outputs #1: Capabilities (for GIO Module #0)</i>	69
<i>General Outputs #1: Parameters (for GIO Module #0)</i>	69
<i>General Inputs #1: Capabilities (for GIO Module #1)</i>	69
<i>General Inputs #1: Parameters (for GIO Module #1)</i>	69
<i>Bidirectional General I/Os: Capabilities (for GIO Module #2)</i>	70
<i>Bidirectional General I/Os: Parameters (for GIO Module #2)</i>	70
SAPERA SERVERS AND RESOURCES	71
TECHNICAL SPECIFICATIONS	72
XTIUM2-CLHS PX8 BOARD SPECIFICATIONS	72
HOST SYSTEM REQUIREMENTS	73

EMI CERTIFICATIONS	74
CONNECTOR AND SWITCH LOCATIONS	75
<i>Xtium2-CLHS PX8 Board Layout Drawing</i>	75
<i>Connector / LED Description List</i>	75
CONNECTOR AND SWITCH SPECIFICATIONS	76
<i>Xtium2-CLHS PX8 End Bracket Detail</i>	76
<i>Data Forwarding Setup</i>	77
<i>Connecting to Dual Output CLHS Camera</i>	79
<i>Status LEDs Functional Descriptions</i>	80
D1: Boot-up/PCIe Status LED	80
D3: Camera Link HS Status LED (when a camera is connected)	80
D3: Camera Link HS Status LED (as Data Forwarding receiver)	81
D6: Data Forwarding Status LED	81
<i>J2: Data Forwarding Connector</i>	81
<i>J3: Camera Link HS Connector</i>	82
<i>J1: External I/O Signals Connector (Female DH60-27P)</i>	82
<i>J4: Internal I/O Signals Connector (26-pin SHF-113-01-L-D-RA)</i>	82
Note 1: General Inputs / External Trigger Inputs Specifications	83
Block Diagram: Connecting External Drivers to General Inputs on J1	85
External Driver Electrical Requirements	85
Note 2: General Outputs /Strobe Output Specifications	86
Block Diagram: Connecting External Receivers to the General Outputs	87
External Receiver Electrical Requirements	87
Note 3: RS-422 Shaft Encoder Input Specifications	88
Example: Connecting to the RS-422 Shaft Encoder Block Diagram	89
Note 3.2: Interfacing to a TTL (also called Push-Pull) Output	90
Note 3.3: Interfacing to a Line Driver (also called Open Emitter) Output	90
Note 3.4: Interfacing to an Open Collector Output	91
<i>J5: Multi-Board Sync / Bi-directional General I/Os</i>	91
Hardware Preparation	91
Configuration via Sopera Application Programming	92
Configuration via Sopera CamExpert	92
CABLES & ACCESSORIES	94
<i>Camera Link HS Cables Overview and Resources</i>	94
<i>DH40-27S Cable to Blunt End (OR-YXCC-27BE2M1, Rev B1)</i>	95
<i>DH40-27S Connector Kit for Custom Wiring</i>	96
<i>Cable assemblies for I/O connector J4</i>	97
Teledyne DALSA I/O Cable (part #OR-YXCC-TIOF120)	97
Third Party I/O Cables for J4	97
<i>Board Sync Cable Assembly OR-YXCC-BSYNC40</i>	98
CAMERA LINK HS INTERFACE	99
CAMERA LINK HS OVERVIEW	99
<i>Rights and Trademarks</i>	99
APPENDIX A: SILENT INSTALLATION	100
SILENT MODE INSTALLATION	100
<i>Creating a Response File</i>	100
<i>Running a Silent Mode Installation</i>	101
SILENT MODE UNINSTALL	101
<i>Creating a Response File</i>	101
<i>Running a Silent Mode Uninstall</i>	101
SILENT MODE INSTALLATION RETURN CODE	102
INSTALLATION SETUP WITH CORAPPLAUNCHER.EXE	102
CUSTOM DRIVER INSTALLATION USING INSTALL.INI	103
<i>Creating the install.ini File</i>	103
<i>Run the Installation using install.ini</i>	103

APPENDIX B: TROUBLESHOOTING PROBLEMS	104
OVERVIEW	104
PROBLEM TYPE SUMMARY	104
<i>First Step: Check the Status LED</i>	104
<i>Possible Installation Problems</i>	104
<i>Possible Functional Problems</i>	105
TROUBLESHOOTING PROCEDURES	105
<i>Diagnostic Tool Overview</i>	105
Diagnostic Tool Main Window	106
Diagnostic Tool Self-Test Window	107
Camera Input Eye Diagram Monitor	107
Diagnostic Tool Live Monitoring Window	108
<i>Checking for PCI Bus Conflicts</i>	108
<i>Windows Device Manager</i>	110
<i>BSOD (blue screen) Following a Board Reset</i>	110
<i>Sapera and Hardware Windows Drivers</i>	110
<i>Recovering from a Firmware Update Error</i>	111
<i>Driver Information via the Device Manager Program</i>	112
<i>Teledyne DALSA Log Viewer</i>	113
<i>On-board Image Memory Requirements for Acquisitions</i>	113
<i>Symptoms: CamExpert Detects no Boards</i>	113
Troubleshooting Procedure	113
<i>Symptoms: Xtium2-CLHS PX8 Does Not Grab</i>	114
<i>Symptoms: Card grabs black</i>	114
<i>Symptoms: Card acquisition bandwidth is less than expected</i>	115
CONTACT INFORMATION	116
SALES INFORMATION	116
TECHNICAL SUPPORT	116

Figures

Figure 1: Automatic Firmware Update	17
Figure 2: Manual Firmware Update	18
Figure 3: Start Menu Firmware Update Shortcut	19
Figure 4: Device Manager Parameter Setting Differences	21
Figure 5: Firmware Update Status	22
Figure 6: Same Firmware For All Devices Checkbox	22
Figure 4: Board Information via Device Manager	23
Figure 5: Device Manager File Menu — Save Device Info Command	26
Figure 6: CamExpert Program	29
Figure 7: Xtium2-CLHS PX8 Block Diagram	44
Figure 8: Xtium2-CLHS Flow Diagram	45
Figure 9: CLHS Camera Interface	46
Figure 10: Encoder Input with Pulse-drop Counter	48
Figure 11: Using Shaft Encoder Direction Parameter	48
Figure 12: Synchronization Signals for a 10 Line Virtual Frame	50
Figure 13: Line scan, Fixed Frame, No Trigger	50
Figure 14: Line scan, Fixed Frame, Edge Trigger	51
Figure 15: Line scan, Fixed Frame, Level Trigger (Roll-Over to Next Frame)	51
Figure 16: Line scan, Variable Frame, Edge Trigger (Active High determines Frame Length)	51
Figure 17: Line scan, Fixed Frame, Level Trigger (Roll-Over)	52
Figure 18: EMI Certifications	74
Figure 19: Board Layout	75
Figure 20: End Bracket Details	76
Figure 21: Data Forwarding Block Diagram	78
Figure 22: Dual Camera Output Connection Block Diagram	79
Figure 23: General Inputs Electrical Diagram	83
Figure 24: External Trigger Input Validation & Delay	84
Figure 25: External Signals Connection Diagram	85
Figure 26: General Outputs Electrical Diagram	86
Figure 27: Output Signals Connection Diagram	87
Figure 28: RS-422 Shaft Encoder Input Electrical Diagram	88
Figure 29: External RS-422 Signals Connection Diagram	89
Figure 30: Interfacing TTL to RS-422 Shaft Encoder Inputs	90
Figure 31: Interfacing to a Line Driver Output	90
Figure 32: Interfacing to an Open Collector Output	91
Figure 33: DH60-27P Cable No. OR-YXCC-27BE2M1 Detail	95
Figure 34: Photo of cable OR-YXCC-27BE2M1	95
Figure 35: I/O Cable #OR-YXCC-TIOF120	97
Figure 36: Photo of cable OR-YXCC-BSYNC40	98
Figure 37: Create an install.ini File	103
Figure 38: Diagnostic Tool “Resource in use”	105
Figure 39: Diagnostic Tool User Interface	106
Figure 40: Diagnostic Tool Self-Test Window	107
Figure 41: Diagnostic Tool Eye Diagram	107
Figure 42: PCI Diagnostic Program	109
Figure 43: PCI Diagnostic Program – PCI bus info	109
Figure 44: Using Windows Device Manager	110
Figure 45: Board Firmware Version	112
Figure 46: PCI Diagnostic Tool BM Button	114

Overview

Product Part Numbers

Xtium2-CLHS PX8 Board

Item	Product Number
Xtium2-CLHS PX8 (PX8)	OR-A8S0-PX870
Xtium2-CLHS PX8 LC (PX8 LC)	OR-A8S0-PX840
Xtium2-CLHS PX8 HR (PX8 HR)	OR-A8S0-HX870
For OEM clients, this manual in printed form, is available on request	OC-A8SM-PX8U0

Xtium2-CLHS PX8 Software

Item	Product Number
Sapera LT version 8.30 or later for full feature support (required but sold separately) <ol style="list-style-type: none">1. Sapera LT: Provides everything needed to build imaging application2. Current Sapera compliant board hardware drivers3. Sapera documentation: (compiled HTML help, Adobe Acrobat® (PDF)	OC-SL00-0000000
<i>(optional)</i> Sapera Processing Imaging Development Library includes over 600 optimized image-processing routines.	Contact Sales at Teledyne DALSA

Optional Xtium2-CLHS PX8 Cables & Accessories

Item	Product Number
DH40-27S cable assembly to blunt end: 6 ft. cable I/O 27 pin Hirose connector to blunt end. This cable assembly connects to J1.	OR-YXCC-27BE2M1
Cable set to connect to J4 Internal I/O Signals connector (J4: 26-pin SHF-113-01-L-D-RA)	see suggested cables
DH40-27S Connector Kit for Custom Wiring: Comprised of a DH40-27S connector plus screw lock housing kit	OR-YXCC-H270000
Cable assembly to connect to J5 (Board Sync) Connecting 2 boards Connection 3 or 4 boards	OR-YXCC-BSYNC20 OR-YXCC-BSYNC40
CX4 Cable:	Contact Sales at Teledyne DALSA

About the Xtium2-CLHS PX8 Frame Grabber



Model Key Features

Feature / Model	PX8	PX8 LC	PX8 HR
Maximum number of lanes	7	4	7
Flat Field Correction (FFC) Flat Line Correction (FLC)	Yes	No	Yes
High Dynamic Range (HDR)	Yes	No	Yes
Linea HS 32K	No	No	Yes
Linea HS Color/MF3 Plane Alignment	No	No	Yes

Series Key Features

- Compliant with Camera Link HS (CLHS) specification version 1.0 (X-Protocol) (visit <http://www.visiononline.org/vision-standards.cfm> for details on industry standards)
- Supports up to 7 lanes.
- Bit transfer rate of 10 Gbps (requires cable length of less than 3m)
- The specification defines a device discovery methodology that can be automated and which provides plug and play capability
- Camera Link HS cameras implement GenICam and associated GenCP, thus resulting in ease of use for Teledyne DALSA or third party cameras
- Uses a PCIe x8 Gen3 slot to maximize transfers to host computer buffers
- Acquire from Monochrome and RGB CLHS cameras, both area scan and linescan
- Output lookup tables
- Vertical and Horizontal Flip supported on board
- External Input Triggers and Shaft Encoder inputs, along with Strobe outputs
- Supports Data Forwarding Mode, where camera image data is automatically transferred to one or more Xtium2-CLHS boards (each installed in a separate computer), allowing distributed processing of the acquisition.
- Supports Multi-board Sync for trigger events, to simultaneously acquire from multiple cameras.
- Supports a number of acquisition events in compliance with "Teledyne DALSA's Trigger to Image Reliability"
- RoHS compliant

See Technical Specifications for detailed information.

User Programmable Configurations

Use the Xtium2-CLHS PX8 firmware loader function in the Teledyne DALSA Device manager utility to select firmware for one of the supported modes. Firmware selection is made either during driver installation or manually later on (see Firmware Update: Manual Mode). Currently there is only one firmware version available:

- **Camera Link HS camera** (*installation default*):
Support for 1 Camera Link HS camera: either monochrome 8/10/12/14/16 bits per pixel or RGB 8 bits per pixel.

ACUPlus: Acquisition Control Unit

ACUPlus consists of a grab controller, one pixel packer and one time base generator.

ACUPlus acquires variable frame sizes up to 128KB per horizontal line and up to 16 million lines per frame. ACUPlus can also capture an infinite number of lines from a line scan camera without losing a single line of data.

DTE: Intelligent Data Transfer Engine

The Xtium2-CLHS PX8 intelligent Data Transfer Engine ensures fast image data transfers between the board and the host computer with zero CPU usage. The DTE provides a high degree of data integrity during continuous image acquisition in a non-real time operating system like Windows. DTE consists of intelligent DMA units with auto-loading Scatter-Gather tables.

PCI Express x8 Gen3 Interface

The Xtium2-CLHS PX8 is a universal PCI Express x8 Gen3 board, compliant with the PCI Express 3.0 specification. The Xtium2-CLHS PX8 board achieves transfer rates up to 7.0Gbytes/sec. to host memory. Note that performance can be lower depending on PC and/or programmed configuration.

The Xtium2-CLHS PX8 board occupies one PCI Express x8 Gen3 expansion slot and one chassis opening.

Important:

- To obtain the maximum transfer rate to host memory, make sure the Xtium2-CLHS PX8 is in a computer with a Gen3 slot. The board will work in a Gen1, Gen2 or Gen3 slot, but only with a quarter or half the possible transfer performance respectively.
- The system motherboard BIOS should allow setting the PCIe maximum payload size to 256 or higher. Systems with fixed settings of 128 will limit performance for transfers to host memory.
- If the computer only has a PCI Express x16 slot, test directly (use the supplied diagnostic tool) or review the computer documentation to know if the Xtium2-CLHS PX8 is supported. Computer motherboards may only support x16 graphic video board products in x16 slots.

Advanced Controls Overview

Visual Indicators

Xtium2-CLHS PX8 features 3 LED indicators to facilitate system installation and setup (see [Status LEDs Functional Descriptions](#)). These indicators provide visual feedback on the board status and camera status.

External Event Synchronization

Trigger inputs and strobe signals precisely synchronize image captures with external events.

Camera Link HS Communication Port

A single Sopera LT Acquisition Device provides access to the Camera Link HS camera configuration via the board device driver. The communication port presents a seamless interface to access GenICam camera features.

Quadrature Shaft Encoder

An important feature for web scanning applications, the Quadrature Shaft Encoder inputs allow synchronized line captures from external web encoders (see [J1- I/O Connector](#)). The Xtium2-CLHS PX8 provides a RS-422 input that supports a tick rate of up to 5MHz.

Development Software Overview

Sapera++ LT Library

Sapera++ LT is a powerful development library for image acquisition and control. Sapera++ LT provides a single API across all current and future Teledyne DALSA hardware. Sapera++ LT delivers a comprehensive feature set including program portability, versatile camera controls, flexible display functionality and management, plus easy to use application development wizards. Applications are developed using either C++ or .NET frameworks.

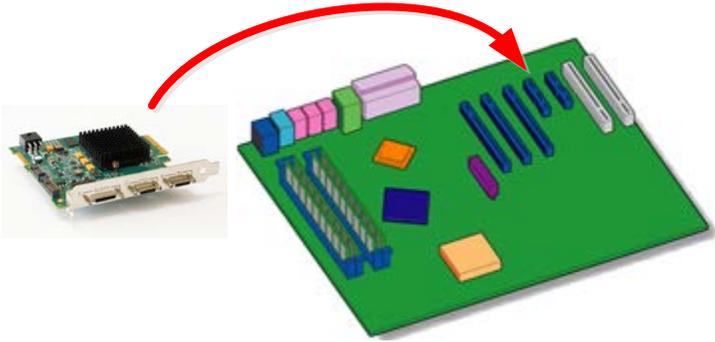
Sapera++ LT comes bundled with CamExpert, an easy to use camera configuration utility to create new, or modify existing camera configuration files.

Sapera Processing Library

Sapera Processing is a comprehensive set of C++ classes or .NET classes for image processing and analysis. Sapera Processing offers highly optimized tools for image processing, blob analysis, search (pattern recognition), OCR and barcode decoding.

Quick Start Setup & Installation

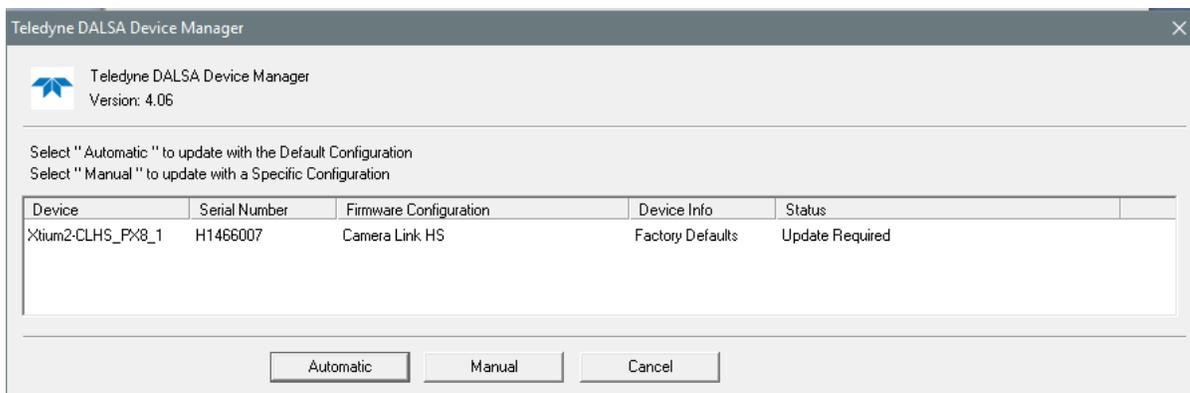
The following procedure outlines the basic steps required to install the Teledyne DALSA Xtium2-CLHS PX8. For complete installation details and information, see [Installing Xtium2-CLHS PX8](#).

<p>1</p>	<p>Install the Xtium2-CLHS PX8 in an available PCIe x8 slot on the host computer.</p> 						
<p>2</p>	<p>Download and install the Spera LT SDK software from the Teledyne DALSA website. http://teledynedalsa.com/imaging/support/downloads/sdks/</p>  <p>Software Development Kits</p> <p>Access to certain drivers and SDK updates are restricted to Teledyne DALSA customers that have registered their development package (SDK). If you have not yet done so, please register your software before proceeding.</p> <table border="1"><thead><tr><th>Description</th><th>Version</th><th>Release Date</th></tr></thead><tbody><tr><td>Spera LT SDK (full version) - Free Download</td><td>8.20</td><td>10/28/2016</td></tr></tbody></table>	Description	Version	Release Date	Spera LT SDK (full version) - Free Download	8.20	10/28/2016
Description	Version	Release Date					
Spera LT SDK (full version) - Free Download	8.20	10/28/2016					
<p>3</p>	<p>Download and install the Xtium2-CLHS PX8 device driver from the Teledyne DALSA website. https://www.teledynedalsa.com/imaging/support/downloads/drivers/</p>						



4

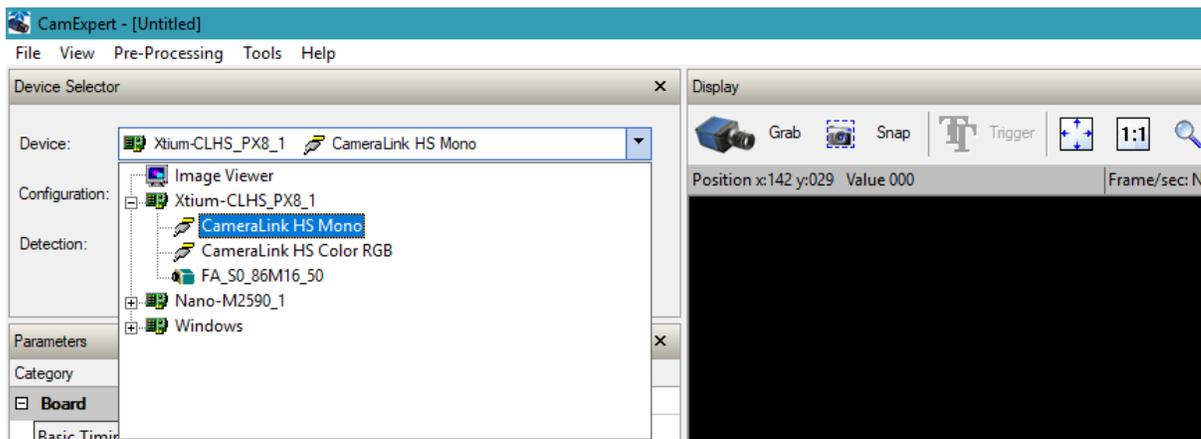
To complete the installation, update the [Xtium2-CLHS PX8 firmware](#) when prompted; select Automatic to update the firmware (only one firmware option is available, support for one Camera Link HS camera).



Reboot when all software and board drivers are installed.

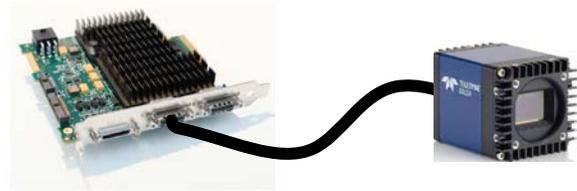
5

Launch [Sapera LT CamExpert](#) to verify the installation; the board should be present in the list of available devices.



6

Connect camera to the board Camera Link HS input connector. Ensure camera is properly powered.



7

When CamExpert detects a camera (as per the CLHS device discovery protocol), camera parameters are displayed along with the board parameters.

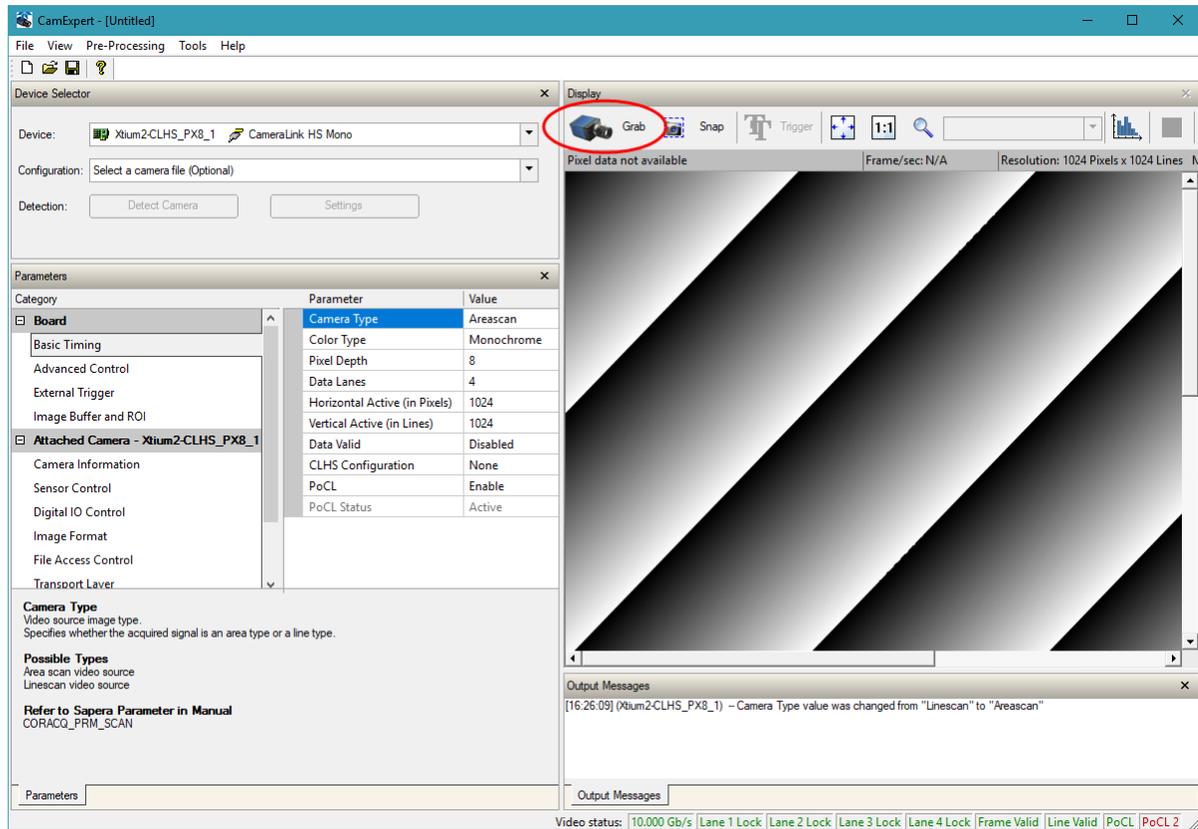
Parameters		Parameter	Value
Board		Camera Type	Areascan
Basic Timing		Color Type	Monochrome
Advanced Control		Pixel Depth	8
External Trigger		Data Lanes	7
Image Buffer and ROI		Horizontal Active (in Pixels)	16384
		Vertical Active (in Lines)	1024
Attached Camera - Xtium2-CL...		Data Valid	Disabled
Camera Information		CLHS Configuration	None
Sensor Control		PoCL	Enable
Digital IO Control		PoCL Status	Active
Image Format			
File Access Control			
Transport Layer			
Acquisition and Transfer Control			
Camera Simulator Settings			

When properly connected, the video status bar displays camera signals in green.

Video status: 10.000 Gb/s Lane 1 Lock Lane 2 Lock Lane 3 Lock Lane 4 Lock Lane 5 Lock Lane 6 Lock Lane 7 Lock Frame Valid Line Valid PoCL PoCL 2

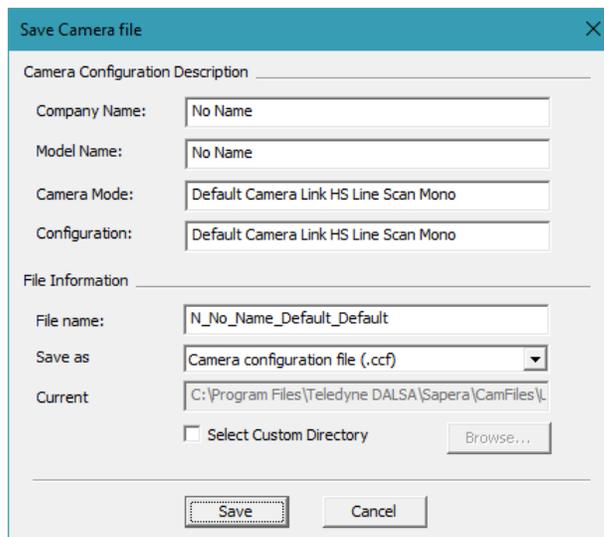
8

Click Grab to acquire a test image to validate the setup.



9

Modify the board and camera parameters as necessary. When completed, save the camera configuration file.



The Xtium2-CLHS PX8 can be configured using the parameter settings in this file when using the Sapera LT API in your application to acquire images

Installing Xtium2-CLHS PX8

Warning! (Grounding Instructions)

Static electricity can damage electronic components. Please discharge any static electrical charge by touching a grounded surface, such as the metal computer chassis, before performing any hardware installation. If you do not feel comfortable performing the installation, please consult a qualified computer technician.



Important: Never remove or install any hardware component with the computer power on. Disconnect the power cord from the computer to disable the power standby mode. This prevents the case where some computers unexpectedly power up when a board is installed.

Installation

The installation sequence is as follows:

- Install the board hardware into an available PCI Express x8 Gen3 slot.
- Turn on the computer.
- Install the Sapera LT Development Library or only its 'runtime library'.
- Install the Xtium2-CLHS PX8 Sapera board driver.
- Update the board firmware if required.
- Reboot the computer.
- Connect a CLHS camera and test.



For information on performing a silent installation, refer to Appendix A: Silent Installation. For troubleshooting installation problems, refer to Appendix B: Troubleshooting Problems.

Hardware Installation

- Turn the computer off, disconnect the power cord (disables power standby mode), and open the computer chassis to allow access to the expansion slot area.
- Install the Xtium2-CLHS PX8 into a free PCI Express x8 Gen3 expansion slot. Note that some computer's x16 slot may support boards such as the Xtium2-CLHS PX8, not just display adapters.
- Close the computer chassis and turn the computer on.
- Logon to the computer as administrator or with an account that has administrator privileges.
- Connect a CLHS camera to J3 after installing Sapera as described below. Test with CamExpert.

Multi-board Data Forwarding Hardware Setup

- For distributed processing applications, see Data Forwarding Setup for information about data forwarding cabling with one to six Xtium2-CLHS boards.

Multi-board Sync & I/O Setup

- For multi-board sync applications, see J5: Multi-Board Sync / Bi-directional General I/Os for information on using two to four Xtium2-CLHS boards in one computer.

Sapera LT Library & Xtium2-CLHS PX8 Driver Installation

Sapera LT SDK (full version), the image acquisition and control SDK for Teledyne DALSA cameras and frame grabbers is available for download from the Teledyne DALSA website:

<http://teledynedalsa.com/imaging/support/downloads/sdks/>

Run-time versions are also available for download at this location.



Software Development Kits

Access to certain drivers and SDK updates are restricted to Teledyne DALSA customers that have registered their development package (SDK). If you have not yet done so, please [register your software](#) before proceeding.

Description	Version	Release Date
Sapera LT SDK (full version) - Free Download	8.30	05/19/2017



The Sapera LT SDK installation includes compiled demo and example programs, along with project source code, in both C++ and .NET languages, for most Microsoft Visual Studio development platforms. The Sapera LT ++ and Sapera LT .NET demo source code are found in the Sapera\Demos directory.

Refer to *Sapera LT User's Manual* for additional details about Sapera LT.

Teledyne DALSA Device Drivers

All Teledyne DALSA device drivers are available for download from the Teledyne DALSA website:

<https://www.teledynedalsa.com/imaging/support/downloads/drivers/>

Installation Procedure

- Sapera LT is installed before Teledyne DALSA board drivers.
- Download the Sapera LT SDK from the Teledyne DALSA website and run the executable file; the installation menu is presented.
- The installation program may prompt to reboot the computer. It is not necessary to reboot the computer between the installation of Sapera LT and the board driver.
- Download the Xtium2-CLHS PX8 device driver from the Teledyne DALSA website and run the executable file; the installation menu is presented.
- During the late stages of the installation, the Xtium2-CLHS PX8 firmware loader application starts.
- Reboot when all software and board drivers are installed.



If Windows displays any unexpected message concerning the board, power off the system and verify the Xtium2-CLHS PX8 is installed in the slot properly. You should also note the board's status LED color and compare it to the defined LED states as described in [D1: Boot-up/PCIe Status LED](#).

Xtium2-CLHS PX8 Firmware Loader

The Device Manager-Firmware Loader program automatically executes at the end of the driver installation and on every subsequent reboot of the computer. It will determine if the Xtium2-CLHS PX8 requires a firmware update. If firmware is required, a dialog displays. This dialog also allows the user to load alternative firmware if available for the Xtium2-CLHS PX8.

Important: In the rare case of firmware loader errors please see Recovering from a Firmware Update Error.

Firmware Update: Automatic Mode

Click Automatic to update the Xtium2-CLHS PX8 firmware. The Xtium2-CLHS PX8 currently supports one firmware configuration.

See User Programmable Configurations for details on all supported modes, selected via a manual update of alternative firmware.

With multiple Xtium2-CLHS PX8 boards in the system, all boards update with new firmware. If any installed Xtium2-CLHS PX8 board installed in a system already has the correct firmware version, an update is not required. In the following screen shot, a single Xtium2-CLHS PX8 board is installed and ready for a firmware upgrade.

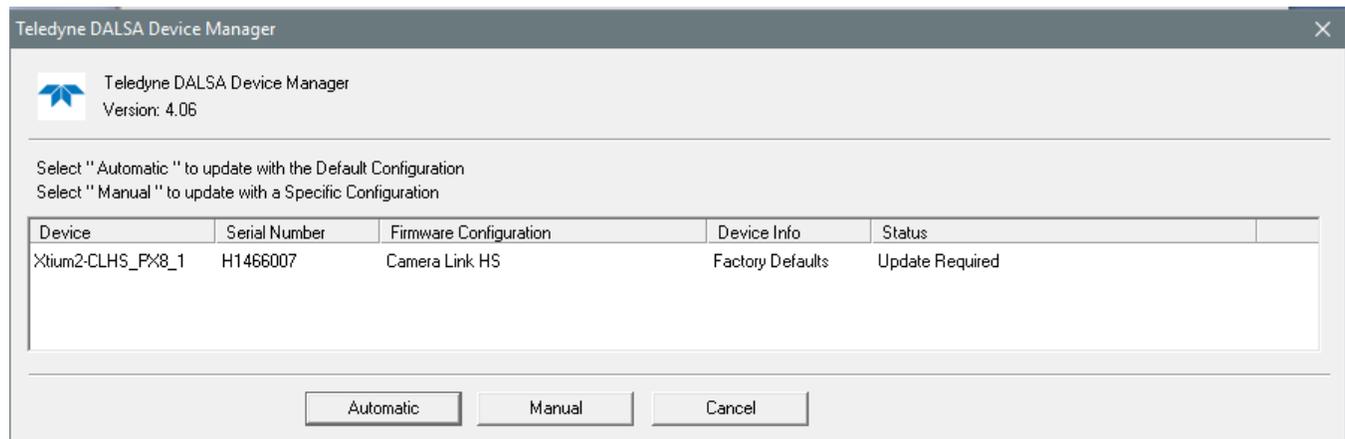


Figure 1: Automatic Firmware Update

Firmware Update: Manual Mode

Select Manual mode to load firmware other than the default version or when, in the case of multiple Xtium2-CLHS PX8 boards in the same system, if each requires different firmware.

The following figure shows the Device Manager manual firmware screen. Displayed is information on all installed Xtium2-CLHS PX8 boards, their serial numbers and their firmware components.

Performing a Manual Firmware Update

- Select the Xtium2-CLHS PX8 to update via the board selection box (if there are multiple boards in the system).
- From the Configuration field drop menu select the firmware version required (typical required or offered to support different CLHS cameras).
- Click on the Start Update button.
- Observe the firmware update progress in the message output window.
- Close the Device manager program when the device reset complete message shows.

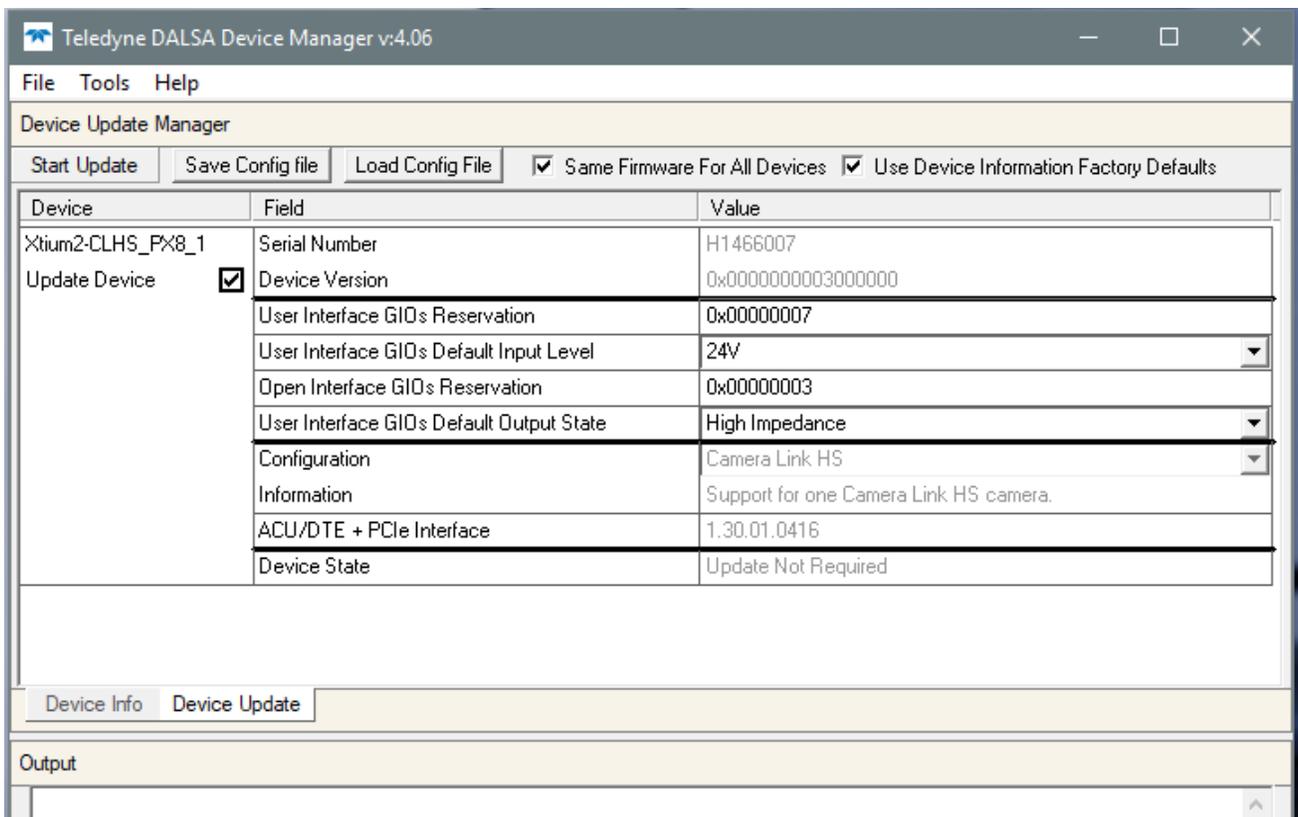


Figure 2: Manual Firmware Update

Executing the Firmware Loader from the Start Menu

If required, the Xtium2-CLHS PX8 Firmware Loader program is executed via the Windows Start Menu shortcut **Start • Programs • Teledyne DALSA • Xtium2-CLHS PX8 Driver • Firmware Update**.

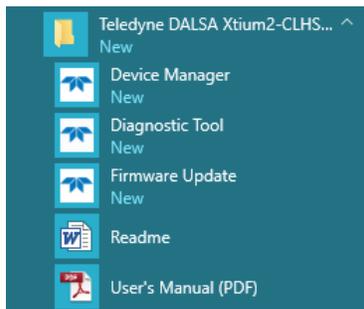


Figure 3: Start Menu Firmware Update Shortcut

A firmware change after installation is required to select a different configuration mode, if available; see User Programmable Configurations.

Upgrading Sapera or Board Driver

When installing a new version of Sapera or a Teledyne DALSA acquisition board driver in a computer with a previous installation, the current version **must** be un-installed first. Described below are two upgrade situations. Note that if the board is installed in a different slot, the new hardware wizard opens. Answer as instructed in the section Installation.

Board Driver Upgrade Only

Minor upgrades to acquisition board drivers are distributed as ZIP files available in the Teledyne DALSA web site www.teledynedalsa.com/mv/support. Board driver revisions are also available on the next release of the Sapera Essential CD-ROM.

Often minor board driver upgrades do not require a new revision of Sapera. To confirm that the current Sapera version will work with the new board driver:

- Check the new board driver ReadMe file before installing, for information on the minimum Sapera version required.
- If the ReadMe file does not specify the Sapera version required, contact Teledyne DALSA Technical Support (see Technical Support).

To upgrade the board driver only:

- Logon the computer as an administrator or with an account that has administrator privileges.
- In **Windows 7**, from the start menu select **Start • Settings • Control Panel • Programs and Features**. Double-Click the Teledyne DALSA Xcelera board driver and click **Remove**.
- In **Windows 8 & Windows 10**, just type Control Panel while in the start screen, or click the arrow in the lower left side to bring up the all applications window. Select Programs and Features, then double-click the Teledyne DALSA Xcelera board driver and click **Remove**.
- Install the new board driver. Run **Setup.exe** if installing manually from a downloaded driver file.
- **Important:** You cannot install a Teledyne DALSA board driver without Sapera LT installed on the computer.

Upgrading both Sapera and Board Driver

When upgrading both Sapera and the acquisition board driver, follow the procedure described below.

- Logon the computer as an administrator or with an account that has administrator privileges.
- In **Windows 7**, from the start menu select **Start • Settings • Control Panel • Programs and Features**. Double-click the Teledyne DALSA Xcelera board driver and click **Remove**. Follow by also removing the older version of Sapera LT.
- In **Windows 8 & Windows 10**, just type Control Panel while in the start screen, or click the arrow in the lower left side to bring up the all applications window. Select Programs and Features, then double-click the Teledyne DALSA Xcelera board driver and click **Remove**. Follow by also removing the older version of Sapera LT.
- Reboot the computer and logon the computer as an administrator again.
- Install the new versions of Sapera and the board driver as if this was a first time installation. See Sapera LT Library & Xtium2-CLHS PX8 Driver Installation for installation procedures.

Preserving Board Parameters during Driver Upgrade

User defined parameter settings for previously installed boards can be preserved when upgrading a device driver by using an *install.ini* file as described in the [Custom Driver Installation using install.ini](#) section. Clicking **Automatic** on the Device Manager Start-up dialog will apply the settings specified in the *install.ini* file.

To verify the settings specified in the *install.ini* file, click **Manual**; differences between the current device settings are shown in **green** in both the Device Info and Device Update tabs.

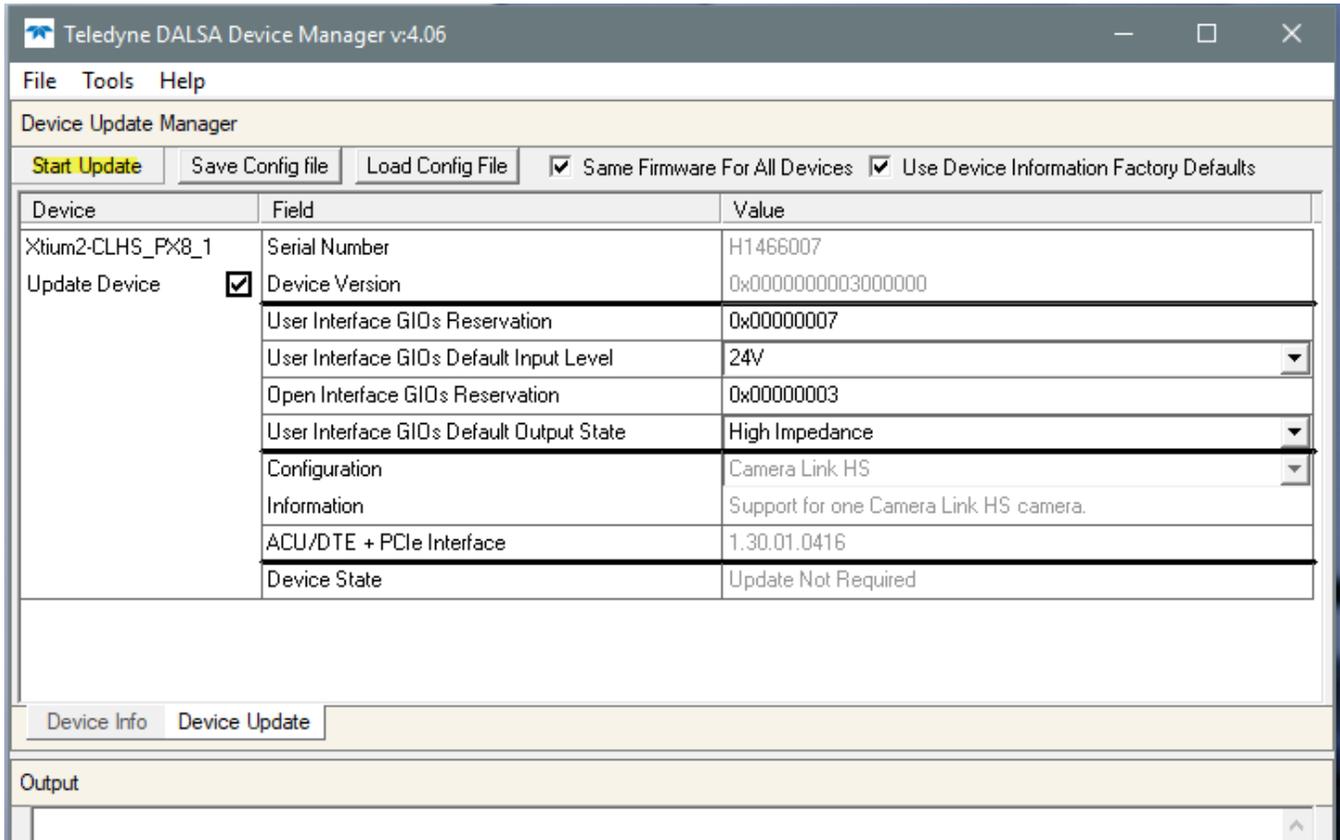


Figure 4: Device Manager Parameter Setting Differences

Upgrading without an *install.ini* file requires selecting **Manual** update on the Device Manager Start-up dialog and setting the required parameters manually.



Note: Without an *install.ini*, configuration information is not preserved and is always set to factory default.

Preserving Board Parameters during Board Replacement or System Cloning

When replacing a board in a system or cloning a system configuration using a harddrive image, if the previous device parameter settings differ from the factory default driver settings it is indicated as "User Defined" or "Manual Configuration" in the Teledyne DALSA Device Manager start-up dialog under the Device Info column. User-defined settings are specific to the PCI Express slot on the system.

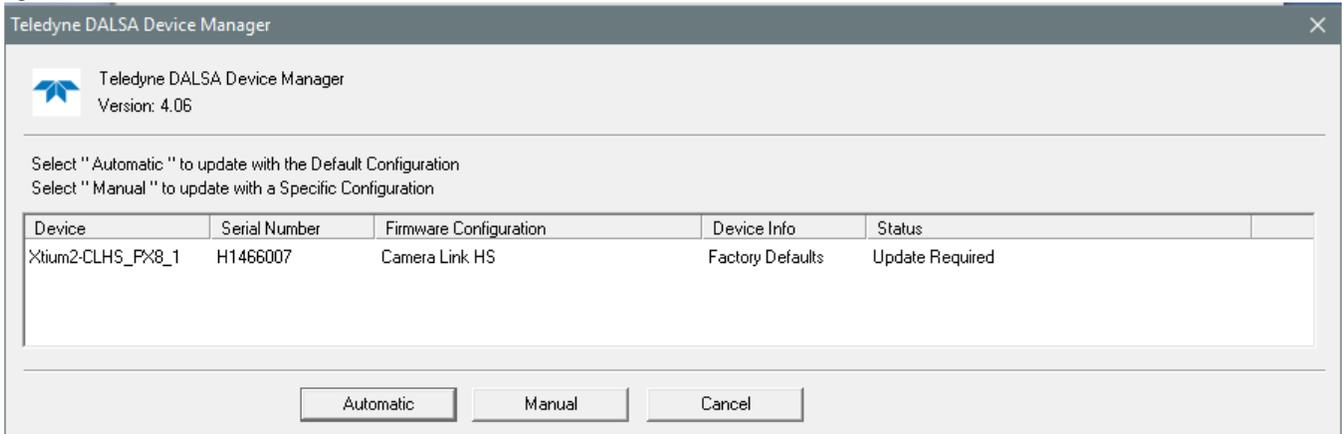


Figure 5: Firmware Update Status

To preserve the user defined parameter settings, select "Manual" and proceed with the update; differences between the current settings are shown in green in both the Device Info and Device Update tabs.

For systems with multiple boards, if boards use different firmware configurations, disable the **Same Firmware For All Devices** option (otherwise the configuration specified for the first board according to slot position is applied to all boards in the system).

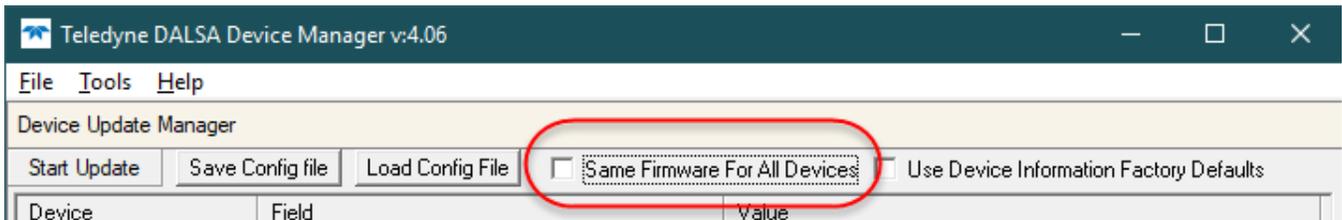
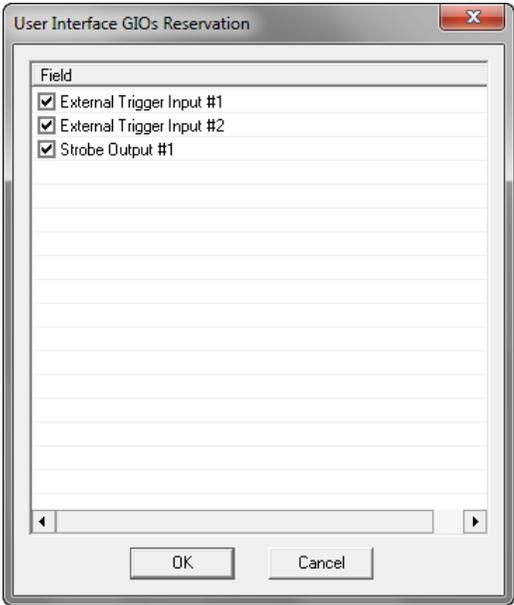
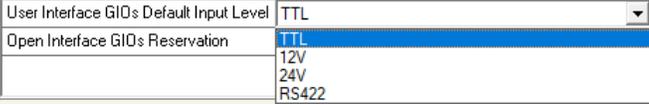
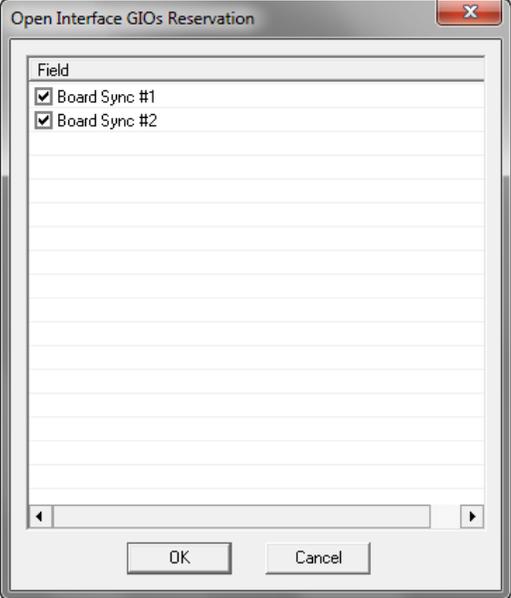
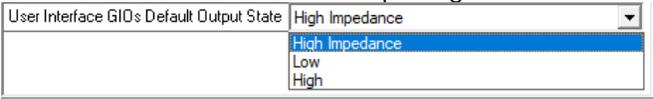


Figure 6: Same Firmware For All Devices Checkbox

Information Field Description

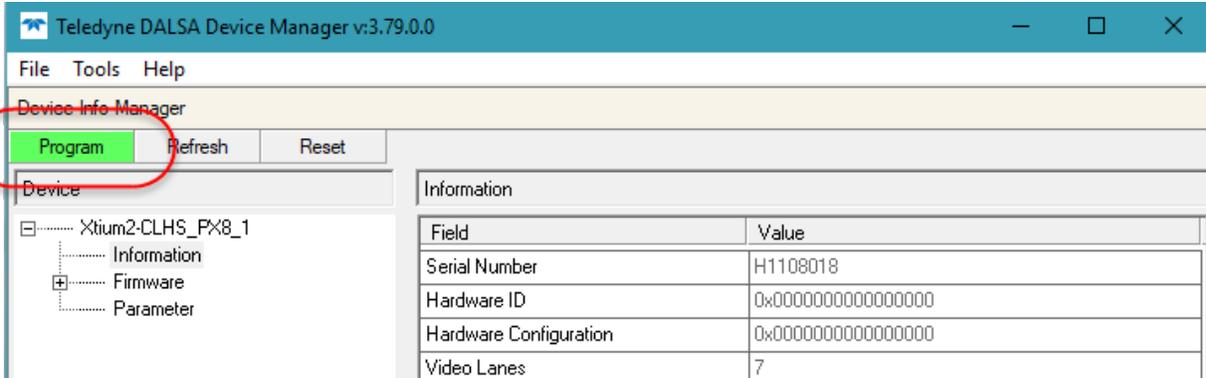
Field	Description
Serial Number	[Read-Only]: Serial Number of the board.
Hardware ID	[Read-Only]: Identifies hardware changes that affect the operation of the board.
Hardware Configuration	[Read-Only]: States the presence or absence of optional components. Currently there are no optional components available.
Video Lanes	[Read-Only]: Indicates the maximum number of video lanes supported by the board. Xtium2-CLHS PX8: The value is 7. Xtium2-CLHS PX8 LC: The value is 4. Xtium2-CLHS PX8 HR: The value is 7.
User Interface Outputs	[Read-Only]: Number of available user interface outputs on the board. For this board, the value is 8.
P/N	[Read-Only]: Indicates the part number of the board. OR-A8S0-PX870, OR-A8S0-PX840 or OR-A8S0-HX870.
P/N Revision	[Read-Only]: Indicates the revision of the part number.
User Data	[Read/Write]: This is a 64 byte general purpose user storage area. For information on how to read/write this field at the application level, contact Teledyne DALSA Technical Support.
User Interface GIOs Reservation	<p>[Read/Write]: Use this field to reserve User Interface GIOs for use by the acquisition module. By default, boards are shipped with User Interface General Inputs 1 & 2 reserved for External Triggers and User Interface General Output 1 reserved for Strobe Output.</p> <p>Click on the 'Value' field to open the dialog box show below. Disable any GIO reservations that are not required. Click the OK button to update the value field.</p> 

<p>User Interface GIOs Default Input Level</p>	<p>[Read/Write]: Use this field to select the default input level of the User Interface GIOs. Click on the 'Value' field to select the input signal level detection required.</p>  <p>By default, boards are shipped with User Interface General Inputs set to 24V. Note that the input level can also be modified at the application level.</p>
<p>Open Interface GIOs Reservation</p>	<p>[Read/Write]: Use this field to reserve Open Interface GIOs for use by the acquisition module. To specify the open interface GIO reservations, click on the 'Value' field to open the Open Interface GIOs Reservation dialog box. Disable any GIO reservations that are not required. Click OK to update the value field.</p>  <p>By default, boards are shipped with Open Interface GIOs 1 & 2 reserved for Board Sync 1 & 2.</p>
<p>User Interface GIOs Default Output State</p>	<p>[Read/Write]: Use this field to select the default Output State of the User Interface GIOs. Click on the 'Value' field to select the input signal level detection required.</p>  <p>By default, boards are shipped with User Interface General Outputs set to High Impedance.</p> <p>Note that the output state can also be modified at the application level.</p>

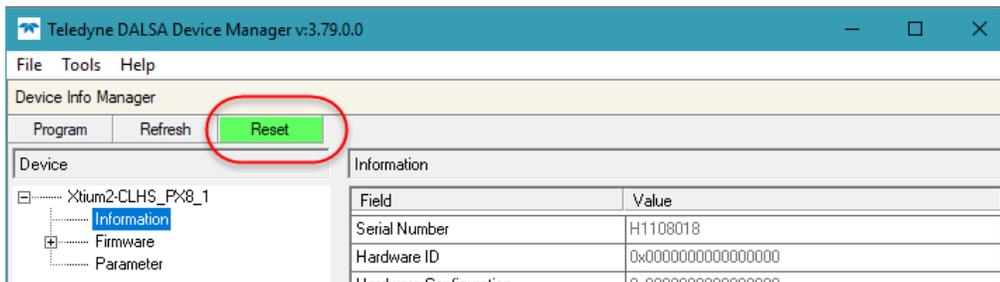
Changing Device Settings

When device settings are changed, the board must be programmed and reset to effect the changes.

If board programming is required, the Program button is displayed in green; click the button to start programming.



When programming is complete, the Reset button is displayed in green, click the button to reset the board.



Device Information Report

Teledyne DALSA Technical Support may request device information report to aid in troubleshooting installation or operational problems. Generate the Xtium2-CLHS PX8 device manager report file (BoardInfo.txt) by clicking **File • Save Device Info**.

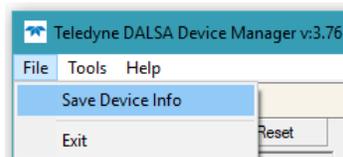


Figure 8: Device Manager File Menu — Save Device Info Command

Configuring Sopera

Viewing Installed Sopera Servers

The Sopera configuration program (**Start • Programs • Teledyne DALSA • Sopera LT • Sopera Configuration**) allows the user to see all available Sopera servers for the installed Sopera-compatible boards. The **System** entry represents the system server. It corresponds to the host machine (your computer) and is the only server that should always be present.

Increasing Contiguous Memory for Sopera Resources

The **Contiguous Memory** section lets the user specify the total amount of contiguous memory (a block of physical memory, occupying consecutive addresses) reserved for the resources needed for **Sopera buffers** allocation and **Sopera messaging**. For both items, the **Requested** value dialog box shows the 'CorMem' driver default memory setting while the **Allocated** value displays the amount of contiguous memory allocated successfully. The default values will generally satisfy the needs of most applications.

The Sopera buffers value determines the total amount of contiguous memory reserved at boot time for the allocation of dynamic resources used for frame buffer management such as scatter-gather list, DMA descriptor tables plus other kernel needs. Adjust this value higher if your application generates any out-of-memory error while allocating host frame buffers or when connecting the buffers via a transfer object.

You can approximate the worst-case scenario amount of contiguous memory required as follows:

- Calculate the total amount of host memory used for one frame buffer
[number of pixels per line * number of lines * (2 if buffer is 10/12/14 or 16 bits)]
-
- Provide 200 bytes per frame buffer for Sopera buffer resources.
- Provide 64 bytes per frame buffer for metadata. Memory for this data is reserved in chunks of 64kB blocks.
- Provide 48 bytes per frame buffer for buffer management. Memory for this data is reserved in chunks of 64kB blocks.
- For each frame buffer DMA table, allocate 24 bytes + 8 bytes for each 4kB of buffer. For example, for a 120x50x8 image:
 $120 * 50 = 6000 = 1.46 \text{ 4kB blocks} \rightarrow \text{roundup to 2 4kB blocks.}$
- Therefore $24 \text{ bytes} + (2 * 8 \text{ bytes}) = 40 \text{ bytes}$ for DMA tables per frame buffer.
- Memory for this data is reserved in chunks of 64kB blocks.
- If vertical flipping is enabled, one must add 16 bytes per line per buffer.
- For example, for an image 4080x3072 image:
 $16 \text{ bytes} * 3072 = 49152 \text{ bytes}$



Note 1: Sopera LT reserves the 1st 5MB for its own resources, which includes the 200 bytes per frame buffer mentioned above.

Note 2: starting with Sopera LT 8.41, contiguous memory can be allocated anywhere in PC memory using the 'Buffer Allocation (64-bit)' entry in Sopera Configuration Tool. Driver will use this memory 1st for frame buffer DMA tables.

- Test for any memory error when allocating host buffers. Simply use the Buffer menu of the Sopera Grab demo program (see Grab Demo Overview) to allocate the number of host buffers required for your acquisition source. Feel free to test the maximum limit of host buffers possible on your host system – the Sopera Grab demo will not crash when the requested number of host frame buffers is not allocated. The following calculation is an example of the amount of contiguous memory to reserve beyond 5MB with 80,000 buffers of 2048x1024x8:

- a) $(80000 * 64 \text{ bytes})$
- b) $(80000 * 48 \text{ bytes})$
- c) $(80000 * (24 + (((2048*1024)/4\text{kB}) * 8))) = 323\text{MB}$
- d) Total = a (rounded up to nearest 64kB) + b (rounded up to nearest 64kB) + c (rounded up to nearest 64kB).

Host Computer Frame Buffer Memory Limitations

When planning a Sapera application and its host frame buffers used, plus other Sapera memory resources, do not forget the Windows operating system memory needs.

A Sapera application using the preferred scatter gather buffers could consume most of the remaining system memory, with a large allocation of frame buffers. If using frame buffers allocated as a single contiguous memory block, Windows will limit the allocation dependent on the installed system memory. Use the Buffer menu of the Sapera Grab demo program to allocate host buffer memory until an error message signals the limit allowed by the operating system used.

Contiguous Memory for Sapera Messaging

The current value for **Sapera messaging** determines the total amount of contiguous memory reserved at boot time for messages allocation. This memory space stores arguments when calling a Sapera function. Increase this value if you are using functions with large arguments, such as arrays and experience any memory errors.

CamExpert Quick Start

Interfacing CLHS Cameras with CamExpert

CamExpert is the camera-interfacing tool for Teledyne DALSA frame grabber boards supported by the Sapera library. CamExpert is the primary tool to configure, test and calibrate your camera and imaging setup. Display tools include, image pixel value readout, image zoom, and histogram.

An important component of CamExpert is its live acquisition display window which allows immediate verification of timing or control parameters without the need to run a separate acquisition program.

Functional tools include hardware Flat Field calibration and operation support (see Flat Field Correction: Theory of Operation), plus support for either hardware based or software Bayer filter camera decoding with auto white balance calibration.

After CamExpert identifies the camera (as per the Camera Link device discovery protocol), timing parameters are displayed and the user can test image acquisition by clicking on Grab.

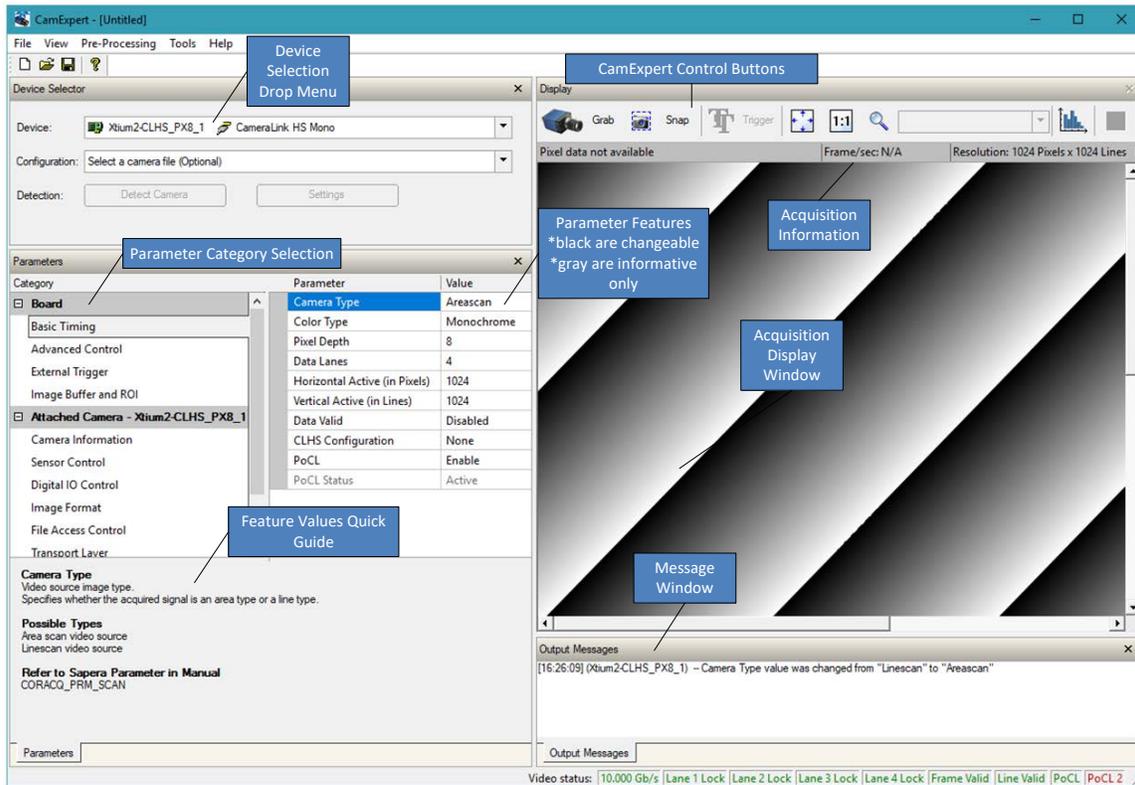
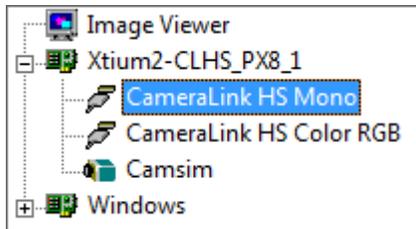


Figure 9: CamExpert Program

CamExpert groups camera features into functional categories. The features shown depend on the frame grabber used and what camera is connected. The values are either the camera defaults or the last stored value when the camera was used. The general descriptions below are not specific to a particular camera.

- **Device Selector:** Two drop menus allow selection of which device and which saved configuration to use.
 - **Device:** Select which acquisition device to control and configure a camera file. Required in cases where there are multiple boards in a system and when one board supports multiple acquisition types. Note in this example, the installed Xtium2-CLHS PX8 has firmware to support a monochrome or color RGB Camera Link HS camera.



- **Configuration:** Select the timing for a specific camera model included with the Sopera installation or a standard video standard. The *User's* subsection is where user created camera files are stored.
- **Parameter Groups:** Select a function category and change parameter values as required. Descriptions for the camera parameters change dependent on the camera.
 - **Basic Timing:** Provides or change static camera parameters.
 - **Advanced Controls:** Advanced parameters used to select various integration methods, frame trigger type, Camera Link HS controls, etc.
 - **External Trigger:** Parameters to configure the external trigger characteristics.
 - **Image Buffer and ROI:** Allows control of the host buffer dimension and format.
- **Display:** An important component of CamExpert is its live acquisition display window, which allows immediate verification of timing or control parameters without the need to run a separate acquisition program. **Grab** starts continuous acquisition (button then toggles to **Freeze** to stop). **Snap** is a single frame grab. **Trigger** is a software trigger to emulate an external source.
- **Output Messages and Video Status Bar:** Events and errors are logged for review. Camera connection status is displayed where green indicates connected signals present.

The CamExpert tool is described more fully in the Sopera Getting Started and Sopera Introduction manuals.

Sapera Camera Configuration Files

CamExpert generates the Sapera camera configuration file (yourcamera.ccf) based on timing and control parameters entered. When using the Sapera LT API in your imaging application, the frame grabber parameter settings can be loaded from this file. For backward compatibility with previous versions of Sapera, CamExpert also reads and writes the *.cca and *.cvi camera parameter files.

Every Sapera demo program starts with a dialog window to select a camera configuration file (for details on the included demos, see the Sapera Demo Applications section). Even when using the Xtium-CL MX4 with common video signals, a camera file is required. Therefore, CamExpert is typically the first Sapera application run after an installation. Existing .ccf files can be copied to any new board installations when similar cameras are used.

Camera Types & Files

The Xtium2-CLHS PX8 supports digital area scan or line scan cameras using the Camera Link HS interface standard. Browse our web site [<http://www.teledynedalsa.com/imaging/>] for the latest information on Teledyne DALSA Camera Link HS cameras.

Camera Files Distributed with Sapera

The Sapera distribution includes camera files for a selection of Xtium2-CLHS PX8 supported cameras. Using the Sapera CamExpert program, you may use the camera files (CCA) provided to generate a camera configuration file (CCF) that describes the desired camera and frame grabber configuration.

Teledyne DALSA continually updates a camera application library composed of application information and prepared camera files. Camera files are ASCII text, readable with Windows Notepad on any computer without having Sapera installed.

Overview of Sapera Acquisition Parameter Files (*.ccf or *.cca/*.cvi)

Concepts and Differences between the Parameter Files

There are two components to the legacy Sapera acquisition parameter file set: CCA files (also called cam-files) and CVI files (also called VIC (video input conditioning) files). The files store video-signal parameters (CCA) and video conditioning parameters (CVI), which in turn simplifies programming the frame-grabber acquisition hardware for the camera in use. Sapera LT 5.0 introduces a new camera configuration file (CCF) that combines the CCA and CVI files into one file.

Typically, a camera application will use a CCF file per camera operating mode (or one CCA file in conjunction with several CVI files, where each CVI file defines a specific camera-operating mode). An application can also have multiple CCA/CCF files to support different image format modes supported by the camera or sensor (such as image binning or variable ROI).

CCF File Details

A file using the ".CCF" extension, (Camera Configuration files), is the camera (CCA) and frame grabber (CVI) parameters grouped into one file for easier configuration file management. This is the default Camera Configuration file used with Sapera LT 5.0 and the CamExpert utility.

CCA File Details

Teledyne DALSA distributes camera files using the legacy “.CCA” extension, (CAMERA files), which contain all parameters describing the camera video signal characteristics and operation modes (what the camera outputs). The Sapera parameter groups within the file are:

- Video format and pixel definition
- Video resolution (pixel rate, pixels per line, lines per frame)
- Synchronization source and timing
- Channels/Taps configuration
- Supported camera modes and related parameters
- External signal assignment

CVI File Details

Legacy files using the “.CVI” extension contain all operating parameters related to the frame grabber board - what the frame grabber can actually do with camera controls or incoming video.

The Sapera parameter groups within the file are:

- Activate and set any supported camera control mode or control variable.
- Define the integration mode and duration.
- Define the strobe output control.
- Allocate the frame grabber transfer ROI, the host video buffer size and buffer type (RGB888, RGB101010, MONO8 and MONO16).
- Configuration of line/frame trigger parameters such as source (internal via the frame grabber /external via some outside event), electrical format (TTL, RS-422, OPTO-isolated), and signal active edge or level characterization.

Saving a Camera File

Use CamExpert to save a camera file (*.ccf) usable with any Sapera demo program or user application.

When CamExpert is setup as required, click on File•Save As to save the new .ccf file. The dialog that opens allows adding details such as camera information, mode of operation, and a file name for the .ccf file.

Camera Interfacing Check List

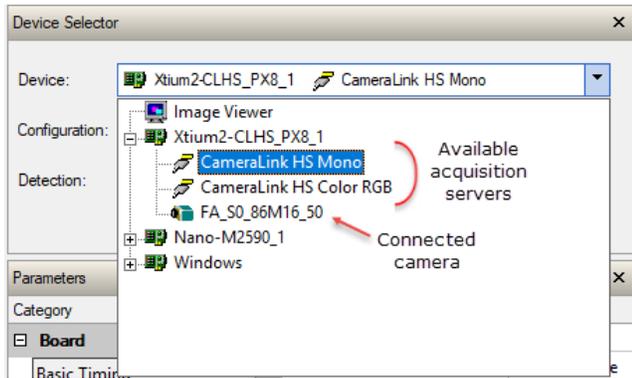
Before interfacing a camera from scratch with CamExpert:

- Confirm that Teledyne DALSA has not already published an application note with camera files [www.teledynedalsa.com].
- Confirm that the correct version or board revision of Xtium2-CLHS PX8 is used. Confirm that the required firmware is loaded into the Xtium2-CLHS PX8.
- Confirm that Sapera does not already have a .cca file for your camera installed on your hard disk. If there is a .cca file supplied with Sapera, then use CamExpert to generate the .ccf file with default parameter values matching the frame grabber capabilities.
- Check if the Sapera installation has a similar type of camera file. A similar .cca file can be loaded into CamExpert and modified to match timing and operating parameters for your camera, and lastly save them as Camera Configuration file (.ccf).
- Finally, if there is no file for your camera, run CamExpert after installing Sapera and the acquisition board driver, select the board acquisition server, and manually enter the camera parameters.

Using CamExpert with Xtium2-CLHS PX8

The Sapera CamExpert tool is the interfacing tool for Xtium2-CLHS PX8 frame grabbers and connected cameras; it is supported by the Sapera library and hardware. CamExpert allows a user to test frame grabber and camera functions. Additionally CamExpert saves the frame grabber settings configuration as individual camera parameter files on the host system (*.ccf).

When an acquisition server is selected, CamExpert only presents parameters supported by the selected device.



The Xtium2-CLHS PX8 firmware supports one Camera Link HS camera and provides the following acquisition servers:

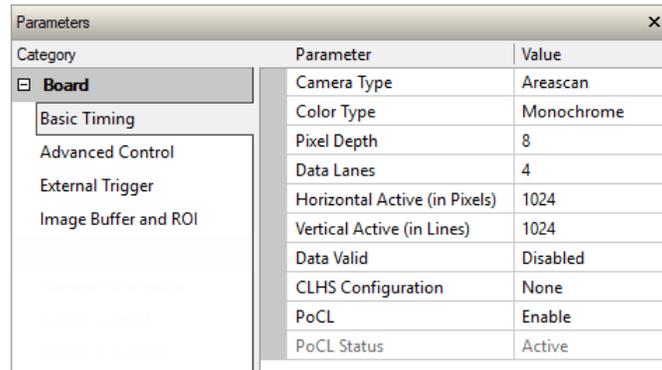
Firmware	Acquisition Servers
Camera Link HS (default configuration)	Xtium2-CLHS_PX8_1 CameraLink HS Mono CameraLink HS Color RGB

Depending on the selected server, different parameters may be displayed. For example, with an RGB acquisition server, the Color Type parameter is not displayed since its value is not configurable.

For more information, see the [Sapera Servers and Resources](#) section.

Basic Timing Category

The Basic Timing category groups parameters such as camera type, the active image size, and other settings related to basic timing.



Parameter Descriptions

The following table describes the CamExpert Basic Timing category of Spera LT parameters. Acquisition server notes, if applicable, indicate if parameter availability or supported values are dependent on the selected frame grabber acquisition server and acquisition device.

Display Name	Parameter	Description	Notes
Camera Type	CORACO_PRM_SCAN	Video source image type. Possible values are areascan or line scan.	Not shown for Bayer servers (area scan only).
Color Type	CORACO_PRM_VIDEO	Sets the color format of the input source.	Not shown for RGB servers. Monochrome servers support: Monochrome Bayer mosaic
Pixel Depth	CORACO_PRM_PIXEL_DEPTH	Pixel depth (bits per pixel) of the input source.	Not shown for RGB servers. Monochrome servers support: 8, 10, 12, 14 or 16 bit
Data Lanes	CORACO_PRM_DATA_LANES	Number of data lanes output by the camera.	
Horizontal Active (in Pixels)	CORACO_PRM_HACTIVE	Sets the horizontal camera resolution in pixels. This corresponds to the visible part of the image from the camera. Valid range is: min = 32 pixel max = 65536 pixel step = 32 pixel Note: minimum is per lane	
Vertical Active (in Lines)	CORACO_PRM_VACTIVE	Sets the vertical camera resolution in lines per frame. This corresponds to the visible part of the image from the camera. Valid range is 1-16777215.	Not shown for linescan cameras.

Data Valid	CORACO_PRM_DATA_VALID_ENABLE	Specifies if the acquisition board uses the camera data valid signal. Boolean parameter (TRUE or FALSE).	
CLHS Configuration	CORACO_PRM_CLHS_CONFIGURATION	Sets the board's CLHS configuration. Possible values are: None Manual Acquisition Start/Stop	
PoCL	CORACO_PRM_POCL_ENABLE	Enables/disables sending power to the Camera Link CLHS connector for Active Optical Cable (AOC). Boolean parameter (TRUE or FALSE).	This does not power the camera.
PoCL Status	CORACO_PRM_SIGNAL_STATUS	Status of power signals connected to the acquisition device. Possible values are Active or Not Active.	

Advanced Control Category

The Advanced Control category groups parameters for configuring camera control signals, board sync outputs and other advanced settings.

Category	Parameter	Value
Board	Internal Frame Trigger	Enable
Basic Timing	Internal Frame Trigger Frequency (in Hz)	30
Advanced Control	Camera Control method selected	None
External Trigger	Time Integration Method Setting	None
Image Buffer and ROI	Camera Trigger Method Setting	None
	Camera Frames Per Trigger	1
	Camera Control During Readout	Invalid
	Strobe Method Setting	None
	Time Stamp Base	Microseconds
	Board Sync Output 1 Source	Disabled
	Board Sync Output 2 Source	Disabled

Parameter Descriptions

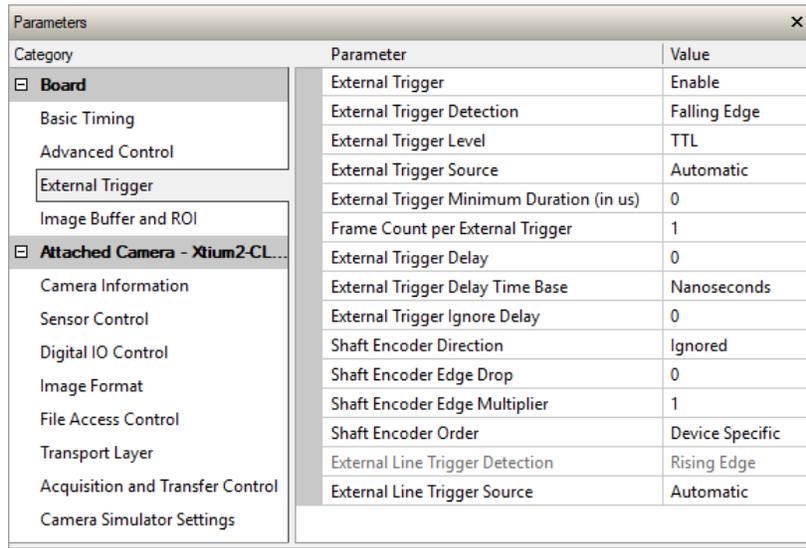
The following table describes the CamExpert Advanced Control category of Spera LT parameters. Acquisition server notes, if applicable, indicate if parameter availability or supported values are dependent on the selected frame grabber acquisition server and acquisition device.

Display Name	Parameter	Description	Notes
Internal Frame Trigger	CORACO_PRM_INT_FRAME_TRIGGER_ENABLE	Enables/disables the acquisition device's internal frame trigger. Boolean parameter (TRUE or FALSE).	Applies to areascan cameras only.
Internal Frame Trigger Frequency (in Hz)	CORACO_PRM_INT_FRAME_TRIGGER_FREQ	Internal frame trigger frequency in Hz. Set to the required frame rate when using internal frame trigger to control camera acquisition. Valid range is 0.001-10000Hz.	
Line Sync Source	CORACO_PRM_EXT_LINE_TRIGGER_ENABLE CORACO_PRM_INT_LINE_TRIGGER_ENABLE CORACO_PRM_SHAFT_ENCODER_ENABLE	Selects the line trigger source for linescan cameras, unless free-running.	Applies to linescan cameras only.
Internal Line Trigger Frequency (in Hz)	CORACO_PRM_INT_LINE_TRIGGER_FREQ	Sets the internal line trigger frequency, in Hz. Applies only when the Line Sync Source is set to Internal Line Trigger.	Applies to linescan cameras only.
Camera Line Trigger Frequency Min (in Hz)	CORACO_PRM_CAM_LINE_TRIGGER_FREQ_MIN	Sets the camera's minimum line trigger frequency. Minimum value is 1Hz.	Applies to linescan cameras only.
Camera Line Trigger Frequency Max (in Hz)	CORACO_PRM_CAM_LINE_TRIGGER_FREQ_MAX	Sets the camera's maximum line trigger frequency. Maximum value is 10000000 Hz.	Applies to linescan cameras only.
Camera Control method selected	CORACO_PRM_TIME_INTEGRATE_ENABLE CORACO_PRM_CAM_TRIGGER_ENABLE CORACO_PRM_LINE_TRIGGER_ENABLE	Enables or disables an available camera control method. Each supported control method has one or more operating modes to choose from; refer to the parameters: Camera Trigger Method Setting Time Integration Method Setting.	
Time Integration Method Setting	CORACO_PRM_TIME_INTEGRATE_METHOD CORACO_PRM_TIME_INTEGRATE_DELAY	When the Camera Control method is Time Integration, select and configure the control method required. Click on the parameter field to open the configuration dialog.	
Camera Trigger Method Setting	CORACO_PRM_CAM_TRIGGER_METHOD	When an asynchronous trigger pulse to a camera is required, select and configure the required method.	
Line Integration Method Setting	CORACO_PRM_LINE_INTEGRATE_METHOD	Sets the method for controlling the camera's line integration.	Applies to linescan cameras only

Line Trigger Method Setting	CORACO_PRM_LINE_TRIGGER_METHOD	Sets the method for line trigger pulse output.	Applies to linescan cameras only
Camera Frames Per Trigger	CORACO_PRM_CAM_FRAMES_PER_TRIGGER	Specifies the number of frames output by the camera per trigger; currently not available.	Applies to area scan cameras only.
Camera Control During Readout	CORACO_PRM_CAM_CONTROL_DURING_READOUT	Specifies if the camera control signals can be sent during the readout of a frame. Possible values are: <ul style="list-style-type: none"> • Valid • Invalid • Ignore 	
Strobe Method Setting	CORACO_PRM_STROBE_METHOD CORACO_PRM_STROBE_ENABLE CORACO_PRM_STROBE_DELAY CORACO_PRM_STROBE_DURATION CORACO_PRM_STROBE_LEVEL CORACO_PRM_STROBE_POLARITY	When a strobe output signal from the acquisition board is required, select and configure the control method required. Note, method 1 is only available for areascan camera type; method 3 for line scan only.	
Line Trigger Auto Delay	CORACO_PRM_LINE_TRIGGER_AUTO_DELAY	Enables delaying line triggers to a camera based on the selected method. Used to avoid over-triggering a camera.	Applies to linescan cameras only
Time Stamp Base	CORACO_PRM_TIME_STAMP_BASE	Sets the counter stamp time base. Possible values are: <ul style="list-style-type: none"> • Microseconds • Line Counts • External line trigger or shaft encoder • Shaft Encoder • 100 Nanoseconds 	
Board Sync Output 1 Source	CORACO_PRM_BOARD_SYNC_OUTPUT1_SOURCE	Specifies the signal to output on board sync output 1. This parameter permits the synchronization of two acquisition devices using a signal from one acquisition device and syncing the second acquisition device with it.	
Board Sync Output 2 Source	CORACO_PRM_BOARD_SYNC_OUTPUT2_SOURCE	Specifies the signal to output on board sync output 2. This parameter permits the synchronization of two acquisition devices using a signal from one acquisition device and syncing the second acquisition device with it.	

External Trigger Category

The External category groups parameters for configuring an external trigger for controlling image acquisition.



Parameter Descriptions

The following table describes the CamExpert External Trigger category of Sopera LT parameters.

Display Name	Parameter	Description
External Trigger	CORACO_PRM_EXT_TRIGGER_ENABLE	Enables/disables external trigger on the acquisition board. When enabled, the acquisition board acquires an image frame from the camera after receiving the trigger. Boolean parameter (TRUE or FALSE). Note: Applies to area scan cameras only.
External Trigger Detection	CORACO_PRM_EXT_TRIGGER_DETECTION (areascan) CORACO_PRM_EXT_FRAME_TRIGGER_DETECTION (linescan)	Defines the signal detected that generates an external trigger event to the acquisition device. Two types of trigger are available: <i>Level Trigger: Active Low / High</i> Logic level (Low/High) on the trigger input enables continuous image capture until the trigger input is set to opposite logic . <i>Edge Trigger: Rising / Falling edge</i> Edge transition of a trigger pulse captures one image frame. Linescan cameras also support: <i>Dual-Input Trigger Rising Edge / Dual-Input Trigger Falling Edge</i>
External Trigger Level	CORACO_PRM_EXT_TRIGGER_LEVEL	Specifies the electrical level of the external trigger connected to the acquisition board. Possible values: TTL single-ended logic signal RS-422 balanced logic signal 12V single-ended logic signal 24V single-ended logic signal

External Trigger Source	CORACO_PRM_EXT_TRIGGER_SOURCE	Specifies the physical input source the external frame trigger is connected to or which trigger input is used on the acquisition device. Note: to assign the external trigger source to a GPIO it must be reserved; By default, boards are shipped with User Interface General Inputs 1 & 2 reserved for External Triggers and User Interface General Outputs 1 & 2 reserved for Strobe Outputs. Refer to User Interface GPIOs Reservation for more information on using the Teledyne DALSA Device Manager tool to reserve GPIOs.
External Trigger Minimum Duration (in μ s)	CORACO_PRM_EXT_TRIGGER_DURATION	Minimum external trigger pulse duration (in μ s), needed for the pulse to be acknowledged by the acquisition device. If the duration of the pulse is shorter, the pulse is ignored. This feature is useful for trigger pulse debouncing. If the value is '0', no validation is performed
Frame Count per External Trigger	CORACO_PRM_EXT_TRIGGER_FRAME_COUNT	Number of images to acquire upon receiving an external trigger. Valid range is 1-262142. Note, infinite frame count (-1) is not supported.
External Trigger Delay	CORACO_PRM_EXT_TRIGGER_DELAY	Sets the delay between the reception of the trigger signal and the start of the image acquisition. Units are specified by the External Trigger Delay Time Base parameter.
External Trigger Delay Time Base	CORACO_PRM_EXT_TRIGGER_DELAY_TIME_BASE	Sets the external trigger delay time base. Possible values: <ul style="list-style-type: none"> • Line Counts • Nanoseconds • External Line Trigger or Shaft Encoder • Shaft Encoder
External Trigger Ignore Delay	CORACO_PRM_EXT_TRIGGER_IGNORE_DELAY	Sets the time delay, in usec, where if another external trigger occurs, it is ignored. Valid range is 0-42949672. The start of the delay (time '0') is the end of the next vertical sync for analog cameras, or the beginning of the next frame valid for digital cameras, following a valid external trigger.
Shaft Encoder Direction	CORACO_PRM_SHAFT_ENCODER_DIRECTION	Selects the direction of the shaft encoder that increments/decrements the acquisition device encoder counter. Support of dual phase encoders might require that the direction of motion be considered. This is the case where system vibrations and/or conveyor backlash can cause the encoder to momentarily travel backwards. The acquisition device must in those cases count the reverse steps and subtract the forward steps such that only pulses after the reverse count reaches zero are considered valid.
Shaft Encoder Edge Drop	CORACO_PRM_SHAFT_ENCODER_DROP	Number of shaft encoder signal edges dropped between active shaft encoder triggers. Use the pulse drop feature to reduce the acquisition rate without reducing the shaft encoder trigger rate.
Shaft Encoder Edge Multiplier	CORACO_PRM_SHAFT_ENCODER_MULTIPLY	Number of signal edges generated internally on the acquisition board for each external shaft encoder signal edge. Use when video acquisitions are controlled by an external shaft encoder trigger but multiple acquisitions are needed from each trigger.
Shaft Encoder Order	CORACO_PRM_SHAFT_ENCODER_ORDER	Specifies the order of the drop/multiply operation of the shaft encoder.
External Line Trigger Detection	CORACO_PRM_EXT_LINE_TRIGGER_DETECTION	Select the signal detected (rising edge/falling edge) that generates an external line trigger to the acquisition device.
External Line Trigger Source	CORACO_PRM_EXT_LINE_TRIGGER_SOURCE CORACO_PRM_EXT_LINE_TRIGGER_ENABLE	Specifies the physical input source the external line trigger is connected to on the acquisition device, in the case where the acquisition device has more than one input. Line scan cameras typically use the shaft encoder signals as the acquisition board line trigger. The 'Automatic' choice selects the trigger normally used with the acquisition module, in the case of multiple modules – multiple trigger inputs.

Image Buffer and ROI Category

The Image Buffer and ROI category groups parameters for the configuring the image buffer format, size and offset settings, as well as image flipping.

Category	Parameter	Value
Basic Timing	Image Width (in Pixels)	640
Advanced Control	Image Height (in Lines)	480
External Trigger	Image Left Offset (in Pixels)	0
Image Buffer and ROI	Image Top Offset (in Lines)	0
	Image Buffer Format	Monochrome 8-bits
	Image Flip	Disabled

Parameter Descriptions

The following table describes the CamExpert Image Buffer and ROI category of Sopera LT parameters. Acquisition server notes, if applicable, indicate if parameter availability or supported values are dependent on the selected frame grabber acquisition server and acquisition device.

Display Name	Parameter	Description	Notes
Image Width (in Pixels)	CORACO_PRM_CROP_WIDTH	Cropped width of the acquisition image, in pixels; this parameter defines the width of the image transferred to the frame buffer. The maximum width is the active horizontal of the image source (see the Horizontal Active parameter in the Basic Timing category). Cropping increments depend on the selected acquisition server; CamExpert automatically adjusts numerical entries to valid increments.	Note: image data is not scaled.
Image Height (in Lines)	CORACO_PRM_CROP_HEIGHT	Cropped height of the acquisition image, in lines; this parameter defines the vertical dimension of the image transferred to the frame buffer. The maximum height is the active vertical width of the image source (see the Vertical Active parameter in the Basic Timing category). Cropping increments depend on the selected acquisition server; CamExpert automatically adjusts numerical entries to valid increments.	Note: image data is not scaled.
Image Left Offset (in Pixels)	CORACO_PRM_CROP_LEFT	Number of pixels to crop from the left side of the acquisition image before transfer to the frame buffer. The maximum left offset is the active horizontal width of the image source less one increment step. Cropping increments depend on the selected acquisition server; CamExpert automatically adjusts numerical entries to valid increments.	Note: image data is not scaled.
Image Top Offset (in Lines)	CORACO_PRM_CROP_TOP	Number of lines to crop from the top of the acquisition image before transfer to the frame buffer. The maximum top offset is the active vertical height of the image source less one increment step. Cropping increments are acquisition hardware dependent; CamExpert automatically adjusts numerical entries to valid increments.	Note: image data is not scaled.

Image Buffer Format	CORACO_PRM_OUTPUT_FORMAT	Data format for the acquisition image transfer to the frame buffer.	The data buffer format is dependent on the selected acquisition server; for details refer to the CORACO_PRM_OUTPUT_FORMAT parameter description
Image Flip	CORACO_PRM_FLIP	Enables real-time on-board horizontal image flip function. The Xtium2-CLHS PX8 also supports a vertical flip operation using CORXFER_PRM_FLIP .	
Acquisition Frame Length method	CORACO_PRM_FRAME_LENGTH	Specifies if the images output by the acquisition device have a fixed or variable frame length. Variable frame length is of interest with linescan applications where the external frame trigger timing changes. External frame trigger could be active high or low pulse width controlled, or external frame trigger could be from a double pulse control.	Applies to linescan cameras only.

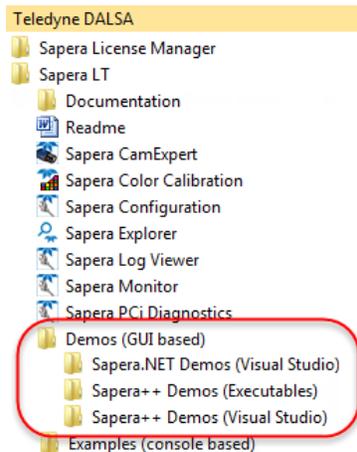
Sapera Demo Applications

Grab Demo Overview

The Grab Demo program demonstrates the basic acquisition functions included in the Sapera library. The program either allows you to acquire images, in continuous or in one-time mode, while adjusting the acquisition parameters. The program code may be extracted for use within your own application.

The Grab Demo is available as a compiled binary; source code is provided for both C++ and .NET projects using Visual Studio 2005/2008/2010/2012/2013/2015.

All demos are available through the Start menu.



Grab Demo Workspace Details

Program file	...\\...\\Sapera\\Demos\\Binaries\\GrabDemo.exe
Visual C++ Solution	...\\...\\Sapera\\Demos\\Classes\\Vc\\SapDemos_2010.sln ...\\...\\Sapera\\Demos\\Classes\\Vc\\SapDemos_2012.sln ...\\...\\Sapera\\Demos\\Classes\\Vc\\SapDemos_2013.sln ...\\...\\Sapera\\Demos\\Classes\\Vc\\SapDemos_2015.sln ...\\...\\Sapera\\Demos\\Classes\\Vc\\SapDemos_2017.sln
Visual .NET Solution	...\\...\\Sapera\\Demos\\NET\\SapDemos_2010.sln ...\\...\\Sapera\\Demos\\NET\\SapDemos_2012.sln ...\\...\\Sapera\\Demos\\NET\\SapDemos_2013.sln ...\\...\\Sapera\\Demos\\NET\\SapDemos_2015.sln ...\\...\\Sapera\\Demos\\NET\\SapDemos_2017.sln
Remarks	This demo is based on Sapera LT classes. See the Sapera User's and Reference manuals for more information.

Using the Grab Demo

Server Selection

Run the grab demo from the start menu:

Start • Programs • Sapera LT • Demos • Frame Grabbers • Grab Demo.

The demo program first displays the acquisition configuration menu. The first drop menu displayed permits selecting from any installed Sapera acquisition servers (installed Teledyne DALSA acquisition hardware using Sapera drivers). The second drop menu permits selecting from the available input devices present on the selected server.

CCF File Selection

Use the acquisition configuration menu to select the required camera configuration file for the connected camera. Sapera camera files contain timing parameters and video conditioning parameters. The default folder for camera configuration files is the same used by the CamExpert utility to save user generated or modified camera files.

Use the Sapera CamExpert utility program to generate the camera configuration file based on timing and control parameters entered. The CamExpert live acquisition window allows immediate verification of those parameters. CamExpert reads both Sapera *.cca and *.cvi for backward compatibility with the original Sapera camera files.

Grab Demo Main Window

The Grab Demo program provides basic acquisition control for the selected frame grabber. The loaded camera file (.ccf) defines the Frame buffer defaults.

Refer to the Sapera LT User's Manual (OC-SAPM-USER), in section "Demos and Examples – Acquiring with Grab Demo", for more information on the Grab Demo and others provided with Sapera LT.

Xtium2-CLHS PX8 Reference

Block Diagram

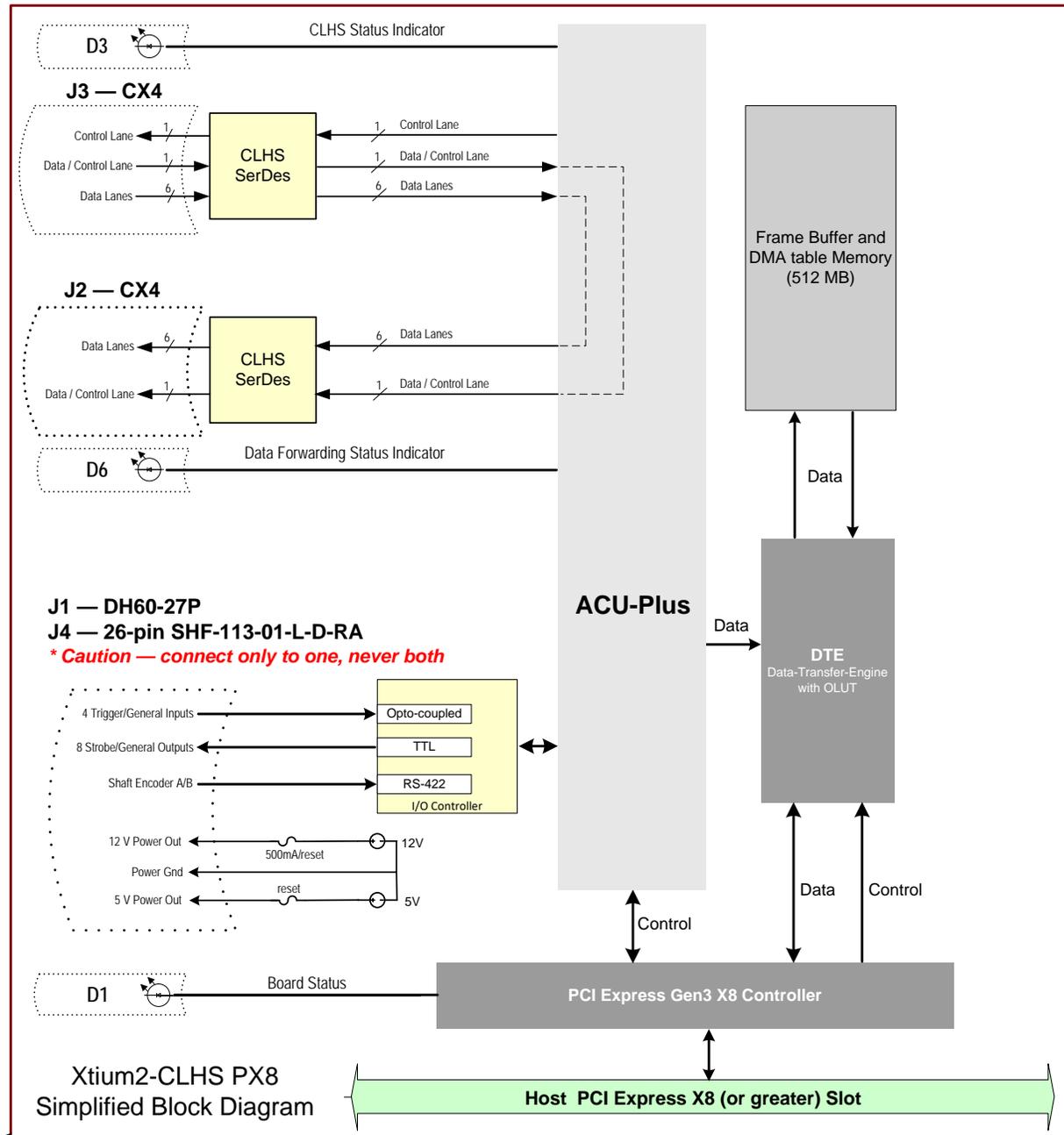


Figure 10: Xtium2-CLHS PX8 Block Diagram

Xtium2-CLHS Flow Diagram

The following diagram represents the processing sequence through the Xtium2-CLHS.

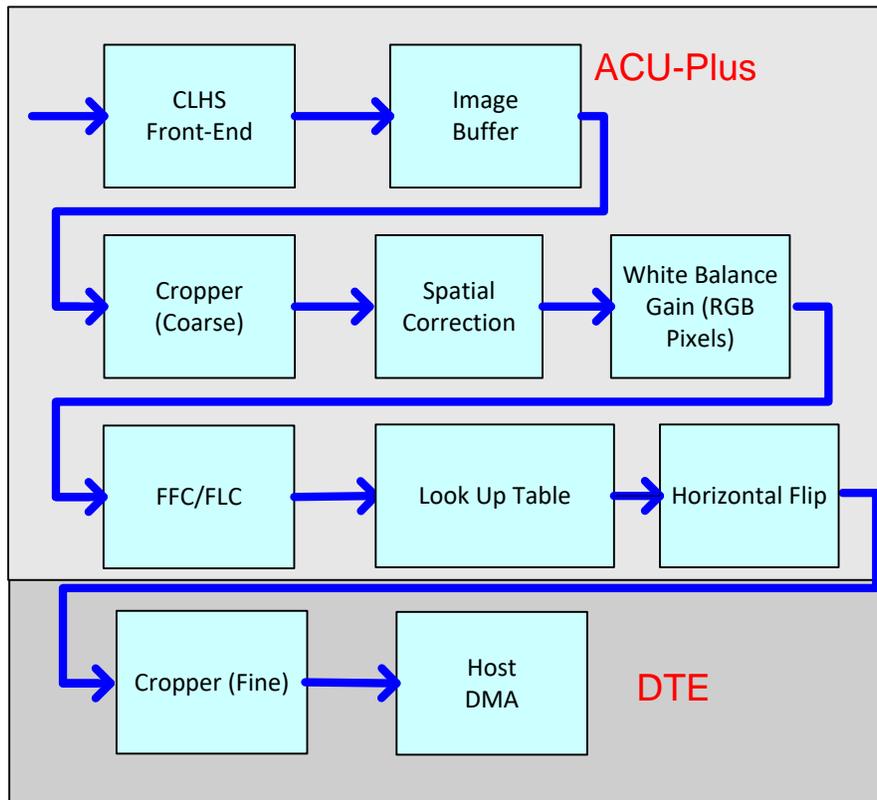


Figure 11: Xtium2-CLHS Flow Diagram

- **Camera Link HS Front End:** Extracts the video data packets from the Camera Link HS port.
- **Image Buffer:** Stores the video data using the model of video frames.
- **Cropper (Coarse):** Horizontal cropper used when reading out from the memory.
- **Spatial Correction:** Depending on the line scan camera, a spatial correction might need to be applied by the frame grabber when acquiring multiple image planes (mono or RGB). Although this feature is transparent to the user, one can query a feature of the camera to know the spatial distance between the mono or color planes. The camera will take care of the fractional part of the spatial distance, while the frame grabber will take care of the integer spatial distance. When a spatial correction is applied by the frame grabber, the distance in lines between the 1st and last plane (let's call this distance "D") must be taken into account when triggering camera lines. If a user wants to get 1024 lines, he will need to send an extra "D" lines (1024 + "D" triggers) to the camera in order to get 1024 lines in the host buffer.
- **White Balance Gain:** Applies White Balance Gain to RGB data.
- **FFC/FLC:** Flat Field/Flat Line correction. Applies to Monochrome data only.
- **Lookup Tables:** Apply lookup table transformation to the image.
- **Horizontal Flip:** Performs the line data flip process.
- **Cropper (Fine):** Crops the resulting image when used, using an 4-byte resolution.
- **Host DMA:** Transfers the data from frame grabber into the host buffer memory. This module will also perform the vertical flip if enabled.

CLHS Camera Implementation

The following figure defines the Xtium2 CLHS PX8 camera interface as per the *Camera Link HS (CLHS) specification version 1.0*. The key parameters are:

- A single camera connector (J3) which is a copper hardwired interface with a thumbscrew locking mechanism – not an optical interface.
- Supports the M-Protocol definition of the Physical and Data Link Layer.
- There is one command channel to/from the camera.
- Supports single connector cameras which have 1 to 7 data Lanes.

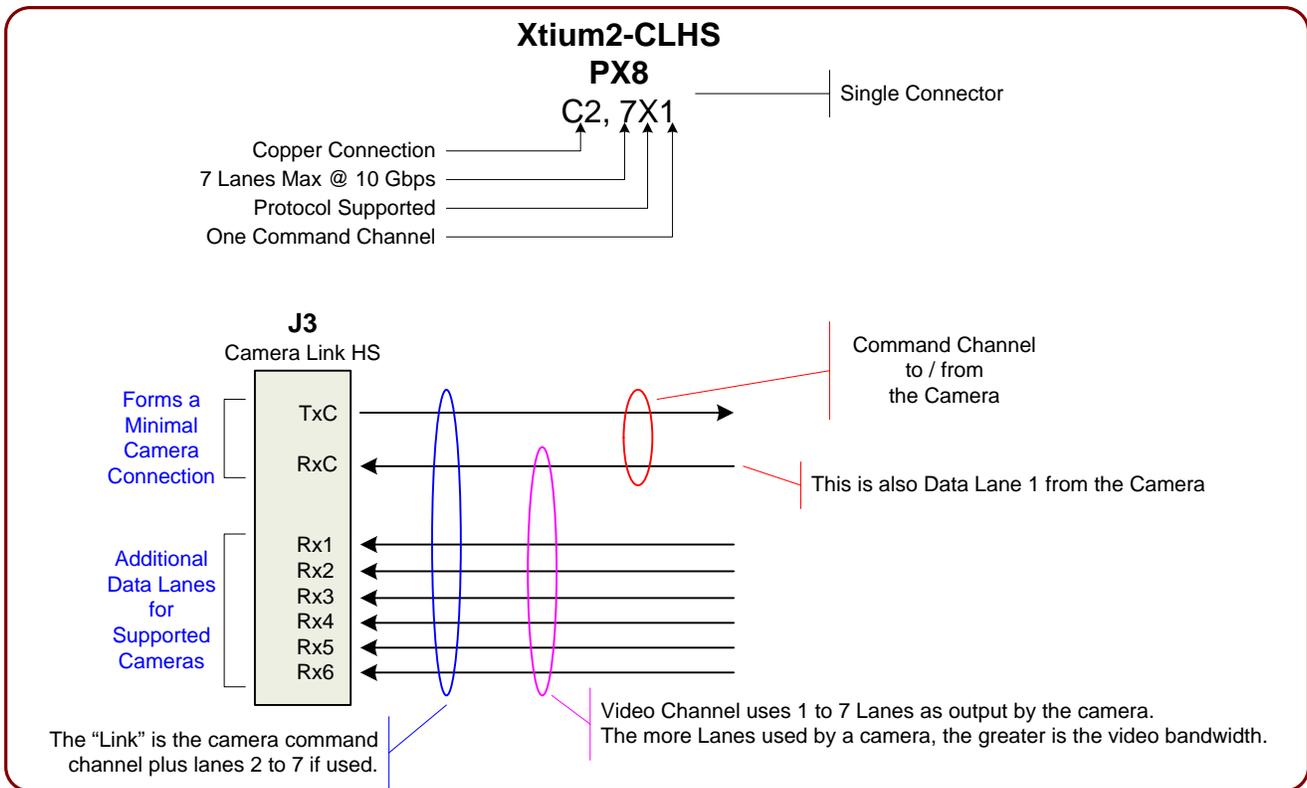


Figure 12: CLHS Camera Interface

Line Trigger Source Selection for Line Scan Applications

Line scan imaging applications require some form of external event trigger to synchronize line scan camera exposures to the moving object. This synchronization signal is either an external trigger source (one exposure per trigger event) or a shaft encoder source composed of a single or dual phase (also known as a quadrature) signal.

The Xtium2-CLHS PX8 shaft encoder inputs provide additional functionality with pulse drop, pulse multiply, and pulse direction support.

The following table describes the line-trigger source types supported by the Xtium2-CLHS PX8. Refer to the Spera Acquisition Parameters Reference Manual (OC-SAPM-APR00) for descriptions of the Spera parameters.

CORACQ_PRM_EXT_LINE_TRIGGER_SOURCE – Parameter Values Specific to the Xtium2-CLHS PX8

PRM Value	Input used External Line Trigger	as:	Input used External Shaft Encoder	as:
	<i>if</i> CORACQ_PRM_EXT_LINE_TRIGGER_ENABLE = <i>true</i>		<i>if</i> CORACQ_PRM_SHAFT_ENCODER_ENABLE = <i>true</i>	
0	From Shaft Encoder Phase A		From Shaft Encoder Phase A & B	
1	From Shaft Encoder Phase A		From Shaft Encoder Phase A	
2	From Shaft Encoder Phase B		From Shaft Encoder Phase B	
3	n/a		From Shaft Encoder Phase A & B	
4	From Board Sync #1		n/a	
5	From Board Sync #2		n/a	

CVI/CCF File Parameters Used

- External Line Trigger Source = parameter value
- External Line Trigger Enable = true/false
- Shaft Encoder Enable = true/false

Shaft Encoder Interface Timing

Dual Balanced Shaft Encoder RS-422 Inputs:

- Input Phase A: Connector J1/J4: Pin 3 (Phase A +) & Pin 2 (Phase A -)
- Input Phase B: Connector J1/J4: Pin 6 (Phase B+) & Pin 5 (Phase B-)
- See J1: External I/O Signals Connector (Female DH60-27P) for complete connector signal details)

Web inspection systems with variable web speeds typically provide one or two synchronization signals from a web mounted encoder to coordinate trigger signals. These trigger signals are used by the acquisition linescan camera. The Xtium2-CLHS PX8 supports single or dual phase shaft encoder signals. Dual encoder signals are typically 90 degrees out of phase relative to each other and provide greater web motion resolution.

Example using any Encoder Input with Pulse-drop Counter

When enabled, the triggered camera acquires one scan line for each shaft encoder pulse-edge. To optimize the web application, a second Sopera parameter defines the number of triggers to skip between valid acquisition triggers. The figure below depicts a system where a valid camera trigger is any pulse edge from either shaft encoder signal. After a trigger, the two following triggers are ignored (as defined by the Sopera pulse drop parameter).

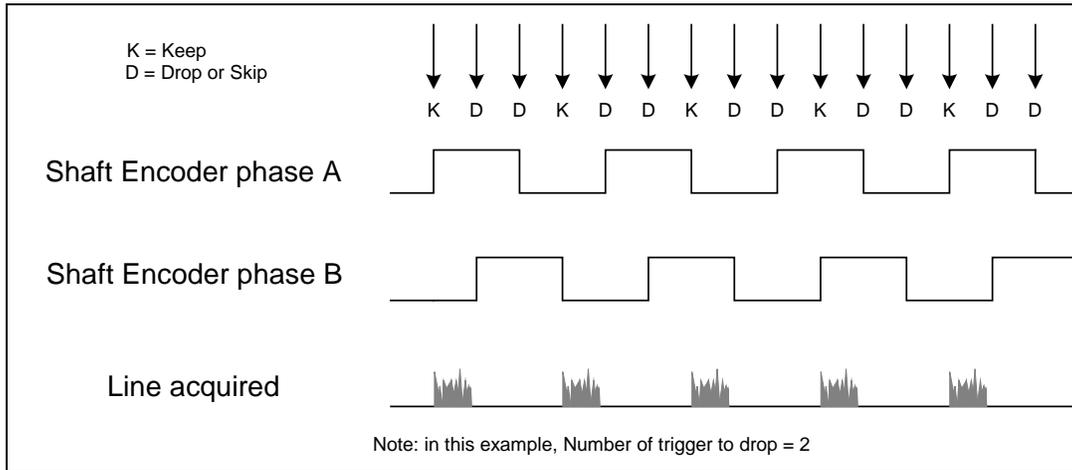


Figure 13: Encoder Input with Pulse-drop Counter

Example using Sequential Encoder Input

Support of a dual phase encoder should consider the direction of motion of one phase signal to the other. Such a case might exist where system vibrations and/or conveyor backlash can cause the encoder to briefly travel backwards. The acquisition device must in those cases count the reverse steps and subtract the forward steps such that only pulses after the reverse count reaches zero are considered. By using the event “Shaft Encoder Reverse Counter Overflow”, an application can monitor an overflow of this counter.

Also, if a maximum line rate camera trigger source is a high jitter shaft encoder, the parameter CORACQ_PRM_LINE_TRIGGER_AUTO_DELAY can be used to automatically delay line triggers to avoid over-triggering a camera, and thus not miss a line. Note that some cameras integrate this feature. See also the event “[Line Trigger Too Fast](#)” that can be enabled when using the ‘auto delay’ feature.

The example figure below shows shaft encoder signals with high jitter. If the acquisition is triggered when phase B follows phase A, with jitter present phase B may precede phase A. Use of the *Shaft Encoder Direction* parameter will prevent false trigger conditions.

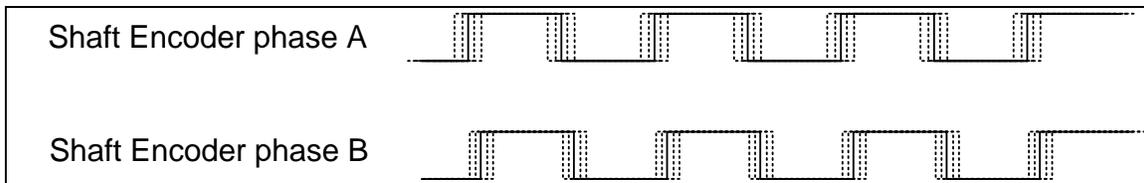


Figure 14: Using Shaft Encoder Direction Parameter



Note: Modify camera file parameters easily with the Sopera CamExpert program.

CVI/CCF File Parameters Used

Shaft Encoder Enable = X, where:

- If X = 1, Shaft Encoder is enabled
- If X = 0, Shaft Encoder is disabled

Shaft Encoder Pulse Drop = X, where:

- X = number of trigger pulses ignored between valid triggers

Shaft Encoder Pulse Multiply = X, where:

- X = number of trigger pulses generated for each shaft encoder pulses

Shaft Encoder Pulse Drop/Multiply Order = X, where:

- If X = 1, the drop operation will be done first, followed by the multiplier operation
- If X = 0 or 2, the multiplier operation will be done first, followed by the drop operation

Shaft Encoder Direction = X, where:

- X = 0, Ignore direction
- X = 1, Forward steps are detected by pulse order A/B (forward motion)
- X = 2, Forward steps are detected by pulse order B/A (reverse motion)



Note: For information on camera configuration files, see the Spera Acquisition Parameters Reference Manual (OC-SAPM-APR00).

Virtual Frame Trigger for Line Scan Cameras

When using line scan cameras, a frame buffer is allocated in host system memory to store captured video lines. To control when a video line is stored as the first line in this “virtual” frame buffer, an external frame trigger signal is used.

For **fixed length** frames, the Spera vertical cropping parameter controls the number of lines sequentially grabbed and stored in the virtual frame buffer.

For **variable length** frames, the External Frame Trigger (when a level or dual input type is selected) controls the number of lines sequentially grabbed up to the maximum of lines in the virtual frame buffer.

For both fixed and variable length frames choosing an active low/high or dual input permits grabbing multiple consecutive images as long as the chosen signal is active. This action is also called “rolling over” to the next buffer. When choosing a single rising or falling edge, a single frame will be acquired; there is never any roll over.

External Frame Trigger Detection	Fixed Frame	Variable Frame
Active Low/High	Roll Over	Roll Over
Rising/Falling Edge	No Roll Over	No Roll Over
Dual Input Rising/Falling Edge	Roll Over	Roll Over

Virtual Frame Trigger Timing Diagram

The virtual frame trigger signal (generated by some external event) connects to the Xtium2-CLHS PX8 trigger input.

- Virtual frame trigger can be differential (RS-422) or single ended (TTL, 12V, or 24V) industry standard, and be rising or falling edge active, active high or low, or double pulse rising or falling edge.
- Virtual frame trigger connects to the Xtium2-CLHS PX8 via the External Trigger Input 1 & 2 inputs.
 - Trigger Input #1 on connector J1: pin 8
 - Trigger Input #2 on connector J1: pin 9
- The Spera vertical cropping parameter specifies the number of lines captured (maximum size of virtual frame).

Synchronization Signals for a 10 Line Virtual Frame

The following timing diagram shows an example of grabbing 10 image lines from a line scan camera and the use of a virtual frame trigger to define when a video line is stored at the beginning of the virtual frame buffer.

In this example, virtual frame trigger control is configured for rising edge trigger.

- Camera control signals are active at all times. These continually trigger the camera acquisition in order to avoid corrupted video lines at the beginning of a virtual frame.
- The camera control signals are either timing controls on Xtium2-CLHS PX8 shaft encoder inputs, or line triggers generated internally by the Xtium2-CLHS PX8.

The following timing diagram shows the relationship between External Frame Trigger input, External Shaft Encoder input (one phase used with the second terminated), and camera control output to the camera.

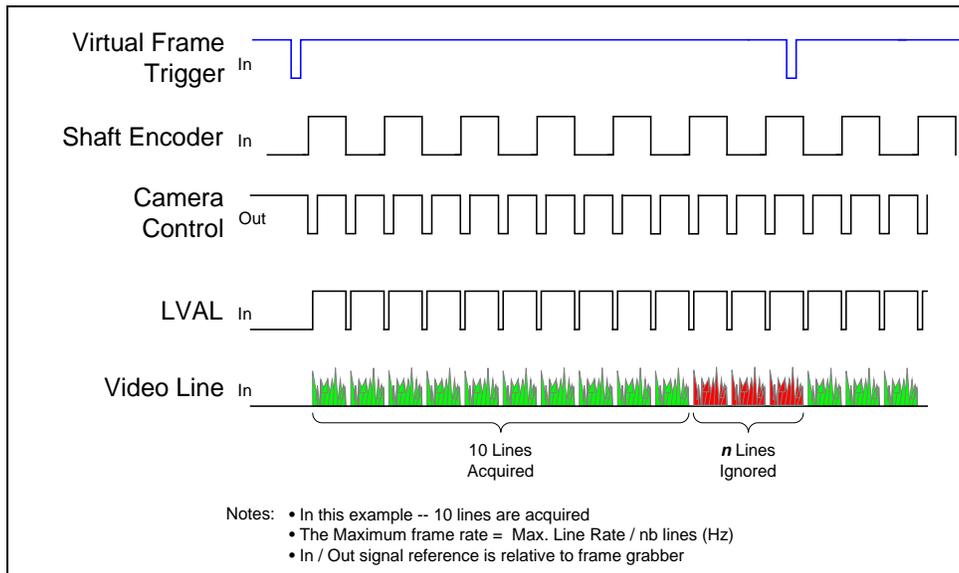


Figure 15: Synchronization Signals for a 10 Line Virtual Frame

Synchronization Signals for Fixed Frame Length Acquisition

A trigger event is only generated when a grab is active; when not grabbing no trigger events are generated. When a frame is complete, the frame grabber checks for the specified active trigger level and, if present, grabs the next frame; otherwise, it waits for the next detected active trigger level.

In the following diagrams:

- "T" indicates a valid external trigger event (SapAcquisition::EventExternalTrigger).
- "Ignored" is an ignored event (SapAcquisition::EventExternalTriggerIgnored).
- such that $Ignored + T = \text{total triggers received by frame grabber}$

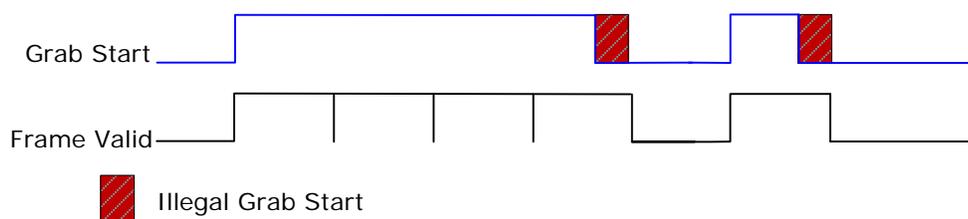


Figure 16: Line scan, Fixed Frame, No Trigger

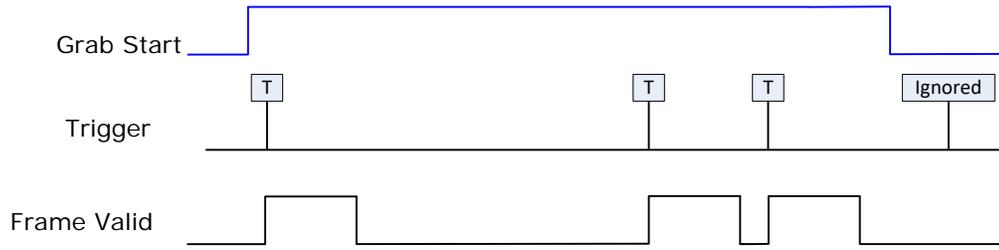


Figure 17: Line scan, Fixed Frame, Edge Trigger

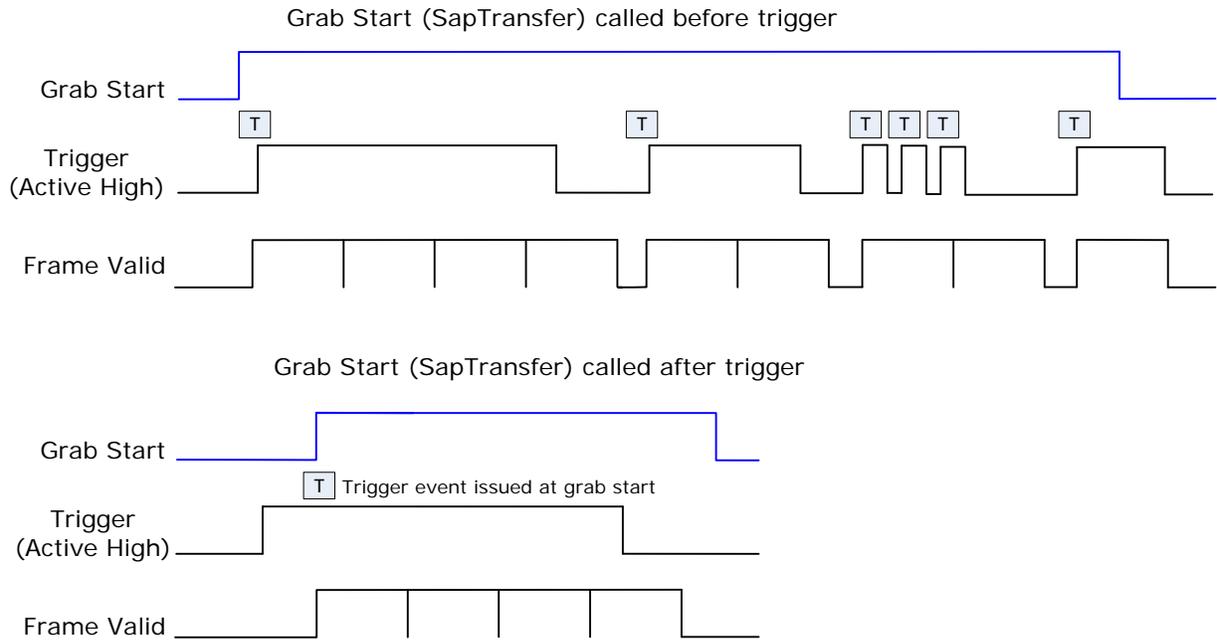


Figure 18: Line scan, Fixed Frame, Level Trigger (Roll-Over to Next Frame)

Synchronization Signals for Variable Frame Length Acquisition

For variable length frames, trigger ignored events (SapAcquisition::EventExternalTriggerIgnored) are not issued; a valid trigger event always initiates either a frame start or frame end.

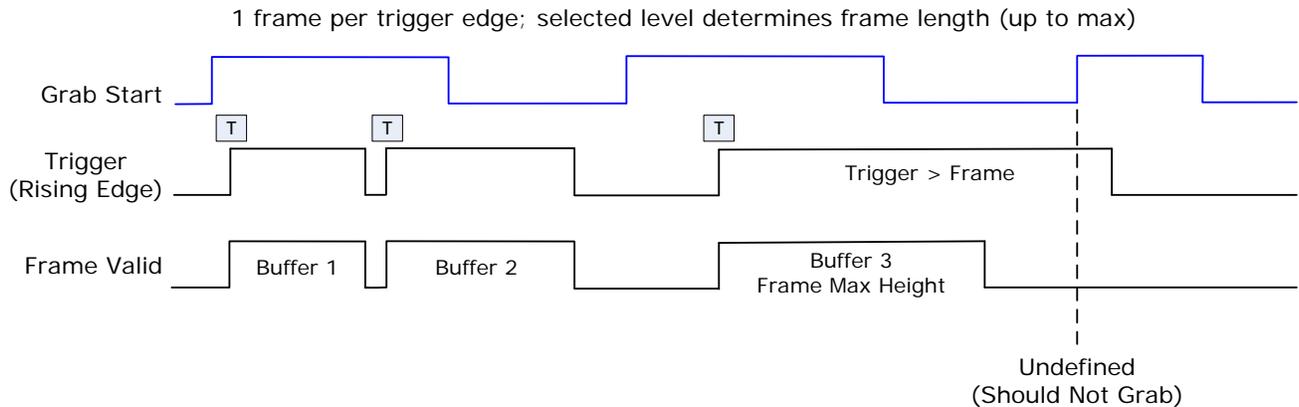


Figure 19: Line scan, Variable Frame, Edge Trigger (Active High determines Frame Length)

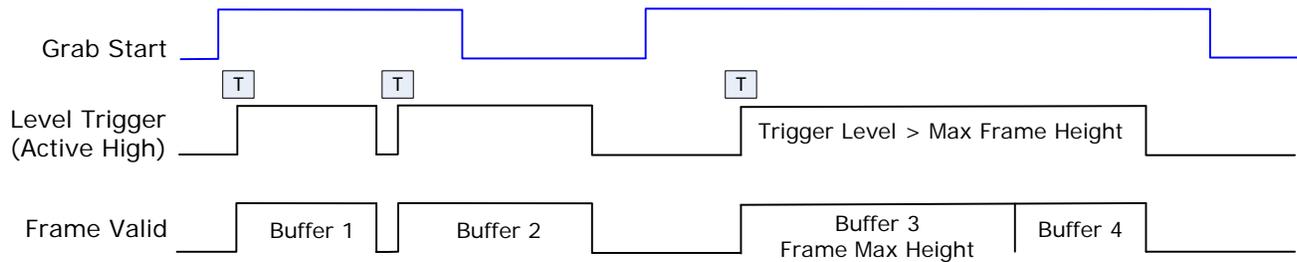


Figure 20: Line scan, Fixed Frame, Level Trigger (Roll-Over)

CVI File (VIC) Parameters Used

The VIC parameters listed below provide the control functionality for virtual frame reset. Sopera applications load pre-configured CVI files, or change VIC parameters during runtime.



Note: Sopera camera file parameters are easily modified by using the CamExpert program.

External Frame Trigger Enable = X, where: (with Virtual Frame Trigger enabled)

- If X = 1, External Frame Trigger is enabled
- If X = 0, External Frame Trigger is disabled

External Frame Trigger Detection = Y, where: (with Virtual Frame Trigger edge select)

- If Y= 1, External Frame Trigger is active low
- If Y= 2, External Frame Trigger is active high
- If Y= 4, External Frame Trigger is active on rising edge
- If Y= 8, External Frame Trigger is active on falling edge
- If Y= 32, External Frame Trigger is dual-input rising edge
- If Y= 64, External Frame Trigger is dual-input falling edge



Note: For dual-input triggers, Trigger Input #1 signals the start of the frame trigger, Trigger Input #2 signals the end of the frame trigger.

External Frame Trigger Level = Z, where: (with Virtual Frame Trigger signal type)

- If Z = 1, External Frame Trigger is a TTL signal
- If Z = 2, External Frame Trigger is differential signal (RS-422)
- If Z = 8, External Frame Trigger is a 24V signal
- If Z = 64, External Frame Trigger is a 12V signal



Note: For information on camera configuration files, see the Sopera Acquisition Parameters Reference Manual (OC-SAPM-APR00).

Sopera Acquisition Methods

Sopera acquisition methods define the control and timing of the camera and frame grabber board. Various methods are available, grouped as:

- Camera Trigger Methods (method 3 supported)
- Line Trigger Methods (method 2)
- Line Integration Methods (methods 8, 9 and 10 supported)
- Time Integration Methods (method 10, 11 and 12)
- Strobe Methods (method 1, 3, 4 and 5 supported)

Refer to the Sopera LT Acquisition Parameters Reference manual (OC-SAPM-APR00) for detailed information concerning camera and acquisition control methods.

Trigger to Image Reliability

Trigger-to-image reliability incorporates all stages of image acquisition inside an integrated controller to increase reliability and simplify error recovery. The trigger-to-image reliability model brings together all the requirements for image acquisition to a central management unit. These include signals to control camera timing, on-board frame buffer memory to compensate for PCI bus latency, and comprehensive error notification. If the Xtium2-CLHS PX8 detects a problem, the application can take appropriate action to return to normal operation.

The Xtium2-CLHS PX8 is designed with a robust ACU (Acquisition and Control Unit). The ACU monitors in real-time the acquisition state of the input plus the DTE (Data Transfer Engine) which transfers image data from on-board memory into PC memory. In general, these management processes are transparent to end-user applications. With the Xtium2-CLHS PX8, applications ensure trigger-to-image reliability by monitoring events and controlling transfer methods as described below:

Supported Events and Transfer Methods

Listed below are the supported acquisition and transfer events. Event monitoring is a major component to the Trigger-to-Image Reliability framework.

Acquisition Events

Acquisition events pertain to the acquisition module. They provide feedback on the image capture phase.

- **External Trigger** (Used/Ignored/End)

Generated when the external trigger pin is asserted, which indicates the start of the acquisition process. There are three types of external trigger events: 'Used', 'Ignored' and 'End'. Following an external trigger, if the event generates a captured image, an External Trigger Used event will be generated (CORACQ_VAL_EVENT_TYPE_EXTERNAL_TRIGGER).

If there is no captured image, an External Trigger Ignored event will be generated (CORACQ_VAL_EVENT_TYPE_EXTERNAL_TRIGGER_IGNORED). An external trigger event is ignored if the event rate is higher than the possible frame rate of the camera. When using an active high/low or double pulse rising/falling edge trigger detection, the 2nd pulse will generate the External Trigger End event (CORACQ_VAL_EVENT_TYPE_EXTERNAL_TRIGGER_END).

- **Start of Frame**

Event generated during acquisition, with the detection of the start of a video frame by the board acquisition hardware. The Sopera event value is: CORACQ_VAL_EVENT_TYPE_START_OF_FRAME.

- **End of Frame**

Event generated during acquisition, with the detection of the end of a video frame by the board acquisition hardware. The Sopera event value is: CORACQ_VAL_EVENT_TYPE_END_OF_FRAME.

- **Data Overflow**

The Data Overflow event indicates that there is not enough bandwidth for the acquired data transfer without loss. Data Overflow would occur with limitations of the acquisition module and should never occur.

The Sopera event value is: CORACQ_VAL_EVENT_TYPE_DATA_OVERFLOW.

- **Frame Valid**

Event generated on detection of the start of a video frame by the board acquisition hardware. Acquisition does not need to be active; therefore, this event can verify a valid signal is connected. The Sopera event value is: CORACQ_VAL_EVENT_TYPE_VERTICAL_SYNC.

- **Link Lock/Unlock**

Event generated on the transition from locking or not locking, of the camera required lanes.

The Sopera event values are:

CORACQ_VAL_EVENT_TYPE_LINK_LOCK

CORACQ_VAL_EVENT_TYPE_LINK_UNLOCK.

- **Frame Lost**
The Frame Lost event indicates that an acquired image failed to transfer to on-board memory. An example is if there are no free on-board buffers available for the new image. This may be the case if the image transfer from onboard buffers to host PC memory is not sustainable due to bus bandwidth issues or no host buffers are available to receive an image. The Sapera event value is: CORACQ_VAL_EVENT_TYPE_FRAME_LOST.
- **External Line Trigger Too Slow**
Event which indicates that the detected shaft encoder input tick rate is too slow for the device to take into account the specified shaft encoder multiplier value. The Sapera event value is CORACQ_VAL_EVENT_TYPE_EXT_LINE_TRIGGER_TOO_SLOW.
- **Line Trigger Too Fast**
Event which indicates a previous line-trigger did not generate a complete video line from the camera. Note that due to jitter associated with using shaft encoders, the acquisition device can delay a line trigger if a previous line has not yet completed. This event is generated if a second line trigger comes in while the previous one is still pending. This event is generated once per virtual frame. The Sapera event value is CORACQ_VAL_EVENT_TYPE_LINE_TRIGGER_TOO_FAST.
- **Shaft Encoder Reverse Count Overflow**
Event which indicates that the shaft encoder has travelled in the opposite direction expected and that the number of pulses encountered during that travel has exceeded the acquisition device counter. The acquisition device will thus not be able to skip the appropriate number of pulses when the expected direction is detected. The Sapera event value is: CORACQ_VAL_EVENT_TYPE_SHAFT_ENCODER_REVERSE_COUNT_OVERFLOW
- **Camera Missed Trigger**
Event which indicates that the camera could not respond to a trigger request as it was busy servicing a previous trigger request. The Sapera event value is CORACQ_VAL_EVENT_TYPE_CAMERA_MISSED_TRIGGER
- **Camera Overrun**
Event which indicates that the camera data and/or video has been corrupted due to insufficient buffer space in the camera. The Sapera event value is: CORACQ_VAL_EVENT_TYPE_CAMERA_OVERRUN
- **Link Error**
Event which indicates that an error has occurred on one or more of the lanes. Information about the source of the link error and the number of occurrences of this error can be retrieved using the SapAcqCallbackInfo class.
- **Slave Link Lock/Unlock**
Event generated on the transition from locking or not locking, of the slave communication lane. The Sapera event values are:
 - CORACQ_VAL_EVENT_TYPE_SLAVE_LINK_LOCK
 - CORACQ_VAL_EVENT_TYPE_SLAVE_LINK_UNLOCK.
- **GetGenericParam0:** returns the source of the error:
 - 1: CRC Error
 - 2: 64/66B Error
 - 3: Packet Buffer Overflow
 - 4: Packet Resend
 - 5: 64B/66B Corrected Error
- **GetGenericParam1:** returns a bitfield indicating which lane(s) generated the error
Bit 0 = Lane 1, Bit 1= Lane 2, ...
- **GetCustomSize:** returns 7 * UINT32
- **GetCustomData:** returns the number of errors per lane. There are 7 entries, each entry being a UINT32.

Transfer Events

Transfer events are the ones related to the transfer module. Transfer events provide feedback on image transfer from onboard memory frame buffers to PC memory frame buffers.

- **Start of Frame**
Start of Frame event generated when the first image pixel is transferred from on-board memory into PC memory.
The Sapera event value is CORXFER_VAL_EVENT_TYPE_START_OF_FRAME.
- **End of Frame**
End of Frame event generated when the last image pixel is transferred from on-board memory into PC memory.
The Sapera event value is CORXFER_VAL_EVENT_TYPE_END_OF_FRAME.
- **End of Line**
The End of Line event is generated after a video line is transferred to a PC buffer.
The Sapera event value is CORXFER_VAL_EVENT_TYPE_END_OF_LINE.
- **End of N Lines**
The End of N Lines event is generated after a set number of video lines are transferred to a PC buffer. The Sapera event value is CORXFER_VAL_EVENT_TYPE_END_OF_NLINES.
- **End of Transfer**
End of Transfer event generated at the completion of the last image transfer from on-board memory into PC memory. Issue a stop command to the transfer module to complete a transfer (if transfers are already in progress). If a frame transfer of a fixed number of images is requested, the transfer module will stop transfer automatically. The Sapera event value is CORXFER_VAL_EVENT_TYPE_END_OF_TRANSFER.

Trigger Signal Validity

The ACU ignores external trigger signal noise with its programmable debounce control. Program the debounce parameter for the minimum pulse duration considered as a valid external trigger pulse. For more information see Note 1: General Inputs / External Trigger Inputs Specifications.

Supported Transfer Cycling Methods

The Xtium2-CLHS PX8 supports the following transfer modes, which are either synchronous or asynchronous.

Images are accumulated in on-board memory in a FIFO type manner. On-board memory can get filled up if the rate at which the images are acquired is greater than the rate at which the DMA engine can write them to host buffer memory. On-board memory can also get filled-up if there are no more empty buffers available to transfer the on-board images.

When no memory is available for a new image to be stored in on-board memory, the image is discarded and a CORACQ_VAL_EVENT_TYPE_FRAME_LOST or trash buffer callback is generated. If a CORACQ_VAL_EVENT_TYPE_FRAME_LOST occurs when host buffers are available, it can indicate a problem with the PX8 bus bandwidth.

If image buffers are constructed using a trash buffer (SapBufferWithTrash using a transfer cycle mode with trash), when no host buffers are available and no memory is available for a new image to be stored in on-board memory, the SapXferCallbackInfo::IsTrash (C++) function or SaxXferNotifyEventsArgs.Trash (.NET) property returns true. If a trash callback function has been registered during construction of the SapTransfer object, it will be executed when a trash event occurs.

When stopping the image acquisition, the event CORXFER_VAL_EVENT_TYPE_END_OF_TRANSFER will occur after all images currently in the on-board memory are transferred to host buffer memory. Note that if the application does not provide enough empty buffers, the Xtium2 event will not occur and an acquisition abort will be required.

- CORXFER_VAL_CYCLE_MODE_SYNCHRONOUS_WITH_TRASH
Before cycling to the next buffer in the list, the transfer device will check the next buffer's

state. If its state is full, the transfer will keep the image in on-board memory until the next buffer's state changes to empty. If the on-board memory gets filled, trash callbacks will be generated.

- **CORXFER_VAL_CYCLE_MODE_SYNCHRONOUS_NEXT_EMPTY_WITH_TRASH**
When starting an acquisition, the buffer list is put in an empty buffer queue list in the exact order they were added to the transfer. Whenever a user sets a buffer to empty, it is added to the empty buffer queue list, so that after cycling once through the original buffer list, the buffers acquired into will follow the order in which they are put empty by the user. So in this mode, the on-board images will be transferred to host buffer memory as long as there are buffers in the empty buffer queue list. If no buffers are available on the host and the on-board memory gets filled, trash callbacks will be generated.
- **CORXFER_VAL_CYCLE_MODE_ASYNCHRONOUS**
The transfer device cycles through all buffers in the list without concern about the buffer state.

The following table describes the possible buffer states and resulting behavior:

Trash Buffer (cycling mode with trash)	Xtium2 On-Board Memory State	Host Sapera Buffer State	Resulting Event
NO	Empty buffer available (at least 1)	Empty buffer available (at least 1)	Normal acquisition events
NO	Empty buffer available (at least 1)	Full	Acquire into Xtium2 on-board memory
NO	Full	Empty buffer available (at least 1)	Frame Lost Event
NO	Full	Full	Frame Lost Event
YES	Empty buffer available (at least 1)	Empty buffer available (at least 1)	Normal acquisition events
YES	Empty buffer available (at least 1)	Full	Acquire into Xtium2 on-board memory
YES	Full	Empty buffer available (at least 1)	Frame Lost Event
YES	Full	Full	Trash Callback

By default, the buffer state (empty or full) is automatically managed by Sapera LT; it can be managed manually by the user if necessary.

Output LUT Availability

The following table defines the supported output LUT (look up tables) for the Xtium2-CLHS PX8. Note that unsupported modes are not listed.

Number of Digital Bits	Output Pixel Format	LUT Format	Notes*
8	MONO 8	8-in, 8-out	
8	MONO 16	8-in, 16-out	8 bits in 8 LSBs of 16-bit
10	MONO 8	10-in, 8-out	
10	MONO 16	10-in, 16-out	10 bits in 10 LSBs of 16-bit
12	MONO 8	12-in, 8-out	8 MSB
12	MONO 16	12-in, 16-out	12 bits in 12 LSBs of 16-bit
8 x 3 (RGB)	RGB888	8-in, 8-out	
8 x 3 (RGB)	RGB8888	8-in, 8-out	

* When no LUTs are available or LUTs are disabled, the data is packed in the LSBs of the target destination.

Metadata: Theory of Operation

The following provides additional details on the metadata implementation.

Metadata Data Structure

The Xtium2-CLHS PX8 supports metadata at the end of each line when enabled through the parameter `CORACQ_PRM_META_DATA`. The metadata consists of 64 bytes. The content of the metadata represents a snapshot of the state of the frame grabber at the beginning of each LVAL received.

```
typedef struct
{
    ULONGLONG shaftEncoderCount;
    ULONGLONG lineCount;
    ULONGLONG lineTriggerCount;
    ULONGLONG timeStamp;
    ULONG frameCounter;
    UCHAR generalInputs;
    UCHAR generalOutputs;
    UCHAR biDirectionalIOs;
    UCHAR reserved[25];
} MX4_METADATA, *PMX4_METADATA;
```

- **shaftEncoderCount**: 64-bit counter of pulses received on the shaft encoder. This is a 'machine counter' that increments in one direction (forward) and decrements (reverse) in the opposite direction.
- **lineCount**: 64-bit counter of line valid (LVAL) received.
- **lineTriggerCount**: 64-bit counter of line triggers sent to the camera.
- **timeStamp**: 64-bit counter of the frame grabber on-board timestamp. See also `CORACQ_PRM_TIME_STAMP_BASE` and `CORACQ_PRM_TIME_STAMP`.
- **frameCounter**: 32-bit counter of frames received. This represents the frame number that the line belongs to.
- **generalInputs**: status of the general inputs (for example, Low, bit = 0 or High, bit = 1).
- **generalOutputs**: status of the general outputs (for example, Low, bit = 0 or High, bit = 1).
- **biDirectionalIOs**: status of the bi-directional I/Os (for example, Low, bit = 0 or High, bit = 1).
- **reserved**: 25 bytes reserved for future usage.

For a demo application showing this feature, please contact Teledyne DALSA technical support.

Flat Field Correction: Theory of Operation

The following provides additional details on the Flat Field Correction and Flat Line Correction (FFC/FLC) implementation.

Flat Field Correction Lists

The Xtium2-CLHS PX8 supports defining more than one Flat Field Correction (FFC) / Flat Line Correction (FLC) data sets. Using the Xfer parameter `CORXFER_PRM_FLATFIELD_CYCLE_MODE`, the user can decide to cycle automatically through the list of FFC/FLC sets by setting the parameter to `CORXFER_VAL_FLATFIELD_CYCLE_MODE_AUTOMATIC`, or select a specific FFC/FLC set from the list by setting the parameter to `CORXFER_VAL_FLATFIELD_CYCLE_MODE_OFF` and selecting the FFC/FLC index to use with the parameter `CORACQ_PRM_FLAT_FIELD_SELECT`.

While the cycling mode is set to off, users can upload new coefficients to an inactive FFC set even when grabbing. When cycling automatically, the FFC/FLC sets are selected in a round-robin fashion, changing at the beginning of every new frame.

The architecture of the Xtium2-CLHS PX8 is such that the FFC/FLC data sets are independent of the host buffers. In automatic mode, the FFC/FLC sets are chosen in a round-robin fashion as images are acquired. So if using the Xfer cycling mode Synchronous with Trash, it is recommended that the number of host buffers be a multiple of the number of FFC/FLC in the list in order to maintain the FFC/FLC relationship with the Host buffers.

- When the FFC/FLC cycle mode automatic is active, reset the acquisition module to start on the 1st FFC/FLC data set of the selected list as follows:
 - Disconnect/Reconnect the transfer (assuming 1st buffer is empty).
 - Selecting a set using the `CORACQ_PRM_FLAT_FIELD_SET_SELECT` parameter will choose the 1st FFC/FLC in the list of the selected set.

- When the FFC/FLC cycle mode automatic is active, start the acquisition module to start on a specific FFC/FLC of the selected list as follows:
 - While acquisition is stopped, by selecting an Xfer pair [ACQ, Buffer]. The index of the FFC/FLC will be selected based on the modulo of the number of FFC/FLC in the list with respect to the [ACQ, Buffer] index pair.

Flat Field Correction Sets

The concept of sets allows a user to define multiple lists of FFC/FLC correction data. The FFC/FLC API allows users to allocate and pre-program those FFC/FLC sets. When acquiring images, the board driver will cycle through the FFC/FLC list of the selected set. During that operation, users can upload new FFC/FLC data to non-active sets without any ill effects.

When changing the active set while grabbing, the new active set will be switched when the current cycling of the current list is completed.

Xtium2-CLHS PX8 specific limitations

- Software driver permits the creation of up to 16 FFC/FLC sets.
- Software driver permits the use of up to 16 sets.
- When the FFC cycling mode is off, the concept of sets is not used. Whichever a FFC index is chosen using CORACQ_PRM_FLAT_FIELD_SELECT, it will be used independently of the set it belongs to.
- Upload of any FFC data is permitted at any time, even while grabbing. If an upload is done to an FFC index of the currently select set while grabbing, then the resulting acquired image will be undefined.
- When changing FFC cycling mode, the acquisition must be stopped.

Programming the sets

The following scheme is used to program FFC/FLC data within a set:

```
// select an active set
CorAcqSetPrm( hAcq, CORAQ_PRM_FLAT_FIELD_SET_SELECT, 0);

// Create 4 new FFC that will be part of the currently active set `0`
For( i = 0; i < 4; i++)
{
CorAcqNewFlatfield( hAcq, pFlatfieldNumber); // Will create FFC #1, #2, #3, #4
}

// select an active set
CorAcq SetPrm( hAcq, CORAQ_PRM_FLAT_FIELD_SET_SELECT, 1);

// Create 4 new FFC that will be part of the currently active set `1`
For( i = 0; i < 4; i++)
{
CorAcqNewFlatfield( hAcq, pFlatfieldNumber); // Will create FFC #5, #6, #7, #8
}
```

Xtium2-CLHS PX8 Supported Parameters

The tables below describe the Spera capabilities supported by the Xtium2-CLHS PX8. Unless specified, each capability applies to all configuration modes and all acquisition modes.

Note: The information here is subject to change. The application needs to verify capabilities. New board driver releases may change product specifications.

Spera describes the Xtium2-CLHS PX8 family as:

- Board Server: Xtium2-CLHS_PX8_1
- Acquisition Module: *dependent on firmware used*

Camera Related Capabilities

Capability	Values
CORACQ_CAP_CONNECTOR_TYPE	CORACQ_VAL_CONNECTOR_TYPE_CLHS (0x10)

Camera Related Parameters

Parameter	Values
CORACQ_PRM_CHANNEL	CORACQ_VAL_CHANNEL_SINGLE (0x1)
CORACQ_PRM_FRAME	CORACQ_VAL_FRAME_PROGRESSIVE (0x2)
CORACQ_PRM_INTERFACE	CORACQ_VAL_INTERFACE_DIGITAL (0x2)
CORACQ_PRM_SCAN	CORACQ_VAL_SCAN_AREA (0x1) CORACQ_VAL_SCAN_LINE (0x2)
CORACQ_PRM_SIGNAL	CORACQ_VAL_SIGNAL_DIFFERENTIAL (0x2)
CORACQ_PRM_VIDEO	Mono CORACQ_VAL_VIDEO_MONO (0x1) CORACQ_VAL_VIDEO_BAYER (0x10) RGB CORACQ_VAL_VIDEO_RGB (0x8) CORACQ_VAL_VIDEO_RGBY (0x40)
CORACQ_PRM_PIXEL_DEPTH	Mono 8 bits, # LUT = 1, LUT format = CORDATA_FORMAT_MONO8 8 bits, # LUT = 1, LUT format = CORDATA_FORMAT_MONO16 10 bits, # LUT = 1, LUT format = CORDATA_FORMAT_MONO8 10 bits, # LUT = 1, LUT format = CORDATA_FORMAT_MONO16 12 bits, # LUT = 1, LUT format = CORDATA_FORMAT_MONO8 12 bits, # LUT = 1, LUT format = CORDATA_FORMAT_MONO16 14 bits, # LUT = 0, LUT format = CORDATA_FORMAT_MONO16 16 bits, # LUT = 0, LUT format = CORDATA_FORMAT_MONO16 RGB 8 bits, # LUT = 1, LUT format = CORDATA_FORMAT_COLORNI8 12 bits, # LUT = 1, LUT format = CORDATA_FORMAT_COLORNI8 12 bits, # LUT = 1, LUT format = CORDATA_FORMAT_COLORNI16
CORACQ_PRM_VIDEO_STD	CORACQ_VAL_VIDEO_STD_NON_STD (0x1)
CORACQ_PRM_FIELD_ORDER	CORACQ_VAL_FIELD_ORDER_NEXT_FIELD (0x4)
CORACQ_PRM_HACTIVE	Mono min = 32 pixel max = 65536 pixel step = 32 pixel RGB min = 32 pixel max = 16384 pixel step = 32 pixel * minimum is per lane
CORACQ_PRM_VACTIVE	min = 1 line max = 16777215 line step = 1 line
CORACQ_PRM_TIME_INTEGRATE_METHOD	CORACQ_VAL_TIME_INTEGRATE_METHOD_10 (0x200) CORACQ_VAL_TIME_INTEGRATE_METHOD_11 (0x400) CORACQ_VAL_TIME_INTEGRATE_METHOD_12 (0x800)
CORACQ_PRM_CAM_TRIGGER_METHOD	CORACQ_VAL_CAM_TRIGGER_METHOD_3 (0x4)
CORACQ_PRM_CAM_NAME	Mono Default Camera Link HS Line Scan Mono RGB Default Camera Link HS Line Scan Color

CORACQ_PRM_LINE_INTEGRATE_METHOD	CORACQ_VAL_LINE_INTEGRATE_METHOD_8 (0x80) CORACQ_VAL_LINE_INTEGRATE_METHOD_9 (0x100) CORACQ_VAL_LINE_INTEGRATE_METHOD_10 (0x200)
CORACQ_PRM_LINE_TRIGGER_METHOD	CORACQ_VAL_LINE_TRIGGER_METHOD_2 (0x2)
CORACQ_PRM_LINE_TRIGGER_DELAY	min = 0 nsec max = 4294967295 nsec step = 1 nsec
CORACQ_PRM_CHANNELS_ORDER	CORACQ_VAL_CHANNELS_ORDER_NORMAL (0x1)
CORACQ_PRM_CAM_LINE_TRIGGER_FREQ_MIN	1 Hz
CORACQ_PRM_CAM_LINE_TRIGGER_FREQ_MAX	10000000 Hz
CORACQ_PRM_CAM_TIME_INTEGRATE_DURATION_MIN	1 µs
CORACQ_PRM_CAM_TIME_INTEGRATE_DURATION_MAX	42949672 µs
CORACQ_PRM_CAM_IO_CONTROL (*)	
CORACQ_PRM_DATA_VALID_ENABLE	TRUE FALSE
CORACQ_PRM_BAYER_ALIGNMENT	Not available
CORACQ_PRM_CAM_CONTROL_DURING_READOUT	CORACQ_VAL_CAM_CONTROL_DURING_READOUT_INVALID (0x0) CORACQ_VAL_CAM_CONTROL_DURING_READOUT_VALID (0x01) CORACQ_VAL_CAM_CONTROL_DURING_READOUT_IGNORE (0x2)
CORACQ_PRM_DATA_LANES	PX8 PX8 HR PX8 LC min = 1 lane, max = 7 lanes, step = 1 lane min = 1 lane, max = 4 lanes, step = 1 lane
CORACQ_PRM_BIT_TRANSFER_RATE	10 Gbps
CORACQ_PRM_CLHS_CONFIGURATION	CORACQ_VAL_CLHS_CONFIGURATION_MANUAL_ACQ_START_STOP (0x8)

VIC Related Parameters

Parameter	Values
CORACQ_PRM_CAMSEL	Mono RGB CAMSEL_MONO = from 0 to 0 CAMSEL_RGB = from 0 to 0
CORACQ_PRM_CROP_LEFT	Mono min = 0 pixel max = 65528 pixel step = 4 pixel RGB min = 0 pixel max = 16376 pixel step = 1 pixel
CORACQ_PRM_CROP_TOP	min = 0 line max = 16777215 line step = 1 line
CORACQ_PRM_CROP_WIDTH	Mono min = 32 pixel max = 65536 pixel step = 4 pixel RGB min = 32 pixel max = 16384 pixel step = 1 pixel * Maximum allowed is 128 kBytes, so maximum in pixels is dependent on the output pixel depth.
CORACQ_PRM_CROP_HEIGHT	min = 1 line max = 16777215 line step = 1 line
CORACQ_PRM_DECIMATE_METHOD	CORACQ_VAL_DECIMATE_DISABLE (0x1)
CORACQ_PRM_LUT_ENABLE	TRUE FALSE
CORACQ_PRM_LUT_NUMBER	Default = 0
CORACQ_PRM_STROBE_ENABLE	TRUE FALSE
CORACQ_PRM_STROBE_METHOD	CORACQ_VAL_STROBE_METHOD_1 (0x1) CORACQ_VAL_STROBE_METHOD_3 (0x4) CORACQ_VAL_STROBE_METHOD_4 (0x8) CORACQ_VAL_STROBE_METHOD_5 (0x10)

CORACQ_PRM_STROBE_POLARITY		CORACQ_VAL_ACTIVE_LOW (0x1) CORACQ_VAL_ACTIVE_HIGH (0x2)
CORACQ_PRM_STROBE_DURATION		min = 1 μ s max = 42949672 μ s step = 1 μ s
CORACQ_PRM_STROBE_DELAY		min = 0 μ s max = 42949672 μ s step = 1 μ s
CORACQ_PRM_TIME_INTEGRATE_ENABLE		TRUE FALSE
CORACQ_PRM_TIME_INTEGRATE_DURATION		min = 1 μ s max = 42949672 μ s step = 1 μ s
CORACQ_PRM_CAM_TRIGGER_ENABLE		TRUE FALSE
CORACQ_PRM_OUTPUT_FORMAT	Mono RGB	CORACQ_VAL_OUTPUT_FORMAT_MONO8 CORACQ_VAL_OUTPUT_FORMAT_MONO16 CORACQ_VAL_OUTPUT_FORMAT_MONO8P2 CORACQ_VAL_OUTPUT_FORMAT_MONO8P3 CORACQ_VAL_OUTPUT_FORMAT_MONO8P4 CORACQ_VAL_OUTPUT_FORMAT_MONO16P2 CORACQ_VAL_OUTPUT_FORMAT_MONO16P4 CORACQ_VAL_OUTPUT_FORMAT_RGB8888 CORACQ_VAL_OUTPUT_FORMAT_RGB888 CORACQ_VAL_OUTPUT_FORMAT_RGB16161616 CORACQ_VAL_OUTPUT_FORMAT_RGBP8 CORACQ_VAL_OUTPUT_FORMAT_RGBAP8 CORACQ_VAL_OUTPUT_FORMAT_RGBP16
CORACQ_PRM_EXT_TRIGGER_ENABLE		CORACQ_VAL_EXT_TRIGGER_OFF (0x1) CORACQ_VAL_EXT_TRIGGER_ON (0x8)
CORACQ_PRM_VIC_NAME	Mono RGB	Default Camera Link HS Line Scan Mono Default Camera Link HS Line Scan Color
CORACQ_PRM_LUT_MAX		1
CORACQ_PRM_EXT_TRIGGER_DETECTION		CORACQ_VAL_ACTIVE_LOW (0x1) CORACQ_VAL_ACTIVE_HIGH (0x2) CORACQ_VAL_RISING_EDGE (0x4) CORACQ_VAL_FALLING_EDGE (0x8)
CORACQ_PRM_LUT_FORMAT	Mono RGB	Default = CORDATA_FORMAT_MONO8 Default = CORDATA_FORMAT_COLORNI8
CORACQ_PRM_LINE_INTEGRATE_ENABLE		TRUE FALSE
CORACQ_PRM_LINE_INTEGRATE_DURATION		min = 1 nsec max = 4294967295 nsec step = 1 nsec
CORACQ_PRM_LINE_TRIGGER_ENABLE		TRUE FALSE
CORACQ_PRM_EXT_FRAME_TRIGGER_ENABLE		TRUE FALSE
CORACQ_PRM_EXT_FRAME_TRIGGER_DETECTION		CORACQ_VAL_ACTIVE_LOW (0x1) CORACQ_VAL_ACTIVE_HIGH (0x2) CORACQ_VAL_RISING_EDGE (0x4) CORACQ_VAL_FALLING_EDGE (0x8) CORACQ_VAL_DOUBLE_PULSE_RISING_EDGE (0x20) CORACQ_VAL_DOUBLE_PULSE_FALLING_EDGE (0x40) CORACQ_VAL_DOUBLE_PULSE_RISING_EDGE_ORDER_REVERSE (0x80) CORACQ_VAL_DOUBLE_PULSE_FALLING_EDGE_ORDER_REVERSE (0x100)
CORACQ_PRM_EXT_LINE_TRIGGER_ENABLE		TRUE FALSE
CORACQ_PRM_EXT_LINE_TRIGGER_DETECTION		CORACQ_VAL_RISING_EDGE (0x4) CORACQ_VAL_FALLING_EDGE (0x8)
CORACQ_PRM_SNAP_COUNT		Not Available
CORACQ_PRM_INT_LINE_TRIGGER_ENABLE		TRUE FALSE
CORACQ_PRM_INT_LINE_TRIGGER_FREQ		Default = 5000 Hz
CORACQ_PRM_BIT_ORDERING		CORACQ_VAL_BIT_ORDERING_STD (0x1)

CORACQ_PRM_EXT_TRIGGER_LEVEL	CORACQ_VAL_LEVEL_TTL (0x1) CORACQ_VAL_LEVEL_422 (0x2) CORACQ_VAL_LEVEL_12VOLTS (0x040) CORACQ_VAL_LEVEL_24VOLTS (0x8)
CORACQ_PRM_STROBE_LEVEL	CORACQ_VAL_LEVEL_TTL (0x1)
CORACQ_PRM_EXT_FRAME_TRIGGER_LEVEL	CORACQ_VAL_LEVEL_TTL (0x1) CORACQ_VAL_LEVEL_422 (0x2) CORACQ_VAL_LEVEL_12VOLTS (0x040) CORACQ_VAL_LEVEL_24VOLTS (0x8)
CORACQ_PRM_EXT_LINE_TRIGGER_LEVEL	CORACQ_VAL_LEVEL_422 (0x2)
CORACQ_PRM_INT_LINE_TRIGGER_FREQ_MIN	8 Hz
CORACQ_PRM_INT_LINE_TRIGGER_FREQ_MAX	500000 Hz
CORACQ_PRM_MASTER_MODE	Not available
CORACQ_PRM_SHAFT_ENCODER_DROP	min = 0 tick max = 254 tick step = 1 tick
CORACQ_PRM_SHAFT_ENCODER_ENABLE	TRUE FALSE
CORACQ_PRM_EXT_TRIGGER_FRAME_COUNT	min = 1 frame max = 262142 frame step = 1 frame Note: Infinite not supported
CORACQ_PRM_INT_FRAME_TRIGGER_ENABLE	TRUE FALSE
CORACQ_PRM_INT_FRAME_TRIGGER_FREQ	min = 1 milli-Hz max = 1000000000 milli-Hz step = 1 milli-Hz
CORACQ_PRM_STROBE_DELAY_2	Not Available
CORACQ_PRM_FRAME_LENGTH	CORACQ_VAL_FRAME_LENGTH_FIX (0x1) CORACQ_VAL_FRAME_LENGTH_VARIABLE (0x2)
CORACQ_PRM_FLIP	CORACQ_VAL_FLIP_OFF (0x00) CORACQ_VAL_FLIP_HORZ (0x01)
CORACQ_PRM_EXT_TRIGGER_DURATION	min = 0 μ s max = 255 μ s step = 1 μ s
CORACQ_PRM_TIME_INTEGRATE_DELAY	min = 0 μ s max = 42949672 μ s step = 1 μ s
CORACQ_PRM_CAM_TRIGGER_DELAY	min = 0 μ s max = 42949672 μ s step = 1 μ s
CORACQ_PRM_SHAFT_ENCODER_LEVEL	CORACQ_VAL_LEVEL_422 (0x2)
CORACQ_PRM_LUT_NENTRIES	8-bit/pixel component 256 entries 10-bit/pixel component 1024 entries 12-bit/pixel component 4096 entries 14/16-bit/pixel component 0 entries
CORACQ_PRM_EXT_FRAME_TRIGGER_SOURCE (*)	min = 0 max = 6 step = 1
CORACQ_PRM_EXT_LINE_TRIGGER_SOURCE (*)	min = 0 max = 5 step = 1
CORACQ_PRM_EXT_TRIGGER_SOURCE (*)	min = 0 max = 6 step = 1
CORACQ_PRM_SHAFT_ENCODER_MULTIPLY	min = 1 max = 32 step = (2 ^N)
CORACQ_PRM_EXT_TRIGGER_DELAY	min = 0 max = 16777215 step = 1
CORACQ_PRM_EXT_TRIGGER_DELAY_TIME_BASE	CORACQ_VAL_TIME_BASE_LINE_VALID (0x4) CORACQ_VAL_TIME_BASE_LINE_TRIGGER (0x8) CORACQ_VAL_TIME_BASE_SHAFT_ENCODER (0x40) CORACQ_VAL_TIME_BASE_NS (0x80)
CORACQ_PRM_COLOR_DECODER_ENABLE	Not Available

CORACQ_PRM_WB_GAIN	RGB	Min = 100000 max = 900000 step = 1
CORACQ_PRM_WB_GAIN_RED	RGB	Min = 100000 max = 900000 step = 1
CORACQ_PRM_WB_GAIN_GREEN	RGB	Min = 100000 max = 900000 step = 1
CORACQ_PRM_WB_GAIN_BLUE	RGB	Min = 100000 max = 900000 step = 1
CORACQ_PRM_EXT_TRIGGER_IGNORE_DELAY		min = 0 max = 42949672 step = 1
CORACQ_PRM_BOARD_SYNC_OUTPUT1_SOURCE (*)		min = 0 max = 6 step = 1
CORACQ_PRM_BOARD_SYNC_OUTPUT2_SOURCE (*)		min = 0 max = 6 step = 1
CORACQ_PRM_EXT_TRIGGER_SOURCE_STR		[0] = Automatic [1] = External Trigger #1 [2] = External Trigger #2 [3] = Board Sync #1 [4] = Board Sync #2 [5] = Software Trigger [6] = Data Valid
CORACQ_PRM_EXT_LINE_TRIGGER_SOURCE_STR		[0] = Automatic [1] = Shaft Encoder Phase A [2] = Shaft Encoder Phase B [3] = Shaft Encoder Phase A & B [4] = Board Sync #1 [5] = Board Sync #2
CORACQ_PRM_VERTICAL_TIMEOUT_DELAY		Not Available
CORACQ_PRM_POCL_ENABLE		TRUE FALSE
CORACQ_PRM_SHAFT_ENCODER_DIRECTION		CORACQ_VAL_SHAFT_ENCODER_DIRECTION_IGNORE (0x00) CORACQ_VAL_SHAFT_ENCODER_DIRECTION_FORWARD (0x01) CORACQ_VAL_SHAFT_ENCODER_DIRECTION_REVERSE (0x02) CORACQ_VAL_SHAFT_ENCODER_DIRECTION_RESCAN (0x4) CORACQ_VAL_SHAFT_ENCODER_DIRECTION_COUNT (0x8)
CORACQ_PRM_LINE_TRIGGER_AUTO_DELAY		CORACQ_VAL_LINE_TRIGGER_AUTO_DELAY_DISABLE (0x0) CORACQ_VAL_LINE_TRIGGER_AUTO_DELAY_FREQ_MAX (0x2)
CORACQ_PRM_TIME_STAMP_BASE		CORACQ_VAL_TIME_BASE_US (0x1) CORACQ_VAL_TIME_BASE_LINE_VALID (0x4) CORACQ_VAL_TIME_BASE_LINE_TRIGGER (0x8) CORACQ_VAL_TIME_BASE_SHAFT_ENCODER (0x40) CORACQ_VAL_TIME_BASE_100NS (0x200)
CORACQ_PRM_BOARD_SYNC_OUTPUT1_SOURCE_STR		[0] = Disabled [1] = External Frame Trigger [2] = Reserved [3] = External Trigger Ignore Region [4] = Shaft Encoder Before Mult/Drop [5] = Shaft Encoder After Mult/Drop [6] = Internal Line Trigger
CORACQ_PRM_BOARD_SYNC_OUTPUT2_SOURCE_STR		[0] = Disabled [1] = External Frame Trigger [2] = Reserved [3] = External Trigger Ignore Region [4] = Shaft Encoder Before Mult/Drop [5] = Shaft Encoder After Mult/Drop [6] = Internal Line Trigger
CORACQ_PRM_SHAFT_ENCODER_ORDER		CORACQ_VAL_SHAFT_ENCODER_ORDER_AUTO (0x0) CORACQ_VAL_SHAFT_ENCODER_ORDER_DROP_MULTIPLY (0x1) CORACQ_VAL_SHAFT_ENCODER_ORDER_MULTIPLY_DROP (0x2) * For auto mode, the order is multiply/drop.
CORACQ_PRM_CAM_FRAMES_PER_TRIGGER		Not Available
CORACQ_PRM_LINE_INTEGRATE_TIME_BASE		CORACQ_VAL_TIME_BASE_NS (0x80)
CORACQ_PRM_EXT_TRIGGER_IGNORE_REGION_DURATION		min = 0 μ s max = 6553 μ s step = 1 μ s

CORACQ_PRM_STROBE_DESTINATION		Not Available
CORACQ_PRM_SHAFT_ENCODER_AVERAGING_ENABLE		Not Available
CORACQ_PRM_HDR_ENABLE	PX8 Mono PX8 HR Mono PX8 RGB PX8 HR RGB PX8 LC	TRUE FALSE Not Available Not Available
CORACQ_PRM_HDR_METHOD		CORACQ_VAL_HDR_METHOD_1 (0x1)
CORACQ_PRM_HDR_WEIGHT		min = 0 max = 65535 step = 1
CORACQ_CAP_HDR_WEIGHT_DIVISOR		0x10000

ACQ Related Parameters

Parameter		Values
CORACQ_PRM_LABEL		Camera Link HS Mono
CORACQ_PRM_EVENT_TYPE		CORACQ_VAL_EVENT_TYPE_START_OF_FRAME CORACQ_VAL_EVENT_TYPE_END_OF_FRAME CORACQ_VAL_EVENT_TYPE_EXTERNAL_TRIGGER CORACQ_VAL_EVENT_TYPE_VERTICAL_SYNC CORACQ_VAL_EVENT_TYPE_FRAME_LOST CORACQ_VAL_EVENT_TYPE_DATA_OVERFLOW CORACQ_VAL_EVENT_TYPE_EXTERNAL_TRIGGER_IGNORED CORACQ_VAL_EVENT_TYPE_EXT_LINE_TRIGGER_TOO_SLOW CORACQ_VAL_EVENT_TYPE_LINK_ERROR CORACQ_VAL_EVENT_TYPE_SHAFT_ENCODER_REVERSE_COUNT_OVERFLOW CORACQ_VAL_EVENT_TYPE_LINE_TRIGGER_TOO_FAST CORACQ_VAL_EVENT_TYPE_EXTERNAL_TRIGGER_END
CORACQ_PRM_EVENT_TYPE_EX		CORACQ_VAL_EVENT_TYPE_LINK_LOCK CORACQ_VAL_EVENT_TYPE_LINK_UNLOCK CORACQ_VAL_EVENT_TYPE_CAMERA_MISSED_TRIGGER CORACQ_VAL_EVENT_TYPE_CAMERA_OVERRUN CORACQ_VAL_EVENT_TYPE_SLAVE_LINK_LOCK CORACQ_VAL_EVENT_TYPE_SLAVE_LINK_UNLOCK
CORACQ_PRM_SIGNAL_STATUS		CORACQ_VAL_SIGNAL_HSYNC_PRESENT CORACQ_VAL_SIGNAL_VSYNC_PRESENT CORACQ_VAL_SIGNAL_POWER_PRESENT CORACQ_VAL_SIGNAL_POCL_ACTIVE CORACQ_VAL_SIGNAL_LINK_LOCK CORACQ_VAL_SIGNAL_LANE1_LOCK CORACQ_VAL_SIGNAL_LANE2_LOCK CORACQ_VAL_SIGNAL_LANE3_LOCK CORACQ_VAL_SIGNAL_LANE4_LOCK CORACQ_VAL_SIGNAL_LANE5_LOCK CORACQ_VAL_SIGNAL_LANE6_LOCK CORACQ_VAL_SIGNAL_LANE7_LOCK CORACQ_VAL_SIGNAL_SLAVE_LINK_LOCK
CORACQ_PRM_FLAT_FIELD_ENABLE		PX8 PX8 HR PX8 LC TRUE / FALSE Not Available
CORACQ_CAP_FLAT_FIELD_OFFSET		8-bit Mono 10-bit Mono 12-bit Mono 14-bit Mono 16-bit Mono min = 0 max = 255 step = 1 min = 0 max = 4095 step = 1 min = 0 max = 16383 step = 1 min = 0 max = 65535 step = 1 Not Available
CORACQ_CAP_FLAT_FIELD_GAIN		8-bit Mono 10-bit Mono 12-bit Mono 14-bit Mono 16-bit Mono min = 0 max = 255 step = 1 min = 0 max = 4095 step = 1 min = 0 max = 16383 step = 1 min = 0 max = 65535 step = 1 Not Available
CORACQ_CAP_FLAT_FIELD_GAIN_DIVISOR		8-bit Mono 10-bit Mono 12-bit Mono 14-bit Mono 16-bit Mono 128 512 2048 8192 Not Available

CORACQ_PRM_FLAT_FIELD_PIXEL_REPLACEMENT_METHOD	CORACQ_VAL_FLAT_FIELD_PIXEL_REPLACEMENT_METHOD_2 (Pixel replacement is done by averaging the 2 neighborhood pixels. When one of the neighbors is not available (border image pixels, the pixel is simply replaced with the available neighbor)
CORACQ_PRM_FLAT_FIELD_SET_SELECT	min = 0 max = 16 step = 1
CORACQ_PRM_TIME_STAMP	Available
CORACQ_CAP_SERIAL_PORT_INDEX	Not Available
CORACQ_PRM_IMAGE_FILTER_ENABLE	Not Available
CORACQ_PRM_SHAFT_ENCODER_REVERSE_COUNT	Max = 65536 ticks
CORACQ_PRM_META_DATA	CORACQ_VAL_META_DATA_PER_LINE_RIGHT (0x2)
CORACQ_PRM_SHAFT_ENCODER_STATUS	CORACQ_VAL_SHAFT_ENCODER_STATUS_DIRECTION_FORWARD / CORACQ_VAL_SHAFT_ENCODER_STATUS_DIRECTION_REVERSE (0x1) CORACQ_VAL_SHAFT_ENCODER_STATUS_TOO_SLOW (0x2) CORACQ_VAL_SHAFT_ENCODER_STATUS_REVERSE_COUNT_OVERFLOW (0x4)
CORACQ_PRM_SHAFT_ENCODER_COUNT	Available

Transfer Related Capabilities

Capability	Values
CORXFER_CAP_NB_INT_BUFFERS	CORXFER_VAL_NB_INT_BUFFERS_AUTO (0x2)
CORXFER_CAP_MAX_XFER_SIZE	4294967040 Bytes
CORXFER_CAP_MAX_FRAME_COUNT	16777215 Frames
CORXFER_CAP_COUNTER_STAMP_AVAILABLE	FALSE
CORXFER_CAP_TRANSFER_SYNC	CORXFER_VAL_TRANSFER_SYNC_SUPPORTED (0x1)

Transfer Related Parameters

Parameter	Values
CORXFER_PRM_EVENT_TYPE CORXFER_PRM_EVENT_TYPE_EX	CORXFER_VAL_EVENT_TYPE_START_OF_FRAME CORXFER_VAL_EVENT_TYPE_END_OF_FRAME CORXFER_VAL_EVENT_TYPE_END_OF_LINE CORXFER_VAL_EVENT_TYPE_END_OF_NLINES CORXFER_VAL_EVENT_TYPE_END_OF_TRANSFER
CORXFER_PRM_START_MODE	CORXFER_VAL_START_MODE_ASYNCHRONOUS (0x0) CORXFER_VAL_START_MODE_SYNCHRONOUS (0x1) CORXFER_VAL_START_MODE_HALF_ASYNCHRONOUS (0x2) CORXFER_VAL_START_MODE_SEQUENTIAL (0x3)
CORXFER_PRM_CYCLE_MODE	CORXFER_VAL_CYCLE_MODE_ASYNCHRONOUS (0x0) CORXFER_VAL_CYCLE_MODE_SYNCHRONOUS_WITH_TRASH (0x2) CORXFER_VAL_CYCLE_MODE_OFF (0x3) CORXFER_VAL_CYCLE_MODE_SYNCHRONOUS_NEXT_EMPTY_WITH_TRASH (0x5)
CORXFER_PRM_FLIP	CORXFER_VAL_FLIP_OFF (0x0) CORXFER_VAL_FLIP_VERT (0x2)
CORXFER_PRM_INT_BUFFERS	* Depends on acquired image size. By default driver will optimize the number of on-board buffers.
CORXFER_PRM_EVENT_COUNT_SOURCE	CORXFER_VAL_EVENT_COUNT_SOURCE_DST (0x1) CORXFER_VAL_EVENT_COUNT_SOURCE_SRC (0x2)
CORXFER_PRM_BUFFER_TIMESTAMP_MODULE	CORXFER_VAL_BUFFER_TIMESTAMP_MODULE_ACQ (0x1) CORXFER_VAL_BUFFER_TIMESTAMP_MODULE_XFER (0x13)
CORXFER_PRM_BUFFER_TIMESTAMP_EVENT (ACQ Related)	CORACQ_VAL_EVENT_TYPE_START_OF_FRAME (0x80000) CORACQ_VAL_EVENT_TYPE_EXTERNAL_TRIGGER (0x1000000)
CORXFER_PRM_BUFFER_TIMESTAMP_EVENT (XFER Related)	CORXFER_VAL_EVENT_TYPE_END_OF_FRAME (0x800000)
CORXFER_PRM_LINE_MERGING	CORXFER_VAL_LINE_MERGING_AUTO (0x0) CORXFER_VAL_LINE_MERGING_OFF (0x2)

General Outputs #1: Capabilities (for GIO Module #0)

Outputs are available on connector J1 and J4.

Capability	Values
CORGIO_CAP_IO_COUNT	8 I/Os
CORGIO_CAP_DIR_OUTPUT	0xff
CORGIO_CAP_DIR_TRISTATE	0xff
CORGIO_CAP_EVENT_TYPE	Not Available
CORGIO_CAP_READ_ONLY	0x03 (* depends on strobe outputs reserved for acquisition device)

General Outputs #1: Parameters (for GIO Module #0)

Parameter	Values
CORGIO_PRM_LABEL	General Outputs #1
CORGIO_PRM_DEVICE_ID	0
CORGIO_PRM_OUTPUT_TYPE	CORGIO_VAL_OUTPUT_TYPE_LVTTL (0x20)
CORGIO_PRM_CONNECTOR	CORGIO_VAL_CONNECTOR_1 (0x1)

General Inputs #1: Capabilities (for GIO Module #1)

Inputs are available on connector J1 and J4.

Capability	Values
CORGIO_CAP_IO_COUNT	4 I/Os
CORGIO_CAP_DIR_OUTPUT	0x0
CORGIO_CAP_DIR_TRISTATE	0x0
CORGIO_CAP_EVENT_TYPE	CORGIO_VAL_EVENT_TYPE_RISING_EDGE (0x1) CORGIO_VAL_EVENT_TYPE_FALLING_EDGE (0x2)
CORGIO_CAP_READ_ONLY	0x03 (* depends on external trigger inputs reserved for acquisition device)

General Inputs #1: Parameters (for GIO Module #1)

Parameter	Values
CORGIO_PRM_LABEL	General Inputs #1
CORGIO_PRM_DEVICE_ID	1
CORGIO_PRM_INPUT_LEVEL	CORGIO_VAL_INPUT_LEVEL_TTL (0x1) CORGIO_VAL_INPUT_LEVEL_422 (0x2) CORGIO_VAL_INPUT_LEVEL_24VOLTS (0x8) CORGIO_VAL_INPUT_LEVEL_12VOLTS (0x40)
CORGIO_PRM_CONNECTOR	CORGIO_VAL_CONNECTOR_1 (0x1)

Bidirectional General I/Os: Capabilities (for GIO Module #2)

These I/Os are available on connector J5.

Capability	Values
CORGIO_CAP_IO_COUNT	8 I/Os
CORGIO_CAP_DIR_OUTPUT	0xff
CORGIO_CAP_DIR_TRISTATE	0xff
CORGIO_CAP_EVENT_TYPE	Not Available
CORGIO_CAP_READ_ONLY	0x03 (* depends on board syncs reserved for acquisition device)

Bidirectional General I/Os: Parameters (for GIO Module #2)

Parameter	Values
CORGIO_PRM_LABEL	Bidirectional General I/Os #1
CORGIO_PRM_DEVICE_ID	2
CORGIO_PRM_OUTPUT_TYPE	CORGIO_VAL_OUTPUT_TYPE_LVTTL (0x20)
CORGIO_PRM_INPUT_LEVEL	CORGIO_VAL_INPUT_LEVEL_LVTTL (0x20)
CORGIO_PRM_CONNECTOR	CORGIO_VAL_CONNECTOR_2 (0x2)

Sapera Servers and Resources

A Sapera Server is an abstract representation of a physical device like a frame-grabber or camera. When using the SapAcquisition or SapAcqDevice constructors, the location parameter specifies the server to use to create the object. Use the Sapera Configuration utility to find the names and indices of all Sapera servers in your system.

In Sapera LT all frame grabbers are configured using the SapAcquisition class. All CLHS cameras are GenCP compliant and are configured in Sapera LT using the SapAcqDevice class.



Note: Currently, CLHS cameras do not have their own server, therefore it is available under the Xtium2_CLHS server. For example, in CamExpert the Xtium2 server displays both the frame grabber and camera resources.

Servers	Resources			
Name	Type	Name	Index	Description
Xtium2-CLHS_PX8_1	Acquisition Module	Camera Link HS Mono	0	CLHS Mono Camera
		Camera Link HS Color RGB	1	CLHS RGB Camera
	Acquisition Device	< Device Name > * Name of Camera	0	CLHS Camera
	GIO Module	General Outputs #1	0	8 General Outputs
General Inputs #1		1	4 General Inputs	
Bidirectional General I/Os #1		2	8 Bidirectional General I/Os	

Technical Specifications

Xtium2-CLHS PX8 Board Specifications

Digital Video Input & Controls

Input Type	Camera Link HS Specifications Rev 1.0 compliant
Common Pixel Formats	Camera Link HS for 8, 10, 12, 14 and 16-bit mono and 8-bit RGB
Scanning	Area scan and Line scan
Resolution <i>note: these are Xtium2-CLHS PX8 maximums, not Camera Link HS specifications</i>	Horizontal Minimum: 32 Pixels per lane Horizontal Maximum: 8-bits/pixel x 64k Pixels/line 16-bits/pixel x 32k Pixels/line Vertical Minimum: 1 line Vertical Maximum: up to 65536—for area scan sensors infinite line count—for linescan sensors
Bit Transfer Rate	10 Gbps
Image Buffer	Available with 512 MB
Bandwidth to Host System	Approximately 6.8 GB/s (maximum obtained is dependent on firmware loaded and PC characteristics)
Controls	Compliant with Teledyne DALSA Trigger-to-Image Reliability framework Comprehensive event notifications Timing control logic for camera triggers and strobe signals 4 opto-coupled general inputs where 2 are shared acquisition trigger inputs (RS-422/TTL/12V/24V) Trigger inputs are programmable as active high or low (edge or level trigger, at maximum input frequency of 100 KHz) External trigger latency less than 100 nsec 8 LVTTTL general Outputs where 1 is shared as Strobe Output Quadrature (phase A & B) shaft encoder inputs for external web synchronization: RS-422 input maximum frequency is 5 MHz Supports camera Data Forwarding up to 5 additional boards Supports multi-camera synchronization of 2 to 4 boards I/O available on a DH60-27P connector (J1) and on 26-pin SHF-113-01-L-D-RA (J4)
Processing <i>Dependent on user loaded firmware configuration</i>	Output Lookup Table Flat Field/Flat Line Correction Bayer Mosaic Filter, 3x3 Image Filter (Convolution), 4x3 Color Calibration Filter: Contact Teledyne DALSA for availability.

Host System Requirements

Xtium2-CLHS PX8 Dimensions

Approximately 5 in. (13 cm) wide by 4 in. (10 cm) high

General System Requirements for the Xtium2-CLHS PX8

- PCI Express Gen3 x8 slot compatible;
- (will work in Gen1 or Gen2 x8 slot with reduced bandwidth to host)
- On some computers the Xtium2-CLHS PX8 may function installed in a x16 slot. The computer documentation or direct testing by the user is required.
- Xtium2-CLHS PX8 operates correctly when installed in a multi-processor system (including Hyper-Threading multi-core processors).

Operating System Support

Windows 7, Windows 8 and Windows 10, each in either 32-bit or 64-bit

Environment Specification

Ambient Temperature:	10° to 50°C (operation) -40° to 75°C (storage)
Relative Humidity:	5% to 90% non-condensing (operating) 0% to 95% (storage)
MTBF @40°C	74 years



Note: Ensure adequate airflow for proper functioning of the board across the entire temperature range of 10 – 50°C. Airflow measuring 80 LFM (linear feet per minute) across the surface of the board is recommended.

Power Requirements during Acquisition

+3.3V:	10 Watts
+12V:	8 Watts

EMI Certifications



EC & FCC DECLARATION OF CONFORMITY

We :

Teledyne Dalsa inc.
880 Rue McCaffrey
St-Laurent, Quebec, Canada
H4T 2C7

Declare under sole legal responsibility that the following products conform to the protection requirements of council directive 2014/30/EU on the approximation of the laws of member states relating to electromagnetic compatibility and are CE-marked accordingly:

Xtium2-CLHS PX8

The products to which this declaration relates are in conformity with the following relevant harmonized standards, the reference numbers of which have been published in the Official Journal of the European Communities:

EN55011: 2015 (CISPR11: 2015)	Industrial, scientific and medical – Radio-frequency disturbance characteristics – Limits and methods of measurement
EN61000-4-2: 2008	Electrostatic discharge immunity
EN61000-4-3: 2006 A1: 2007 A2: 2010	Radiated electromagnetic field immunity – radio frequencies
EN61000-4-4: 2012	Electrical fast transient immunity
EN61000-4-5: 2014	Surge immunity
EN61000-4-6: 2013	Conducted immunity
EN61000-4-8: 2009	Magnetic field immunity
EN61000-4-11: 2004	Voltage dips, short interruptions and voltage variation immunity

Further declare under our sole legal responsibility that the product listed conforms to the code of federal regulations CFR 47 part 15: 2016, subpart B, for a class A product.

Note: this product is intended to be a component of a larger industrial system. It is not intended for use in a residential system.

Waterloo, Canada
Location

2018-08-15
Date


Hank Helmond.
Manager, Quality Assurance

Figure 21: EMI Certifications

Connector and Switch Locations

Xtium2-CLHS PX8 Board Layout Drawing

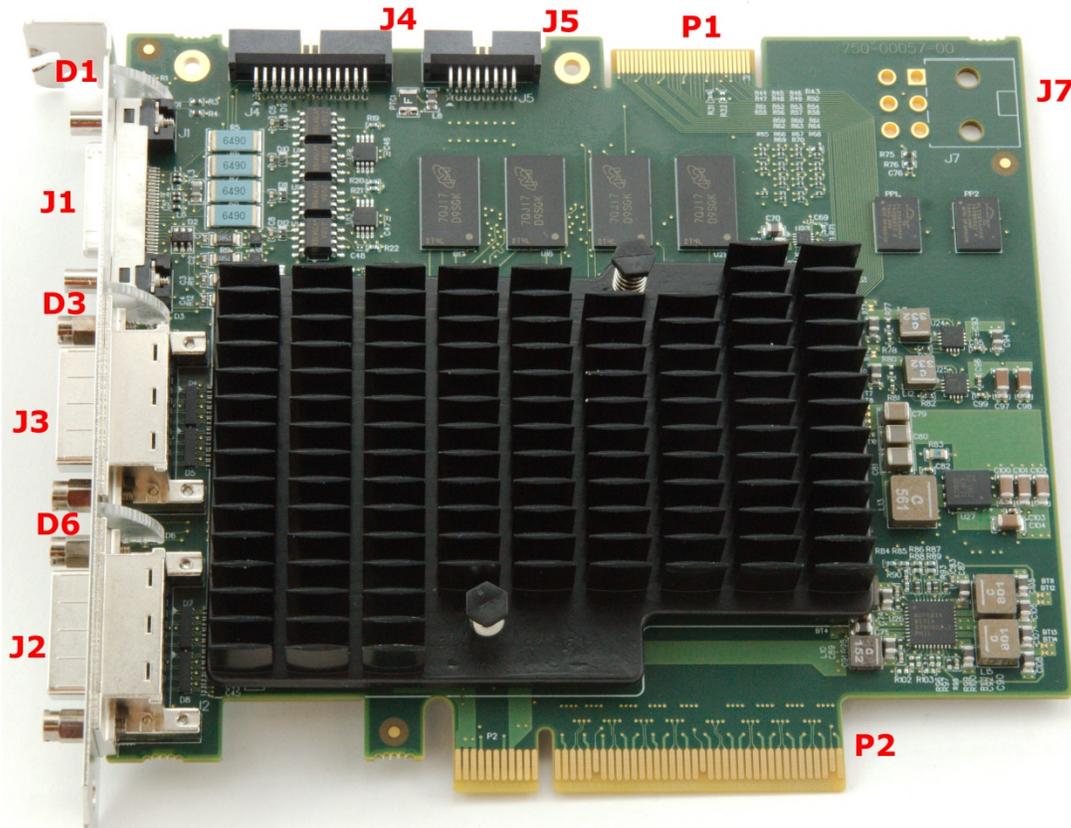


Figure 22: Board Layout

Connector / LED Description List

The following table lists components on the Xtium2-CLHS PX8 board. Detailed information concerning the connectors/LEDs follows this summary table.

Location	Description	Location	Description
J1	External I/O Signals connector (DH60-27P)	J4	Internal I/O Signals connector (26-pin SHF-113-01-L-D-RA)
D1	Boot-up/PCIe Status LED (refer to text)	J5	Multi Board Sync
J3	Camera Link HS Input Connector	P2	PCIe x8 computer bus connector (Gen3 compliant slot preferred)
D3	Camera Link HS Input status LED	P1	Reserved
J2	Camera Link HS Output Connector (used for Data Forwarding)		
D6	Data Forwarding Output status LED		

Connector and Switch Specifications

Xtium2-CLHS PX8 End Bracket Detail

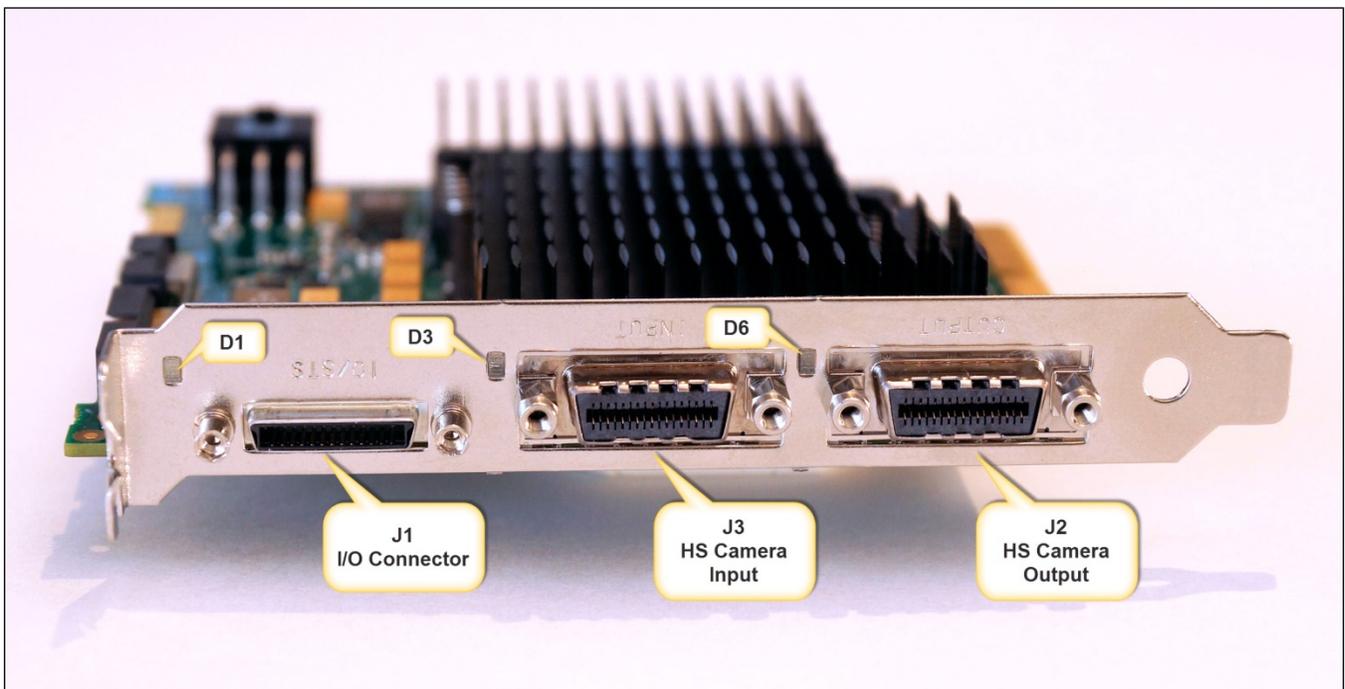
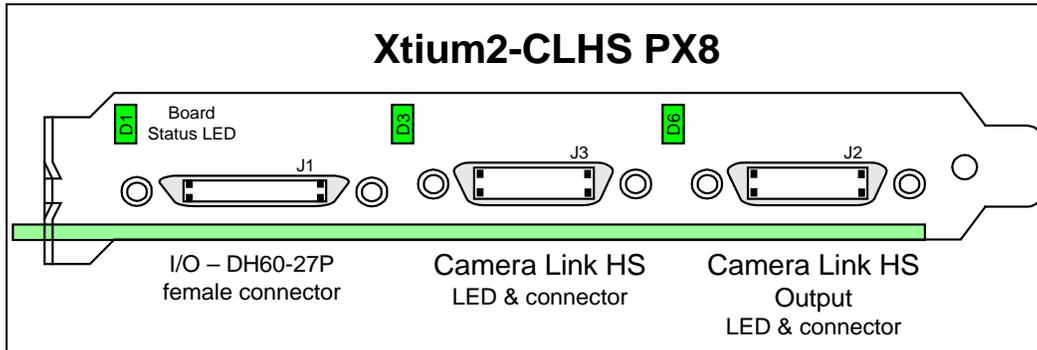


Figure 23: End Bracket Details

The hardware installation process completes with the connection of a supported camera to the Xtium2-CLHS PX8 board using a Camera Link HS cable (see the [Camera Link HS Cables Overview and Resources](#) section).

- The Xtium2-CLHS PX8 board supports one Camera Link HS camera output.
- Connect the camera to the J3 connector with a Camera Link HS cable.

Data Forwarding Setup

Distributed processing of high bandwidth image data is easily configured by inter-connecting multiple Xtium2-CLHS boards. The following description and block diagram shows the simple physical setup. The user has total control to the actual distributed processing task divisions and algorithms.

- Connect a camera to J3 of the first Xtium2-CLHS board installed in the first PC. This board is defined as the "Data Forwarding Master".
- Using a second Camera Link HS cable, connect J2 of the Data Forwarding Master Xtium2-CLHS board to J3 of second Xtium2-CLHS installed in a separate computer or the same as the first Xtium2 if it can manage the processing. This second board is defined as the "Data Forwarding Slave #1".
- Camera Link HS cables used to interconnect Xtium2-CLHS boards could be up to 15 meters.
- Optionally, the J2 connector of the Data Forwarding Slave #1 Xtium2-CLHS board can connect to J3 of a third Xtium2-CLHS ("Data Forwarding Slave #2").
- The number of Data Forwarding Slave boards should not exceed 5, for a total of 6 boards. The Xtium2 CLHS boards can either have separate computers or share computers dependent on the distributed processing requirements.
- The Xtium2-CLHS driver will automatically detect whether a board is connected to a camera (becoming the Data Forwarding Master) or is connected to forwarded data (becoming a Data Forwarding Slave).
- Each Data Forwarding Slave board has full control of the camera data portion transferred to the host computer for processing.
- The CORACQ_PRM_DATA_VALID parameter can be used in order for all frame grabbers to acquire the same triggered frames and/or lines. Once the parameter is enabled on the master frame grabber, a data valid signal is initiated by the master through the camera trigger message. The camera will then pass the data valid control in the video packets. On slave frame grabbers that also have the data valid enabled, only the video packets that have the data valid control enabled will be acquired. In the case the acquired images are of type variable frame length, the slave frame grabber must select 'Data Valid' as the 'External Frame Trigger Source' Note that during the inactive level of the the external frame trigger, there must be at least one line triggered out of the camera in order for the frame grabbers to detect the actual end of the variable frame.

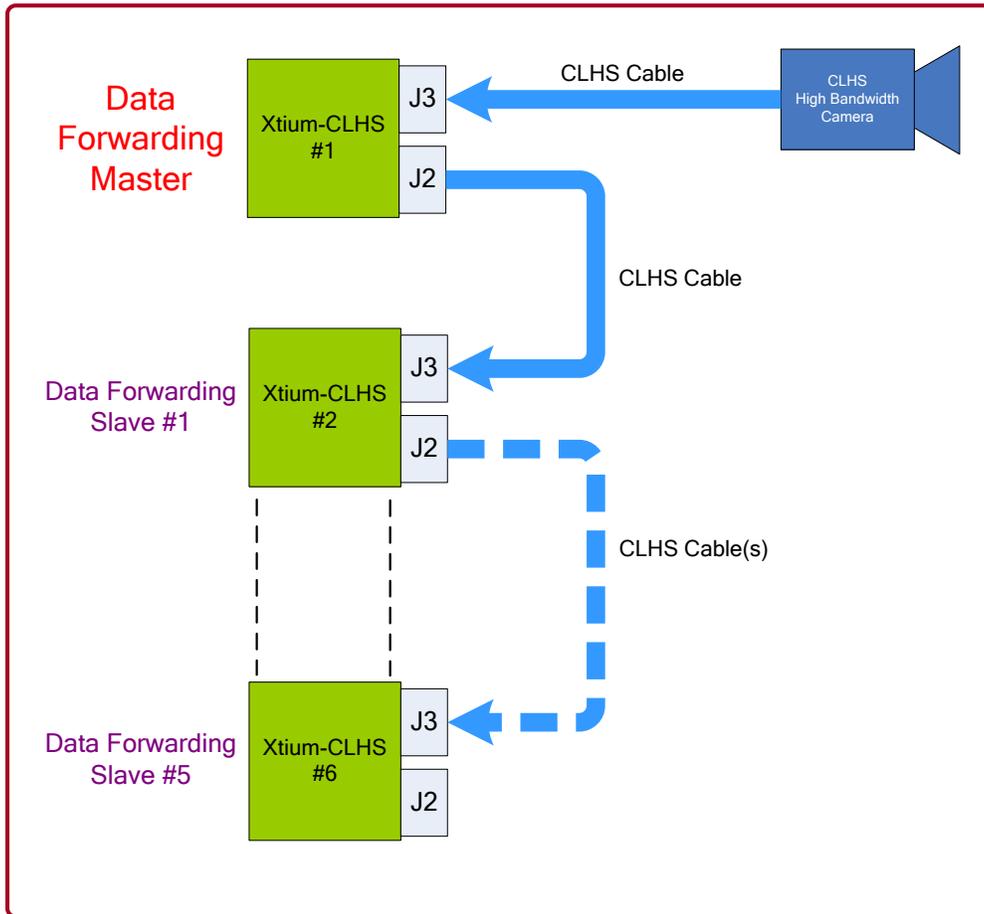


Figure 24: Data Forwarding Block Diagram

Connecting to Dual Output CLHS Camera

Distributed processing of high bandwidth image data generated by Dual Output CLHS camera is easily configured by connecting the camera to multiple Xtium2-CLHS boards. The following description and block diagram shows the simple physical setup. The user has total control to the actual distributed processing task divisions and algorithms.

- Connect camera output #1 to J3 of the first Xtium2-CLHS board installed in the first PC. This board is defined as the "Master Frame Grabber".
- Using a second Camera Link HS cable, connect camera output #2 to J3 of a second Xtium2-CLHS board installed in a separate computer or the same as the first Xtium2 if it can manage the processing. This second board is defined as the "Camera Slave Port Frame Grabber".
- The Camera Slave Port Frame Grabber must set `CORACQ_VAL_CLHS_CONFIGURATION_CAM_PORT_SLAVE` in the parameter `CORACQ_PRM_CLHS_CONFIGURATION` in order to configure the frame grabber as the one connected to a camera slave port. In this mode, camera controls are written via the Camera Master Port Frame Grabber only.
- Control of the data portion transferred on each camera output is controlled by the camera.
- The use of the `CORACQ_PRM_DATA_VALID` parameter can be used in order for all frame grabbers to acquire the same triggered frames and/or lines. Once the `CORACQ_PRM_DATA_VALID` is enabled on the master frame grabber, a data valid signal is initiated by the master frame grabber through the camera trigger message. The camera will then pass the data valid control in the video packets. On Camera Slave Port Frame Grabbers that also have the data valid enabled, only the video packets that have the data valid control enabled will be acquired.

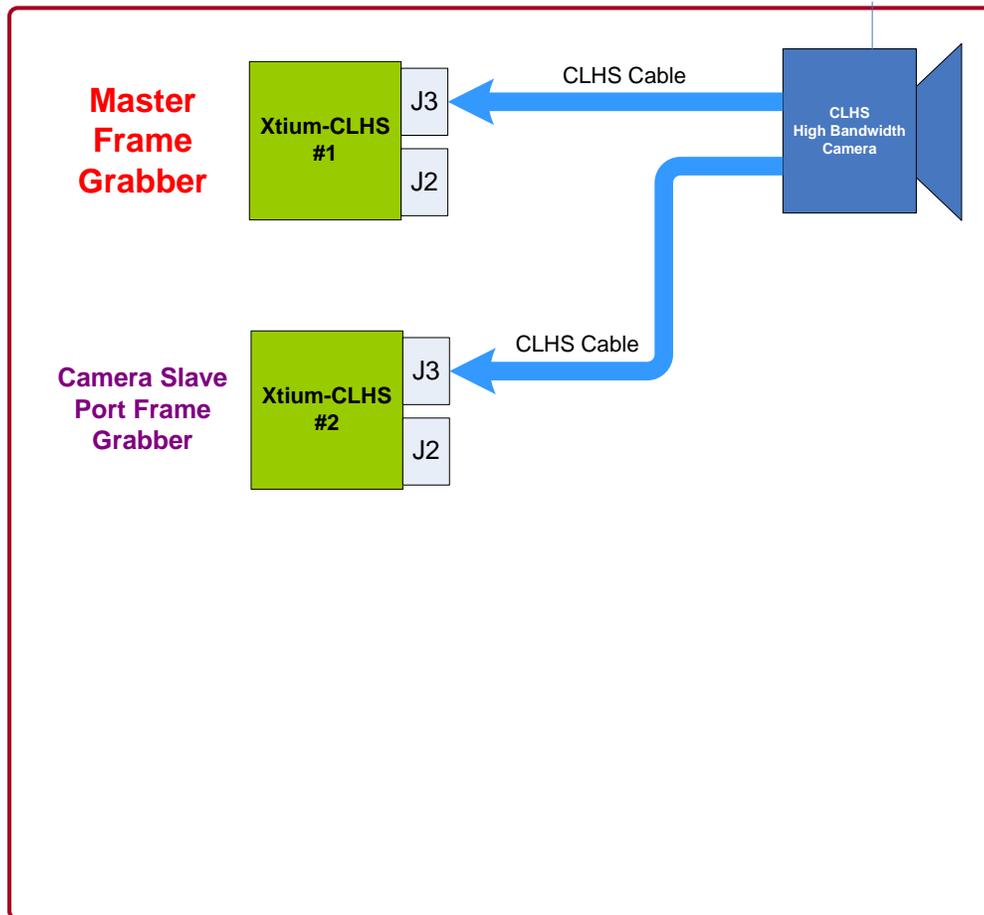


Figure 25: Dual Camera Output Connection Block Diagram

Status LEDs Functional Descriptions

Three LED indicators, mounted on the board bracket, provide information on board and connection status as per the tables below.

D1: Boot-up/PCIe Status LED — Provides general board status information

D3: Camera Link HS status LED — Indicates data status for J3 when connected to a camera or when receiving forwarded data from another Xtium2-CLHS system.

D6: Camera Link HS Forwarded Data status LED — Indicates connection status when the data forwarding connector J2 is connected to another Xtium2-CLHS.

D1: Boot-up/PCIe Status LED

Color	State	Description
Red	Solid	FPGA firmware not loaded
Green	Solid	Normal FPGA firmware loaded, Gen3 speed, link width x8
Green	Flashing	Normal FPGA firmware loaded, Gen1/Gen2 speed, link width x8
Yellow	Solid	Normal FPGA firmware loaded, Gen3 speed, link width not x8
Yellow	Flashing	Normal FPGA firmware loaded, Gen1/Gen2 speed, link width not x8
Blue	Solid	Safe FPGA firmware loaded, Gen3 speed
Blue	Flashing	Safe FPGA firmware loaded, Gen1/Gen2 speed
Red	Flashing	PCIe Training Issue – Board will not be detected by computer

D3: Camera Link HS Status LED (when a camera is connected)

The Xtium2-CLHS PX8 implements the mandatory LED states defined by the Camera Link HS Specification v1.0 RC5. The first column – Priority, defines the signaling order when multiple events are reported simultaneously.

This LED status table reflects activity on input connector J3 when a camera is connected (that is, the Xtium2 is the Data Forwarding Master).

LED State	Description
Off	Device not powered and/or waiting for software.
Flashing Orange Medium ~2Hz	The devices have established communication and determined that they are not interoperable. This would be the case when the frame grabber and the camera have different pixel depth, pixel format and/or number of lanes.
Flashing Green Medium ~2Hz	Hardware is fine, but connection not established or recently broken.
Constant Green	Link established and data transfer may take place.
Flashing Green Fast ~4Hz	Acquisition in progress.

D3: Camera Link HS Status LED (as Data Forwarding receiver)

When the Xtium2-CLHS PX8 does not have a camera connected but is used as a Data Forwarding Slave, (that is, the board receives data on J3 from another Xtium2 in a separate computer), the LED D3 describes these two additional conditions.

LED Color	State	Description
Green	Flashing	Connection not established on input connector J3
Green	Constant	Link established on input connector J3 and data transfer may take place.

D6: Data Forwarding Status LED

D6 defines the connection status for when the Camera Link HS output J2 is forwarding acquisition data to another Xtium2-CLHS in a separate computer. Note that the Xtium2-CLHS PX8 data forwarding feature is not part of the standard CLHS specifications.

LED Color	State	Description
Off	Constant	Connection not established on input connector J3 of the receiving Xtium2-CLHS
Green	Constant	Link established with the receiving Xtium2-CLHS and data transfer may take place.

J2: Data Forwarding Connector

	<p>Note: The Data Forwarding connector on the Xtium2-CLHS PX8 has the same specifications as the Camera Link HS camera connector (J3) defined in the AIA document "<i>Specifications of the Camera Link HS Interface Standard for Digital Cameras and Frame Grabbers</i>" version 1.0 RC5, ©2012 AIA. Typically there is no need to be concerned with the physical pinout of the connector or cables. Refer to their site www.visiononline.org for additional information.</p>
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J3: Camera Link HS Connector



Note: The Camera Link HS camera connector is defined in the AIA document “Specifications of the Camera Link HS Interface Standard for Digital Cameras and Frame Grabbers” version 1.0 RC5, ©2012 AIA.

Typically there is no need to be concerned with the physical pinout of the connector or cables. Refer to their site www.visiononline.org for additional information.

J1: External I/O Signals Connector (Female DH60-27P)

J4: Internal I/O Signals Connector (26-pin SHF-113-01-L-D-RA)



Warning: J1 and J4 have the same pinout assignment. Signals are routed to both connectors directly from their internal circuitry. Therefore never connect both J1 and J4 to external devices at the same time.

Description	Pin #	Pin #	Description
Ground	1	15	General Input 3 (+)
RS-422 Shaft Encoder Phase A (-)	2	16	General Input 4 (+)
RS-422 Shaft Encoder Phase A (+) (see note 3)	3	17	General Input 4 (-)
Ground	4	18	General Input 3 (-)
RS-422 Shaft Encoder Phase B (-)	5	19	Power Output 5 Volts, 100mA max
RS-422 Shaft Encoder Phase B (+)	6	20	External Trigger Input 2 or General Input 2 (-)
External Trigger Input 1/General Input 1 (-)	7	21	General Output 3
External Trigger Input 1/General Input 1 (+)	8	22	General Output 4
External Trigger Input 2/General Input 2 (+)	9	23	General Output 5
Ground	10	24	General Output 6
Strobe 1 / General Output 1 (See note 2)	11	25	General Output 7
General Output 2	12	26	General Output 8
Ground	13	27	NC
Power Output 12 Volts, 350mA max	14		

Note 1: General Inputs / External Trigger Inputs Specifications

Each of the four General Inputs are opto-coupled and able to connect to differential or single ended source signals. General Input 1 and 2 can also act as External Trigger Inputs. See “Board Information” user settings. These inputs generate individual interrupts and are read by the Sapera application. The following figure is typical for each General Input.

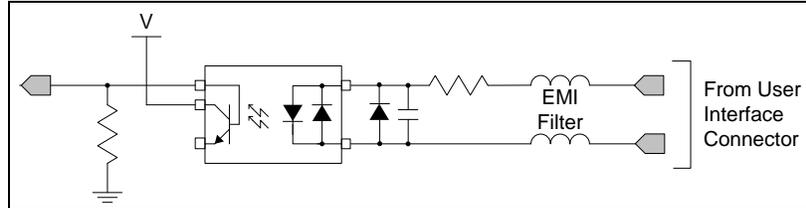


Figure 26: General Inputs Electrical Diagram

Input Details:

- Maximum input voltage is 26V.
- Maximum input signal frequency is 100 KHz.
- Each input has a 649-ohm series resistor on the opto-coupler input.
- The 0.01µF capacitor provides high frequency noise filtering.
- Minimum current is dependent on input voltage applied: $I_{optoin(min)} = (V_{optoin} - 0.5)/649\Omega$
- The switch point is software programmable to support differential RS-422 or single ended TTL, 12V or 24V input signals.

For External Trigger usage:

- Input signal is “debounced” to ensure that no voltage glitch is detected as a valid transition. This debounce circuit time constant can be programmed from 1µs to 255µs. Any pulse smaller than the programmed value is blocked and therefore not seen by the board. If no debounce value is specified (value of 0µs), the minimum value of 1µs will be used.
- Refer to Sapera parameters:
CORACQ_PRM_EXT_TRIGGER_SOURCE
CORACQ_PRM_EXT_TRIGGER_ENABLE
CORACQ_PRM_EXT_TRIGGER_LEVEL
CORACQ_PRM_EXT_FRAME_TRIGGER_LEVEL
CORACQ_PRM_EXT_TRIGGER_DETECTION
CORACQ_PRM_EXT_TRIGGER_DURATION
- See also *.cvi file entries:
- External Trigger Level, External Frame Trigger Level, External Trigger Enable, External Trigger Detection.
- External Trigger Input 2 used for two pulse external trigger with variable frame length line scan acquisition.

Trigger Signal Total Delay

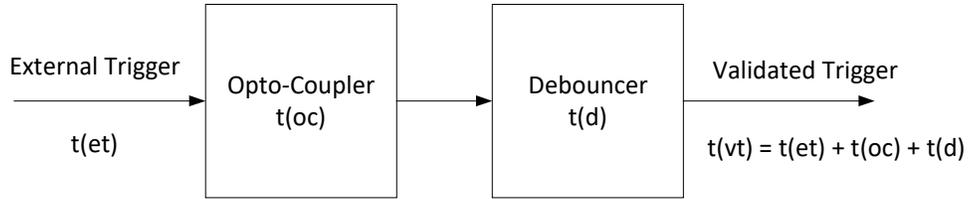


Figure 27: External Trigger Input Validation & Delay

Let	$t(et)$ = time of external trigger in μs
	$t(oc)$ = time opto-coupler takes to change state (time varies dependent on input voltage)
	$t(d)$ = user set debounce duration from 1 to 255 μs
	$t(vt)$ = time of validated trigger in μs



Note: Teledyne DALSA recommends using the fastest transition to minimize the time it takes for the opto-coupler to change state.

If the duration of the external trigger is $> t(oc) + t(d)$, then a valid acquisition trigger is detected.

It is possible to emulate an external trigger using the software trigger which is generated by a function call from an application.

Input Switching Points and Propagation Delay

Trigger Level	Switch Point	Propagation Delay $t(oc)$ (rising edge signal \uparrow)	Propagation Delay $t(oc)$ (falling edge signal \downarrow)
RS-422	1.6V	1.75 μs	5.5 μs
TTL	1.6V	1.75 μs	5.5 μs
12V	6V	2.6 μs	2.6 μs
24V	12V	1.9 μs	3.1 μs

Block Diagram: Connecting External Drivers to General Inputs on J1

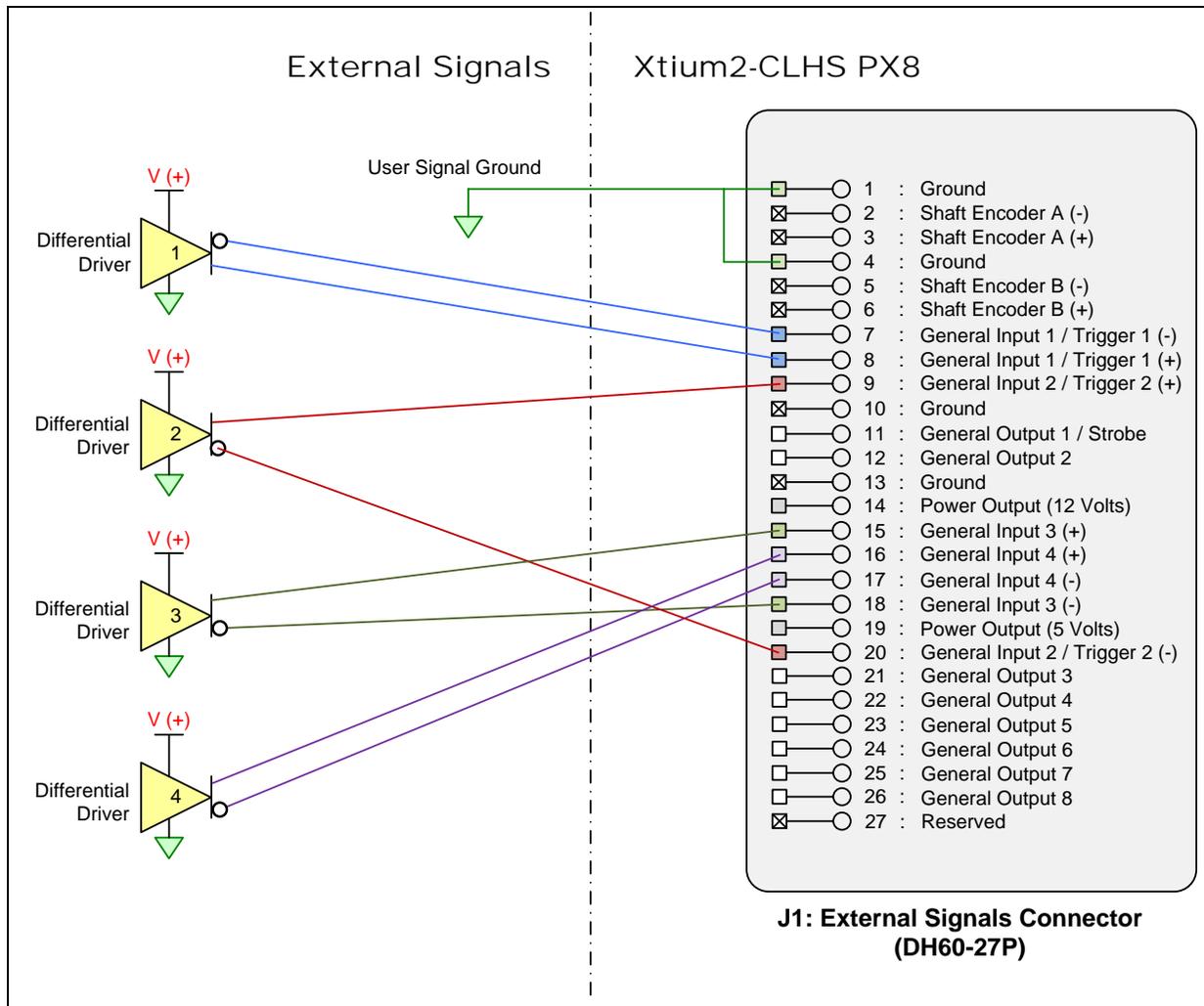


Figure 28: External Signals Connection Diagram

External Driver Electrical Requirements

The Xtium2-CLHS allows user selected (software programmable) input switching points to support differential (RS-422) input signals and single ended (TTL, 12V or 24V) input signals. The following table defines the external signal voltage requirements from the driver circuits connected to the Xtium2 external inputs.

Input Level	Description	MIN	MAX
RS-422	Output Voltage High (V_{OH})	2.4 V	13.0 V
	Output Voltage Low (V_{OL})	-2.4 V	-13.0 V
TTL	Output Voltage High (V_{OH})	2.4 V	5.5 V
	Output Voltage Low (V_{OL})	0 V	0.8 V
12V	Output Voltage High (V_{OH})	9 V	13.2 V
	Output Voltage Low (V_{OL})	0 V	3 V
24V	Output Voltage High (V_{OH})	18 V	26.4 V
	Output Voltage Low (V_{OL})	0 V	6 V

Note 2: General Outputs /Strobe Output Specifications

Each of the eight General Outputs is TTL (3.3V) compatible. General Output 1 also functions as the Strobe Output controlled by Sapera strobe control functions. See “Board Information” user settings. The following figure is typical for each General Output.

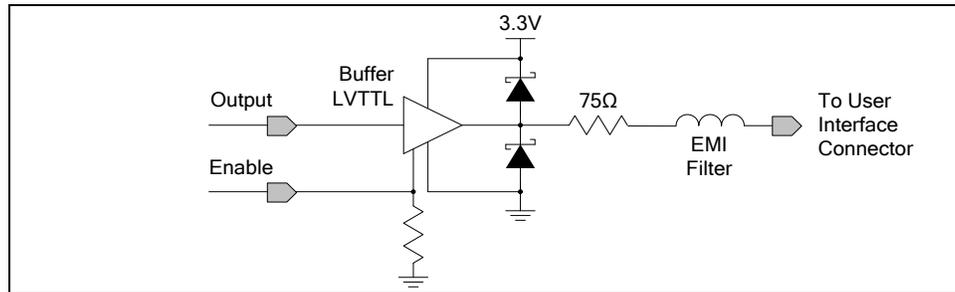


Figure 29: General Outputs Electrical Diagram

Output Details:

- Each output has a 75-ohm series resistor
- The 2 diodes protect the LVTTL buffer against overvoltage
- Each output is a tri-state driver, enabled by software
- Minimum guaranteed output current is +/- 24mA @ 3.3V
- Maximum output current is 50mA
- Maximum short circuit output current is 44mA
- Minimum voltage for output level high is 2.4V, while maximum voltage for output low is 0.55V
- Maximum output switching frequency is limited by driver and register access on the PCIe bus.

For Strobe Usage:

- Refer to Sapera Strobe Methods parameters:
CORACQ_PRM_STROBE_ENABLE
CORACQ_PRM_STROBE_POLARITY
CORACQ_PRM_STROBE_LEVEL
CORACQ_PRM_STROBE_METHOD
CORACQ_PRM_STROBE_DELAY
CORACQ_PRM_STROBE_DURATION
- See also *.cvi file entries:
Strobe Enable, Strobe Polarity, Strobe Level, Strobe Method, Strobe Delay, Strobe Duration.

Block Diagram: Connecting External Receivers to the General Outputs

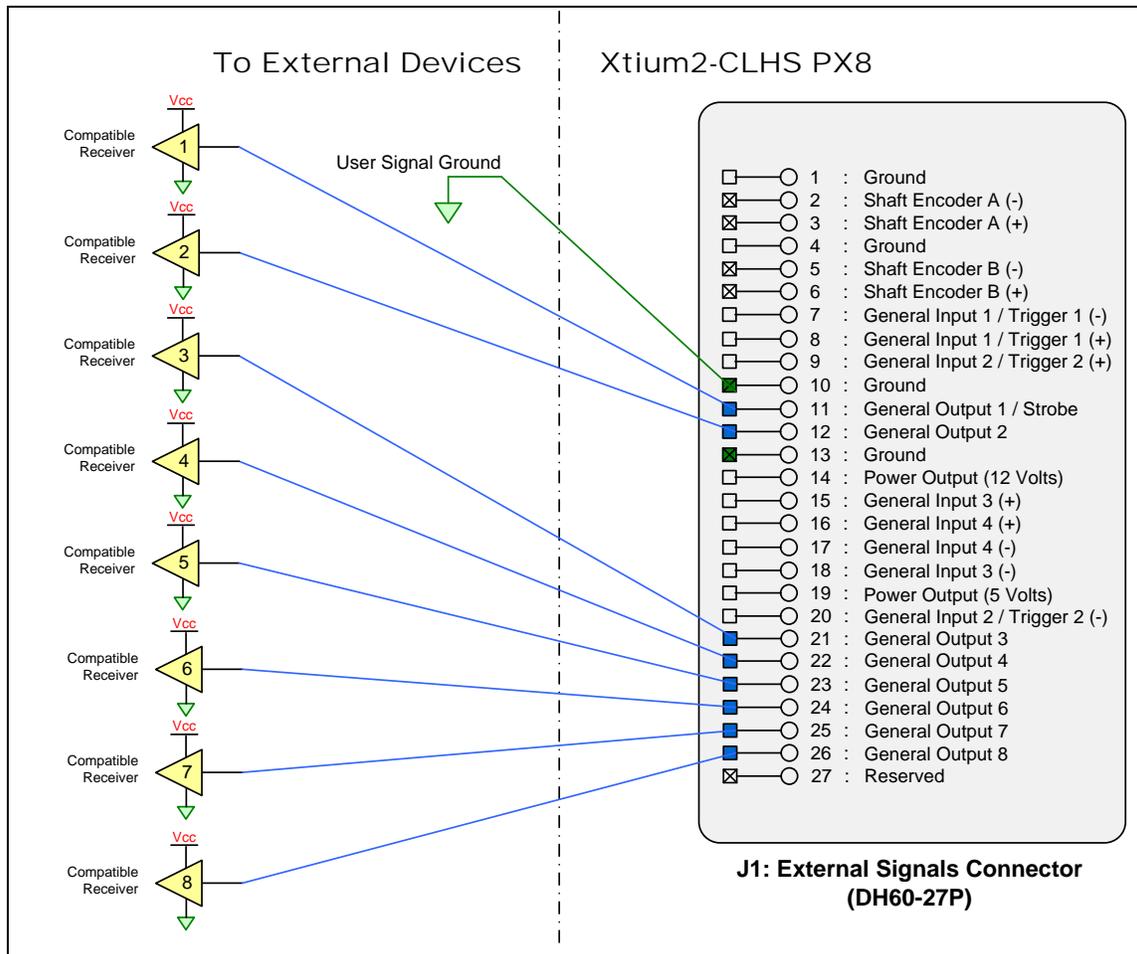


Figure 30: Output Signals Connection Diagram

External Receiver Electrical Requirements

- Xtium2 General Outputs are standard TTL logic levels.
- External receiver circuits must be compatible to TTL signals.

Xtium2 PX8 Output Level	Description	MIN	MAX
TTL	Output Voltage High (V_H)	2.0 V	–
	Output Voltage Low (V_L)	–	0.8 V

Note 3: RS-422 Shaft Encoder Input Specifications

Dual Quadrature Shaft Encoder Inputs (phase A and phase B) connect to differential signals (RS-422) or single ended signals. The figure below shows the simplified representation of these inputs.

	<p>WARNING: When connecting shaft encoders to Xtium2-CLHS PX8, make sure to connect a common ground between the shaft encoder and the frame grabber. See RED boxed connections in the diagram below. Failure to follow the described instructions could damage the board resulting in the shaft encoder functionality not working properly.</p>
<p>Ensure that these grounding measures are followed when migrating from boards with opto-coupled shaft encoders (such as the Xcelera).</p>	

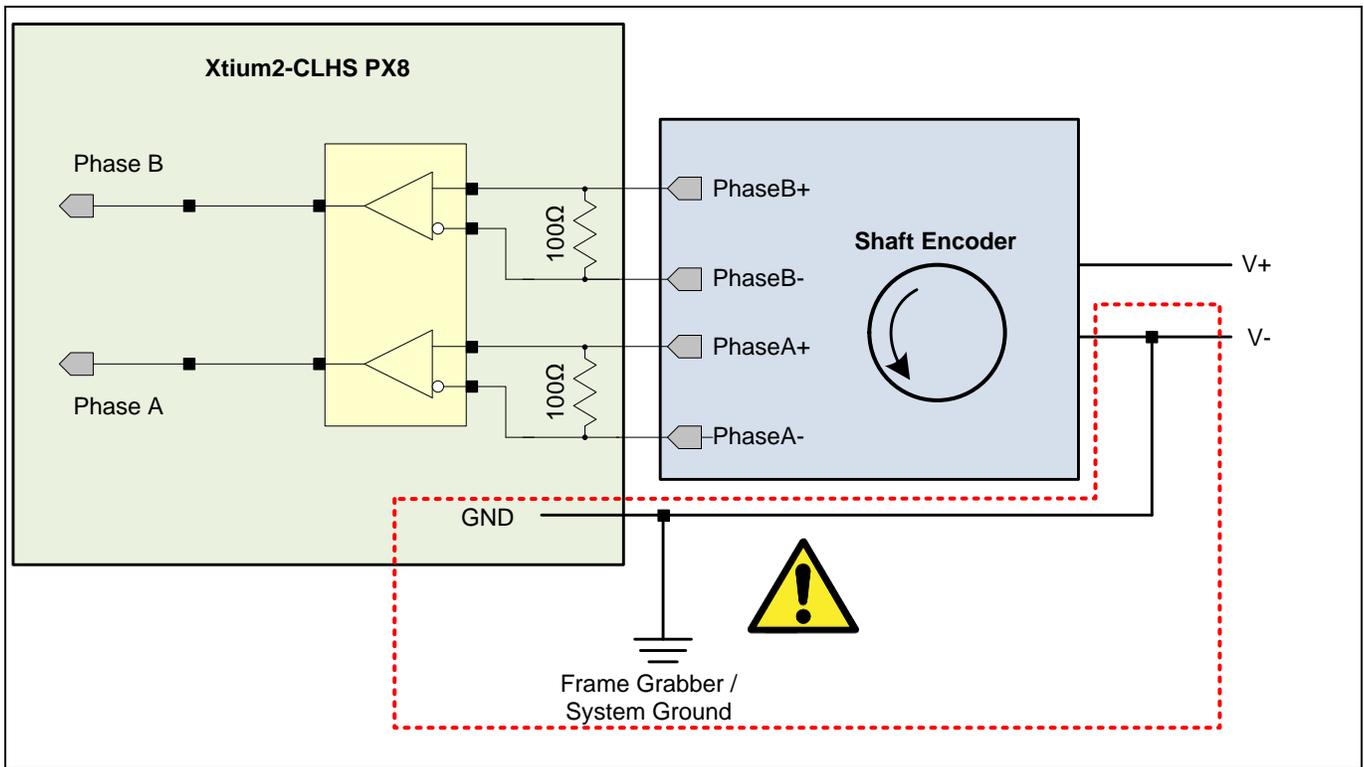


Figure 31: RS-422 Shaft Encoder Input Electrical Diagram

- The shaft encoder ground and the Xtium2-CLHS PX8 computer system ground must be connected together.
- RS-422 differential line receiver used is am26lv32.
- Input signals must meet the following
 - Maximum differential input voltage is +/- 7V.
 - Minimum differential voltage level is +/- 200mV.
- Both inputs have a 100-ohm differential resistor.
- Maximum input signal frequency is 10 MHz.
- The Xtium2-CLHS provides ESD filtering on-board.
- See the Line Trigger Source Selection for Line Scan Applications section for more information.

- Refer to Sopera parameters:
 - CORACQ_PRM_SHAFT_ENCODER_ENABLE CORACQ_PRM_SHAFT_ENCODER_DROP
or refer to
CORACQ_PRM_EXT_LINE_TRIGGER_ENABLE
CORACQ_PRM_EXT_LINE_TRIGGER_DETECTION
CORACQ_PRM_EXT_LINE_TRIGGER_LEVEL (fixed at RS-422)
CORACQ_PRM_EXT_LINE_TRIGGER_SOURCE
- See also *.cvi file entries: Shaft Encoder Enable, Shaft Encoder Pulse Drop, or see External Line Trigger Enable, External Line Trigger Detection, External Line Trigger Level, External Line Trigger Source.
- For TTL single ended signals, connect a bias voltage to the RS-422 (-) input to ensure correct detection of the logic state of the signal connected to the RS-422 (+) input. See the following section for connection methods.

Example: Connecting to the RS-422 Shaft Encoder Block Diagram

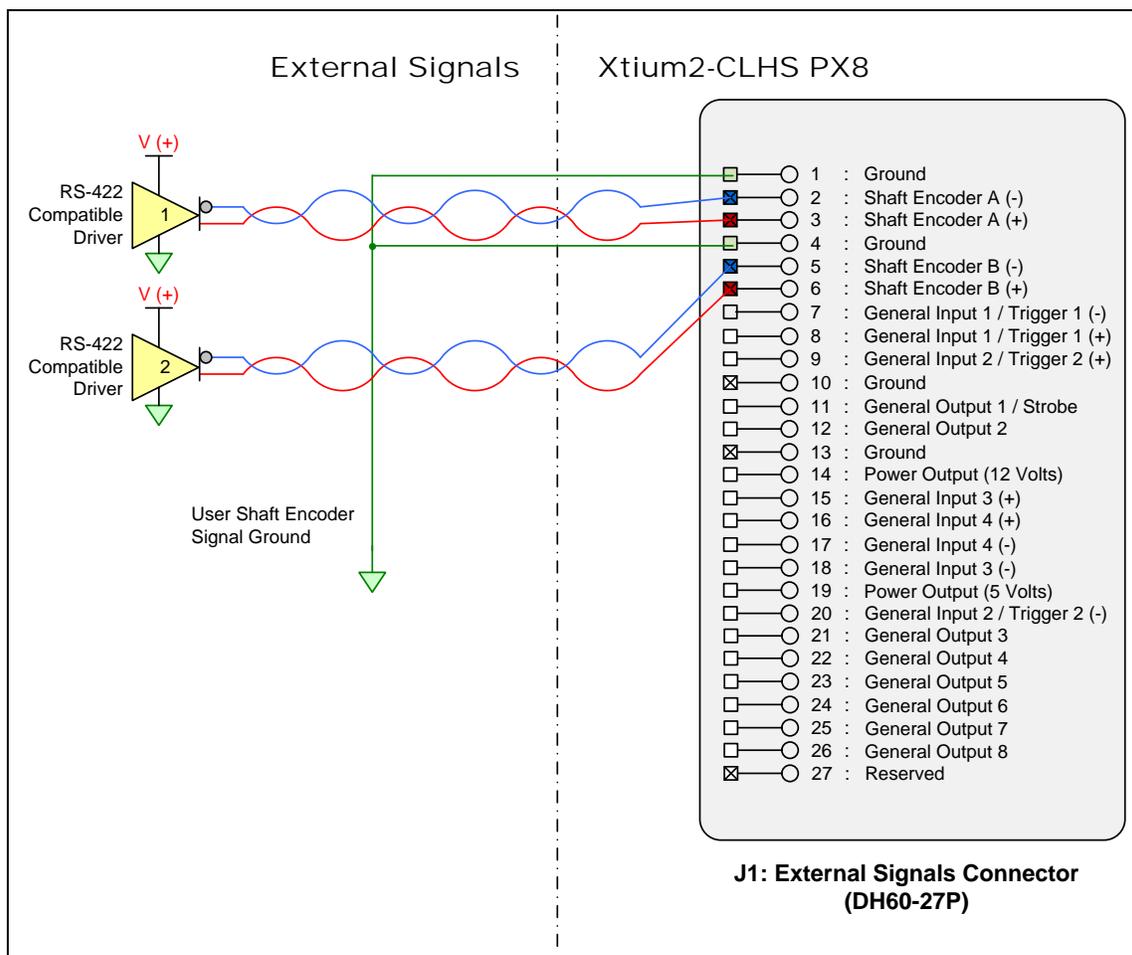


Figure 32: External RS-422 Signals Connection Diagram

Note 3.2: Interfacing to a TTL (also called Push-Pull) Output

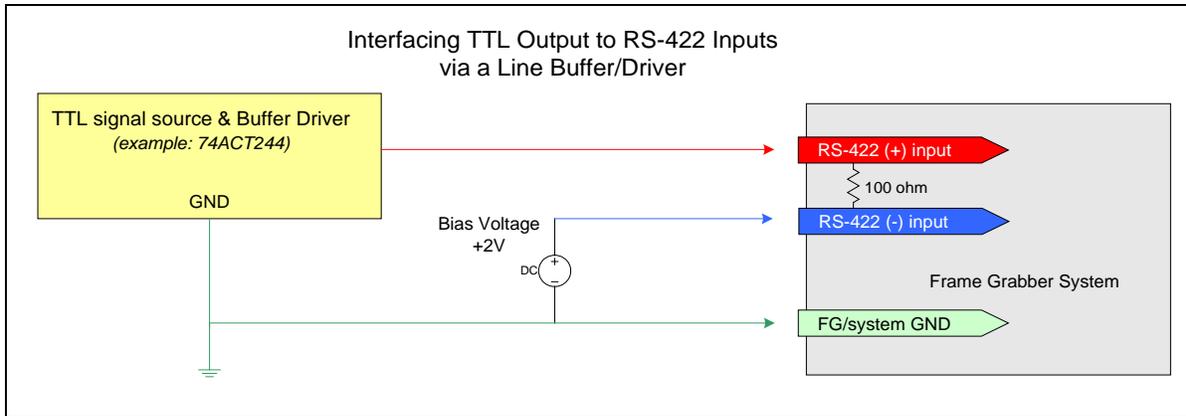


Figure 33: Interfacing TTL to RS-422 Shaft Encoder Inputs

- The graphic shows a single-ended driver signal interfaced to the RS-422 input.
- RS-422 (-) input is biased to a DC voltage of +2 volts.
- This guarantees that the TTL signal connected to the RS-422 (+) input will be detected as a logic high or low relative to the (-) input.
- The TTL shaft encoder ground, the bias voltage ground, and the Xtium2-CLHS PX8 computer system ground must be connected together.
- DC voltage for the RS-422 (-) input can be generated by a resistor voltage divider.
- Use a single battery cell if this is more suitable to your system.

Note 3.3: Interfacing to a Line Driver (also called Open Emitter) Output

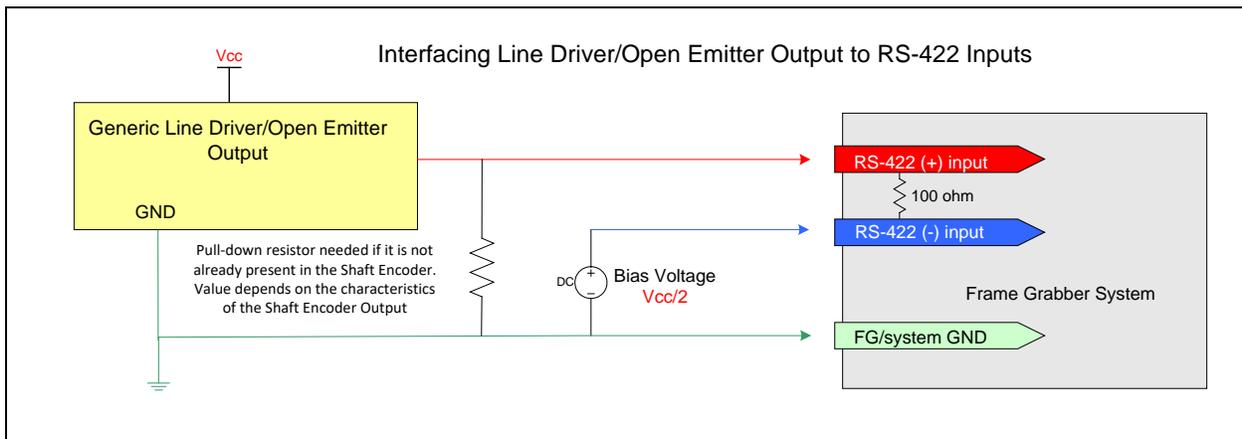


Figure 34: Interfacing to a Line Driver Output

Note 3.4: Interfacing to an Open Collector Output

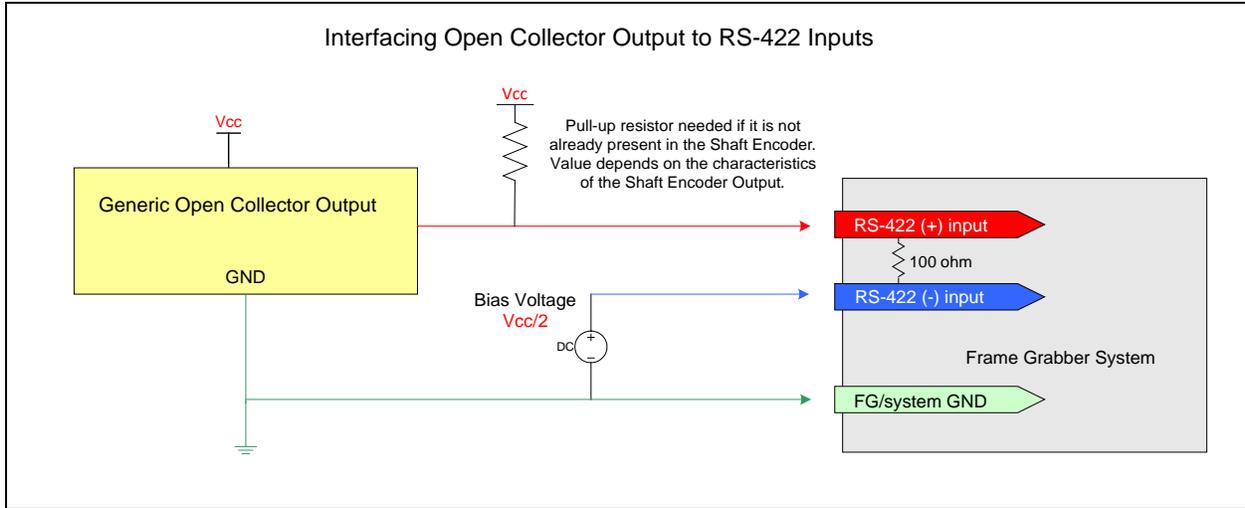


Figure 35: Interfacing to an Open Collector Output

J5: Multi-Board Sync / Bi-directional General I/Os

There are 8 bi-directional General I/Os that can be interconnected between multiple boards. These bi-directional I/Os can be read/written by Sapera application. Bi-directional General I/Os no.1 and no.2 also can also act as the multi-board sync I/Os.

The multi-board sync feature permits interconnecting multiple Xtium2 boards to synchronize acquisitions to one or two triggers or events. The trigger source origin can be either an external signal or a software control signal. The board sending the trigger(s) is the "Sync Master" board, while the one or more boards receiving the control signal(s) are "Sync Slaves".

Setup of the boards is done either by setting parameters via a Sapera application or by using CamExpert to configure two camera files (.ccf). For testing purposes, two instances of CamExpert (one for each board) can be run on the system where the frame grabbers are installed.

Hardware Preparation

- Interconnect two, three, or four Xtium2 boards via their J5 connector using the OR-YXCC-BSYNC20 cable (for 2 boards) or the OR-YXCC-BSYNC40 cable (see [Board Sync Cable Assembly OR-YXCC-BSYNC40](#) Board Sync Cable Assembly OR-YXCC-BSYNC40 for 3 or 4 boards).



Warning: Multi-Board Sync / Bi-directional General I/Os are only for use with Teledyne DALSA frame grabbers within the same PC, otherwise electrical damage to boards can occur.

Configuration via Sapera Application Programming

- **Sync Master Board** Software Setup: Choose one Xtium2 as “Sync Master”. The Sapera parameter CORACQ_PRM_BOARD_SYNC_OUTPUT1_SOURCE and/or CORACQ_PRM_BOARD_SYNC_OUTPUT2_SOURCE select the signal(s) to send to the “Sync Slave” boards.
- Other sync master board parameters are set as for any external trigger application, such as External Trigger enable, detection and level. See Sapera documentation for more details.
- **Sync Slave Board** Software Setup: The Sapera parameter CORACQ_PRM_EXT_TRIGGER_SOURCE and/or CORACQ_PRM_EXT_LINE_TRIGGER_SOURCE are set to Board Sync #1 or #2.

Configuration via Sapera CamExpert

- Start the first instance of CamExpert and select one installed **Xtium2 board** to be the **sync master**. As shown in the following image, this board is configured to use an external trigger on input #1.

Category	Parameter	Value
Basic Timing	External Trigger	Enable
Advanced Control	External Trigger Detection	Rising Edge
External Trigger	External Trigger Level	TTL
Image Buffer and ROI	External Trigger Source	External Trigger #1
	External Trigger Minimum Duration (in us)	0
	Frame Count per External Trigger	1
	External Trigger Delay	0
	External Trigger Delay Time Base	nanoseconds
	External Trigger Ignore Delay	0

- The **Sync Master Xtium2 board** is also configured to output the external trigger on board sync #1, as shown in the following image.

Category	Parameter	Value
Basic Timing	Internal Frame Trigger	Disabled
Advanced Control	Internal Frame Trigger Frequency (in Hz)	30
External Trigger	Camera Control method selected	Camera Trigger
Image Buffer and ROI	Time Integration Method Setting	None
	Camera Trigger Method Setting	Method 3
	Camera Frames Per Trigger	1
	Camera Control During Readout	Invalid
	Strobe Method Setting	None
	Time Stamp Base	Microseconds
	Board Sync Output 1 Source	External Frame Trigger
	Board Sync Output 2 Source	Disabled

- The **Sync Slave Xtium2 board** is configured to receive its trigger on the board sync signal. As an example the following image shows the Xtium2 board configured for an external sync on board sync #2.

Parameters ×		
Category	Parameter	Value
Basic Timing	External Trigger	Enable
Advanced Control	External Trigger Detection	Rising Edge
External Trigger	External Trigger Level	TTL
Image Buffer and ROI	External Trigger Source	Board Sync #2
	External Trigger Minimum Duration (in ...	0
	Frame Count per External Trigger	1
	External Trigger Delay	0
	External Trigger Delay Time Base	Nanoseconds
	External Trigger Ignore Delay	0

- **Test Setup:** Start the acquisition on all slave boards. The acquisition process is now waiting for the control signal from the master board. Trigger master board acquisition and the acquisition start signal is sent to each slave board.

Cables & Accessories

The following cables and accessories are available for purchase via third party vendors or Teledyne DALSA. Contact sales for information.

Camera Link HS Cables Overview and Resources

In general, a CX4 compliant cable assembly is acceptable for use as a CLHS interface cable with the exception that it must have a thumbscrew type junction shell.



Note: This cable assembly is primarily intended as a point-to-point interface of up to 15 meters at bit rates of 5Gb/s and less, and not more than 3M at bit rates of 10Gb/s.

A manufactured CX4 cable shall use the SFF-8470 multi-sourced connector as specified by the published standard "SFF-8470 Specification for Shielded High Speed Serial Multilane Copper Connector (Rev 3.3 April 3, 2006 or later)".

Cables are also available as CX4 Active optical interconnects allowing much longer distances between camera and frame grabber.

Visit our web site for additional information on the CLHS interface:

<https://www.teledynedalsa.com/en/learn/knowledge-center/clhs/>

For additional information on cables and their specifications, visit the following web sites and search for "Camera Link HS" cables:

Components Express

<http://www.componentsexpress.com/>

Alysium-Tech

<https://www.alysium.com/>

DH40-27S Cable to Blunt End (OR-YXCC-27BE2M1, Rev B1)

Cable assembly consists of a 2000 mm (~6 ft.) blunt end cable to mate to Xtium2 external connector J1.



Note: The applicable wiring color code table is included with the printed Product Notice shipped with the cable package — no other wiring table should be used.

Important: Cable part number OR-YXCC-27BE2M0 rev.3 is obsolete and should not be used with any Xtium2 series boards.

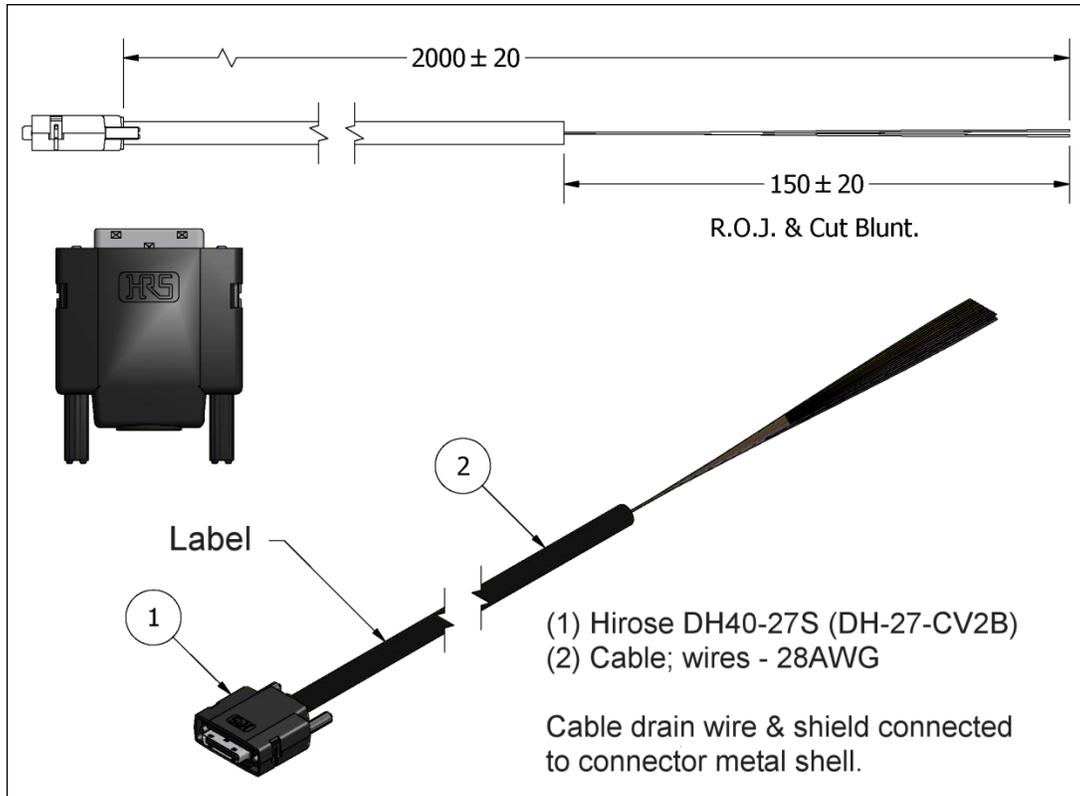


Figure 36: DH60-27P Cable No. OR-YXCC-27BE2M1 Detail

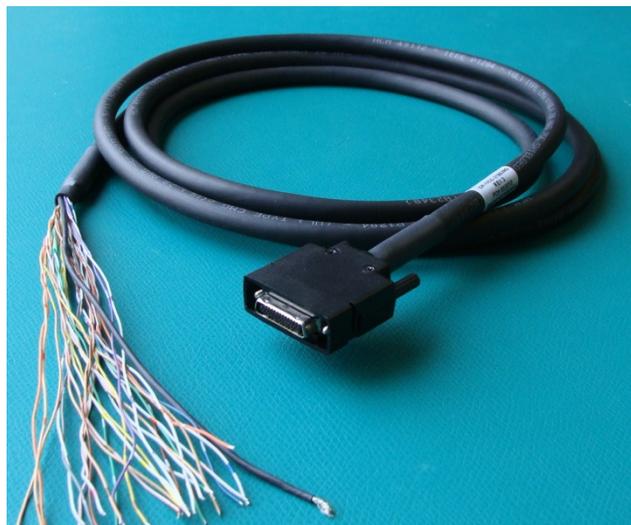
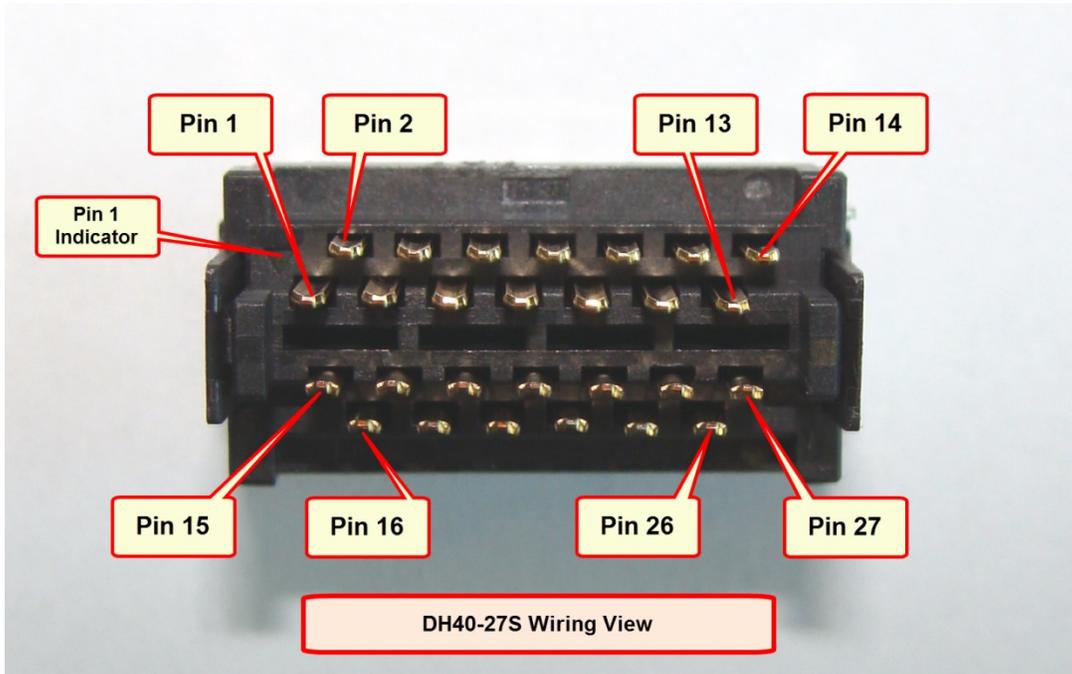


Figure 37: Photo of cable OR-YXCC-27BE2M1

DH40-27S Connector Kit for Custom Wiring

Teledyne DALSA makes available a kit comprised of the DH40-27S connector plus a screw lock housing package, for clients interested in assembling their own custom I/O cable. Order part number "OR-YXCC-H270000", (package as shown below).



Cable assemblies for I/O connector J4

Flat ribbon cables for connecting to J4 can be purchased from Teledyne DALSA or from third party suppliers, as described below.

Teledyne DALSA I/O Cable (part #OR-YXCC-TIOF120)

Contact Teledyne DALSA Sales to order the 12 inch (~30cm) I/O cable with connectors on both ends, as shown in the following picture.

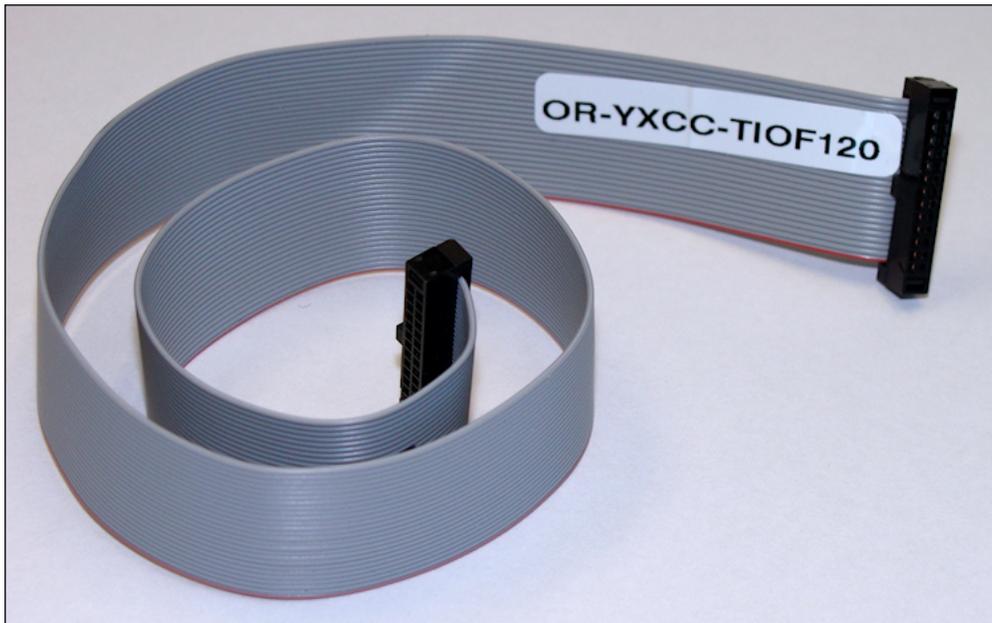


Figure 38: I/O Cable #OR-YXCC-TIOF120

Third Party I/O Cables for J4

Suggested third party cables are available from SAMTEC. Below are two examples:

- Connector to connector (FFSD-13-D-xx.xx-01-N)
- Connector to blunt end (FFSD-13-S-xx.xx-01-N)
- Note: xx.xx denotes length, where 06.00 is a 6 inch (~15 cm) length cable
- URL: http://cloud.samtec.com/catalog_english/FFSD.PDF

Board Sync Cable Assembly OR-YXCC-BSYNC40

This cable connects 3 to 4 Xtium2 boards for the board sync function as described in section [J5: Multi-Board Sync / Bi-directional General I/Os](#). For a shorter 2 board cable, order cable assembly OR-YXCC-BSYNC20.

For a third part source of cables, see http://cloud.samtec.com/catalog_english/FFSD.PDF.

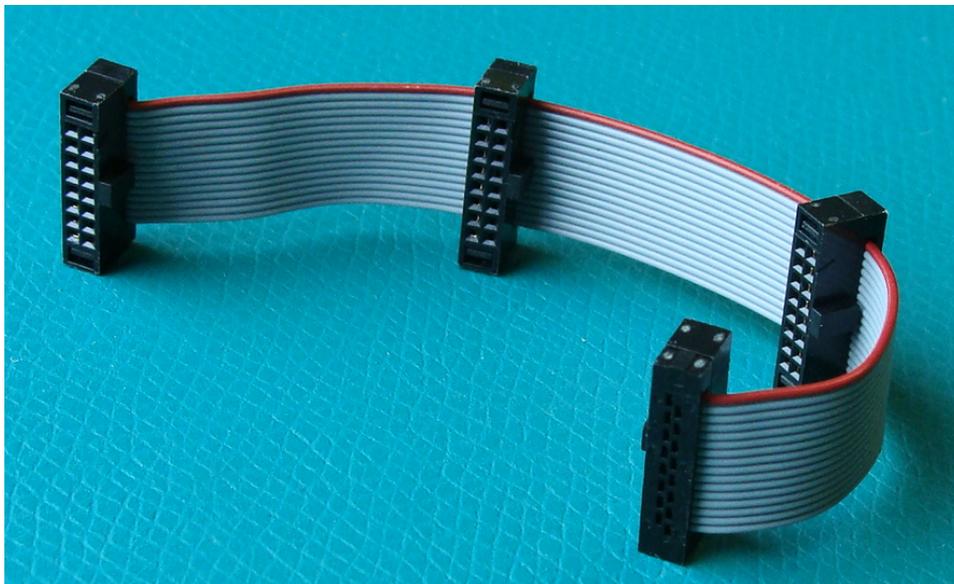


Figure 39: Photo of cable OR-YXCC-BSYNC40

Camera Link HS Interface



Camera Link HS Overview



Note: The following text is extracted from the AIA document "*Specifications of the Camera Link HS Interface Standard for Digital Cameras and Frame Grabbers*" version 1.0 RC5, ©2012 AIA. Refer to their site www.visiononline.org for additional information.

Camera Link HS (CLHS) is a global standard defining the communications between a camera and a frame grabber. The CLHS standard offers high performance control functions and scalable data transfer bandwidths between the camera and frame grabber. The data transmission technology employed in CLHS is available from multiple suppliers and has roadmaps to higher bit rates driven by the telecom market. The use of widely used technology guarantees a low component cost and long term supply for machine vision customers.

The packet based protocol used in CLHS is machine vision specific, thus delivering the high image reliability needed in modern machine vision systems. CLHS Messages are defined independent of the physical layer, allowing CLHS to adopt new physical layers as they become available.

Currently CLHS employs simple 8b/10b technology in the M-Protocol and the XAUI-64/66 encoding for the X-Protocol. CLHS supports real time triggers (Pulse) and General Purpose Input/Output (GPIO), using a priority methodology that results in CLHS having the lowest latency and jitter of any packet based protocol. Designed with forward error correction for real time messages, plus CRC and hardware based resend mechanisms for video and command packets, ensure data reliability.

Rights and Trademarks

The AIA, as sponsor of the Camera Link HS committee, owns the U.S. trademark registration for the Camera Link HS logo as a certification mark for the mutual benefit of the industry. Usage of the Camera Link HS logo with any product(s) implies compliancy with the Camera Link HS standard.

Appendix A: Silent Installation

Both Sapera LT and the Xtium2-CLHS PX8 driver installations share the same installer technology. When the installations of Teledyne DALSA products are embedded within a third party's product installation, the mode can either have user interaction or be completely silent. The following installation mode descriptions apply to both Sapera and the hardware driver.



Note: You must reboot after the installation of Sapera LT. However, to streamline the installation process, Sapera LT can be installed without rebooting before installing the board hardware device drivers. The installations then complete with a single final system reboot.

Perform Teledyne DALSA embedded installations in either of these two ways:

- **Normal Mode**
The default mode is interactive. This is identical to running the setup.exe program manually from Windows (either run from Windows Explorer or the Windows command line).
- **Silent Mode**
This mode requires no user interaction. A preconfigured "response" file provides the user input. The installer displays nothing.

Silent Mode Installation

A Silent Mode installation is recommended when integrating Teledyne DALSA products into your software installation. The silent installation mode allows the device driver installation to proceed without the need for mouse clicks or other input from a user.

Preparing a Silent Mode Installation requires two steps:

- Prepare the response file, which emulates a user.
- Invoke the device driver installer with command options to use the prepared response file.

Creating a Response File

Create the installer response file by performing a device driver installation with a command line switch "-r". The response file is automatically named setup.iss and is saved in the \windows folder. If a specific directory is desired, the switch -f1 is used.

As an example, to save a response file in the same directory as the installation executable of the Xtium2-CLHS PX8, the command line would be:

```
Xtium2-CLHS_PX8_1.00.00.0000 -r -f1" .\setup.iss"
```

Running a Silent Mode Installation

A device driver silent installation, whether done alone or within a larger software installation requires the device driver executable and the generated response file **setup.iss**.

Execute the device driver installer with the following command line:

```
Xtium2-CLHS_PX8_1.00.00.0000 -s -f1" .\setup.iss"
```

Where the **-s** switch specifies the silent mode and the **-f1** switch specifies the location of the response file. In this example, the switch **-f1" .\setup.iss"** specifies that the **setup.iss** file be in the same folder as the device driver installer.



Note: On Windows 7, 8, and 10, the Windows Security dialog box will appear unless one has already notified Windows to 'Always trust software from "Teledyne DALSA Inc."' during a previous installation of a driver.

Silent Mode Uninstall

Similar to a silent installation, a response file must be prepared first as follows.

Creating a Response File

The installer response file is created by performing a device driver un-installation with a command line switch **"-r"**. The response file is automatically named **setup_uninstall.iss** which is saved in the **\windows** folder. If a specific directory is desired, the switch **"-f1"** is used.

As an example, to save a response file in the same directory as the installation executable of the Xtium2-CLHS PX8, the command line would be:

```
Xtium2-CLHS_PX8_1.00.00.0000 -r -f1" .\setup_uninstall.iss"
```

Running a Silent Mode Uninstall

Similar to the device driver silent mode installation, the un-installation requires the device driver executable and the generated response file **setup.iss**.

Execute the device driver installer with the following command line:

```
Xtium2-CLHS_PX8_1.00.00.0000 -s -f1" .\setup_uninstall.iss"
```

Where the **-s** switch specifies the silent mode and the **-f1** switch specifies the location of the response file. In this example, the switch **-f1" .\setup_uninstall.iss"** specifies that the **setup_uninstall.iss** file be in the same folder as the device driver installer.

Silent Mode Installation Return Code

A silent mode installation creates a file "corinstall.ini" in the Windows directory. A section called [SetupResult] contains the 'status' of the installation. A value of 1 indicates that the installation has started and a value of 2 indicates that the installation has terminated.

A silent mode installation also creates a log file "setup.log" which by default is created in the same directory and with the same name (except for the extension) as the response file. The /f2 option enables you to specify an alternative log file location and file name, as in

Setup.exe /s /f2"C:\Setup.log".

The "setup.log" file contains three sections. The first section, [InstallShield Silent], identifies the version of InstallShield used in the silent installation. It also identifies the file as a log file. The second section, [Application], identifies the installed application name, version, and the company name. The third section, [ResponseResult], contains the 'ResultCode' indicating whether the silent installation succeeded. A value of 0 means the installation was successful.

Installation Setup with CorAppLauncher.exe

The installation setup can be run with the CorAppLauncher.exe tool provided with the driver.

- Install the board driver and get CorAppLauncher.exe from the \bin directory of the installation.
- When running the installation, CorAppLauncher.exe will return only when the installation is finished.
- When run from within a batch file, obtain the installation exit code from the ERRORLEVEL value.
- The arguments to CorAppLauncher.exe are:
 - l: Launch application
 - f: Application to launch. Specify a fully qualified path.

As an example:

- CorAppLauncher -l -f"c:\driver_install\Xtium2-CLHS_PX8_1.00.00.0000.exe"
- IF %ERRORLEVEL% NEQ 0 goto launch error

Note: There is a 32-bit and 64-bit version of CorAppLauncher.exe. When installing the driver, only the version related to the OS is installed. However, the 32-bit version is usable on either 32-bit or 64-bit Windows.

Custom Driver Installation using install.ini

Customize the driver installation by parameters defined in the file "install.ini".

By using this file, the user can:

- Select the user default configuration.
- Select different configurations for systems with multiple boards.
- Assign a standard Serial COM port to board.

Creating the install.ini File

- Install the driver in the target computer. All Xtium2-CLHS PX8 boards required in the system must be installed.
- Configure each board's acquisition firmware using the Teledyne DALSA Device Manager tool (see Device Manager – Board Viewer).
- When each board setup is complete, using the Teledyne DALSA Device Manager tool, click on the **Save Config File** button. This will create the "install.ini" file.

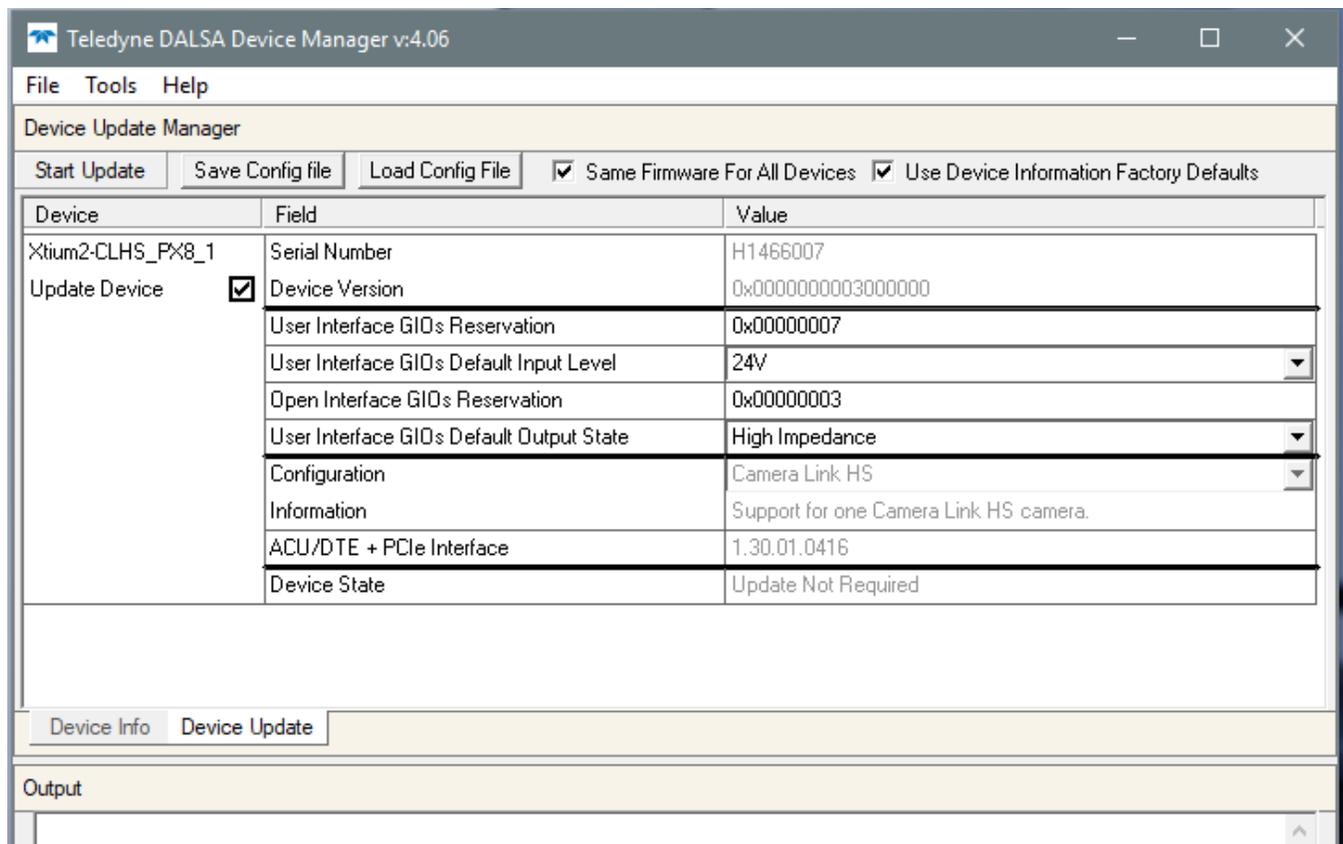


Figure 40: Create an install.ini File

Run the Installation using install.ini

Copy the install.ini file into the same directory as the setup installation file. Run the setup installation as normal. The installation will automatically check for an install.ini file and if found, use the configuration defined in it.

Appendix B: Troubleshooting Problems

Overview

The Xtium2-CLHS PX8 (and the Xtium2 family of products) is tested by Teledyne DALSA in a variety of computers. Although unlikely, installation problems may occur due to the constant changing nature of computer equipment and operating systems. This section describes what the user can verify to determine the problem or the checks to make before contacting Teledyne DALSA Technical Support.

If you require help and need to contact Teledyne DALSA Technical Support, make detailed notes on your installation and/or test results for our technical support to review. See Technical Support for contact information.

Problem Type Summary

Xtium2-CLHS PX8 problems are either installation types where the board hardware is not recognized on the PCIe bus (that is, trained), or function errors due to camera connections or bandwidth issues. The following links jump to various topics in this troubleshooting section.

First Step: Check the Status LED

Status LED D1 should be **BLUE** or flashing **BLUE** just after power up. If it remains flashing **RED**, the board firmware did not load correctly. Once the Windows driver is started, LED D1 should be **GREEN** or flashing **GREEN**. If LED D1 remains **BLUE** or flashing **BLUE**, the board is still running from the safe mode load. This could indicate that the normal load in the flash is corrupted or not present.

CLHS Link status is indicated by LED D3 – above the camera connector. The status colors displayed follow industry specifications for Camera Link HS.

The complete status LED descriptions are available in the technical reference section, (see [Status LEDs Functional Descriptions](#)).

Possible Installation Problems

- **Hardware PCI bus conflict:** When a new installation produces PCI bus error messages or the board driver does not install, it is important to verify that there are no conflicts with other PCI or system devices already installed. Use the Teledyne DALSA PCI Diagnostic tool as described in [Checking for PCI Bus Conflicts](#). Also verify the installation via the Windows Device Manager.
- **BSOD (blue screen) following a board reset:** After programming the board with different firmware, the computer displays the BSOD when the board is reset (see BSOD (blue screen) Following a Board Reset).
- **Verify Sapera and Board drivers:** If there are errors when running applications, confirm that all Sapera and board drivers are running. See Sapera and Hardware Windows Drivers for details. In addition, Teledyne DALSA technical support will ask for the log file of messages by Teledyne DALSA drivers. Follow the instructions describe in Teledyne DALSA Log Viewer.
- **Firmware update error:** There was an error during the Xtium2-CLHS PX8 firmware update procedure. The user can usually easily correct this. Follow the instructions Recovering from a Firmware Update Error.

- Installation went well but the board does not work or stopped working. Review these steps described in Symptoms: CamExpert Detects no Boards.
- **Using Windows 8/10 Fast Boot option:** When adding, removing, or moving boards while the PC is shutdown with the Windows Fast Boot option activated, it is possible that the boards do not get mapped properly on the next reboot of the computer. The driver will detect such a situation and the Device Manager launched at startup will display a message indicating that a reboot is required.

Possible Functional Problems

- **Driver Information:** Use the Teledyne DALSA device manager program to view information about the installed Xtium2-CLHS PX8 board and driver. See Driver Information via the Device Manager Program.
- **On-Board Image Memory Requirements:** The Xtium2-CLHS PX8 on-board memory can provide two frame buffers large enough for most imaging situations. See On-board Image Memory Requirements for Acquisitions for details on the on board memory and possible limitations.

Sometimes the problem symptoms are not the result of an installation issue but due to other system issues. Review the sections described below for solutions to various Xtium2-CLHS PX8 functional problems.

- Symptoms: Xtium2-CLHS PX8 Does Not Grab
- Symptoms: Card grabs black
- Symptoms: Card acquisition bandwidth is less than expected

Troubleshooting Procedures

The following sections provide information and solutions to possible Xtium2-CLHS PX8 installation and functional problems. The previous section of this manual summarizes these topics.

Diagnostic Tool Overview

The Xtium2-CLHS PX8 Board Diagnostic Tool provides a quick method to see board status and health. It additionally provides live monitoring of FPGA temperature and voltages, which may help in identifying problems. A shortcut to this tool is in the Windows Start menu within the “Teledyne DALSA/Xtium2-CLHS PX8” folder. Do not have any other application running that connects to the Xtium2 such as CamExpert, else the diagnostic window will indicate an error for the PCIe Bandwidth, as shown in the screen capture below.

	Bus Bit Transfer Rate	Gen 3		
	Bus Payload Size (bytes)	256		
	Bus Request Size (bytes)	512		
PCIe Bandwidth (MB/s)	Achieved Bandwidth	Resource in use	Resource in use	Resource in use
	Maximum Theoretical	Resource in use		
FPGA Temperature (°C)	Measured	70.256	70.256	70.256

Figure 41: Diagnostic Tool “Resource in use”

The following section describes the information available from the Xtium2 board via the diagnostic program.

Diagnostic Tool Main Window

The main window provides a comprehensive view of the installed Xtium2 board. Toolbar buttons execute the board self-test function and open a FPGA live status window.

Important parameters include the PCI Express bus transfer supported by the host computer and the internal Xtium2 FPGA temperature. The bus transfer defines the maximum data rate possible in the computer, while an excessive FPGA temperature may explain erratic acquisitions due to poor computer ventilation.

The screenshot shows the Diagnostic Tool interface with several callouts pointing to specific features and data tables:

- Generate Report**: Points to the 'TEST' button in the toolbar.
- Execute Self Test**: Points to the 'TEST' button in the toolbar.
- Live FPGA Monitors**: Points to the 'Live FPGA Monitors' button in the toolbar.
- Save Report**: Points to the 'Save Report' button in the toolbar.
- Channel Signal Integrity**: Points to the 'Channel Signal Integrity' button in the toolbar.
- Computer Bus & Slot**: Points to the 'Computer Bus & Slot' button in the toolbar.
- FPGA Monitors**: Points to the 'FPGA Monitors' button in the toolbar.
- Sapera & System Monitors**: Points to the 'Sapera & System Monitors' button in the toolbar.
- Right Click to Reset Lane Stats**: Points to the right-click context menu option for the Lane Stats table.

The main window displays the following data tables:

Field/Value	Value	Min	Max
Driver Version	1.10.01.0103		
Serial Number	H1108006		
PCI Info			
Bus #	4		
Slot #	0		
Function #	0		
Bus Total Lanes	4		
Bus Bit Transfer Rate	Gen 3		
Bus Payload Size (bytes)	256		
Bus Request Size (bytes)	512		
PCIe Bandwidth (MB/s)			
Achieved Bandwidth	3266	3127	3339
Maximum Theoretical	3500		
FPGA Temperature (°C)			
Measured	92.438	92.193	92.438
Operating Range		0.000	100.000
Voltage Aux (V)			
Measured	1.763	1.763	1.763
Operating Range		1.746	1.854
Voltage Int (V)			
Measured	0.954	0.953	0.954
Operating Range		0.922	0.979

	CRC Error	Video MSG	Packet Buffer Overflow	Resend Flag	64b/66b Error	64b/66b Corrected
Lane 1	0	554083135	0	0	0	0
Lane 2	0	554083138	0	0	0	0
Lane 3	0	554083140	0	0	0	0
Lane 4	0	554083143	0	0	0	0
Lane 5	0	554083145	0	0	0	0
Lane 6	0	554083148	0	0	0	1
Lane 7	0	554083150	0	0	0	0

	Total (MB/KB)	Free (MB/KB)	Handles	Process	Thread
Physical Memory	16275/ 16666428	10536/ 10789408			
Page File	18707/ 19156796	12700/ 13005348			
Virtual Memory	134217727/ 137438953344	134217489/ 137438708996			
Total			79860	181	2794

	Free (KB/B)	Used (KB/B)	Free Blocks	Largest Free Block (KB/B)	Used Blocks	Largest Used Block (KB/B)
Message Memory	3071/ 3145724	0/ 4	2	2163/2215932	1	0/ 4
Buffer Memory	3063/ 3136944	8/ 8784	1	3063/3136944	12	2/ 2140

Figure 42: Diagnostic Tool User Interface

Diagnostic Tool Self-Test Window

Click the Start button to initiate the board memory self-test sequence. A healthy board will pass all memory test patterns.

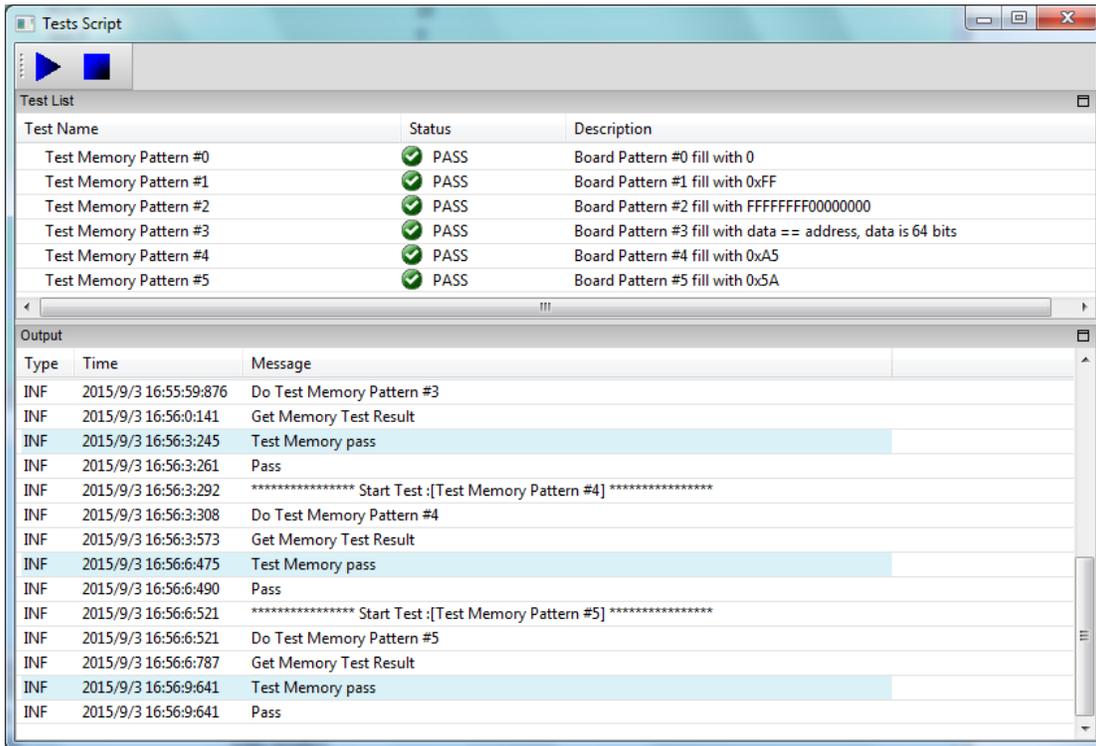


Figure 43: Diagnostic Tool Self-Test Window

Camera Input Eye Diagram Monitor

Eye Diagrams allow the user to evaluate signal integrity between camera data lanes or between different cable sets. This tool does not provide specific measurements but will help to identify signal issues associated with bad cables or overly long cables.

The screen capture below shows a camera with seven data lanes, where each digital signal is repetitively sampled and overlaid over itself, showing relative low-high transitions of the differential signal. The blue center area (eye surface) seems similar between each lane, typical for a good cable set.

The closure (collapse or horizontal shortening) of the eye surface would indicate problems such as poor signal to noise, high cable capacitance, multipath interference, among many possible digital transmission faults.

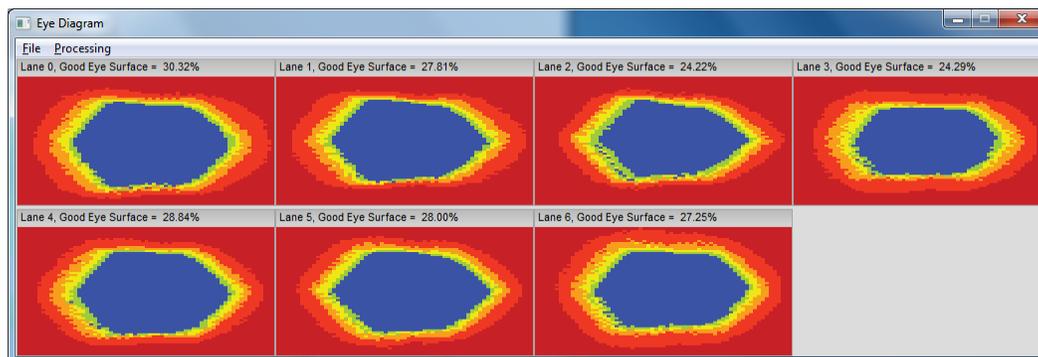


Figure 44: Diagnostic Tool Eye Diagram

Diagnostic Tool Live Monitoring Window

The three FPGA parameters can be monitored in real time. Choosing a parameter puts that graph at the top where the user can select the time unit and time range. Clicking the Output button will open a window displaying any error messages associated with that parameter.



Checking for PCI Bus Conflicts

One of the first items to check when there is a problem with any PCI board is to examine the system PCI configuration and ensure that there are no conflicts with other PCI or system devices. The *PCI Diagnostic* program (**cpctdiag.exe**) allows examination of the PCI configuration registers and can save this information to a text file. Run the program via the Windows Start Menu shortcut **Start • Programs • Teledyne DALSA • Sopera LT • Tools • PCI Diagnostics**.

As shown in the following screen image, use the first drop menu to select the PCI device to examine. Select the device from Teledyne DALSA. Note the bus and slot number of the installed board (this will be unique for each system unless systems are setup identically). Click on the **Diagnostic** button to view an analysis of the system PCI configuration space.

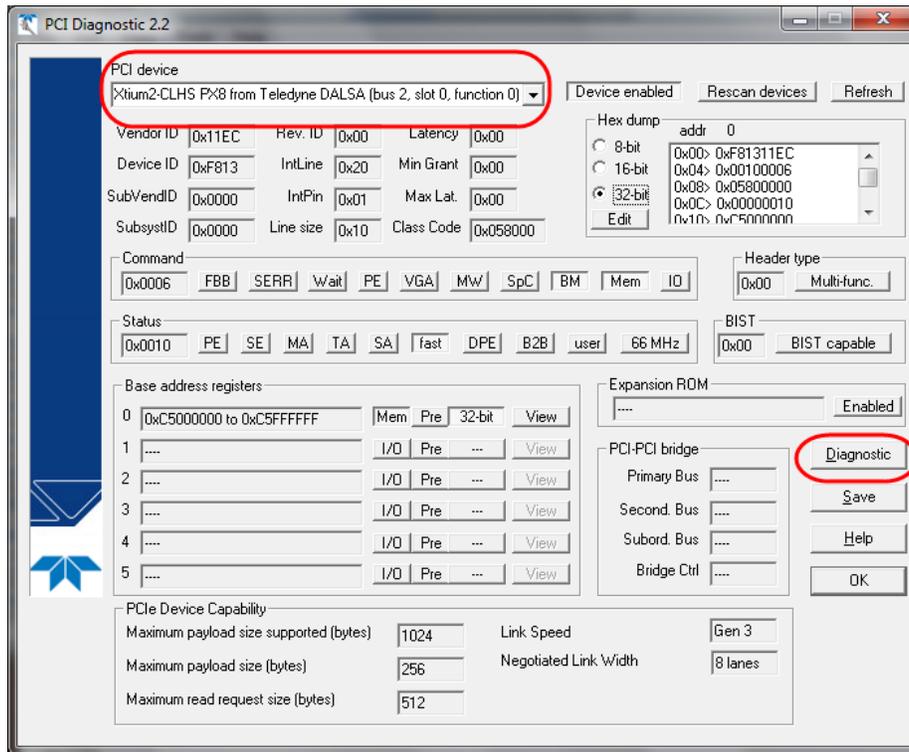


Figure 45: PCI Diagnostic Program

Clicking on the **Diagnostic** button opens a new window with the diagnostic report. From the PCI Bus Number drop menu, select the bus number that the Xtium2-CLHS PX8 is installed in—in this example the slot is bus 2.

The window now shows the I/O and memory ranges used by each device on the selected PCI bus. The information display box will detail any PCI conflicts. If there is a problem, click on the **Save** button. A file named '**pcdiag.txt**' is created (in the Sapera\bin directory) with a dump of the PCI configuration registers. Email this file when requested by the Teledyne DALSA Technical Support group along with a full description of your computer.

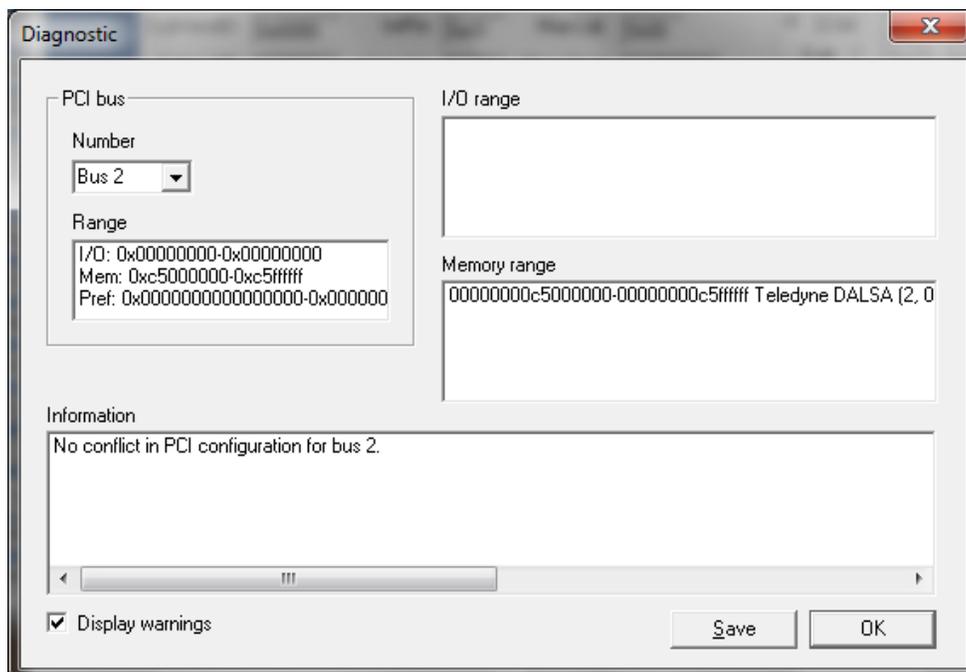


Figure 46: PCI Diagnostic Program – PCI bus info

Windows Device Manager

An alternative method to confirm the installation of the Xtium2-CLHS PX8 board and driver is to use the Windows Device manager tool. Use the Start Menu shortcut **Start • Control Panel • System • Device Manager**. As shown in the following screen images, look for Xtium2-CLHS PX8 board under “Imaging Devices”. Double-click and look at the device status. You should see “This device is working properly.” Go to “Resources” tab and make certain that the device has an interrupt assigned to it, without conflicts.

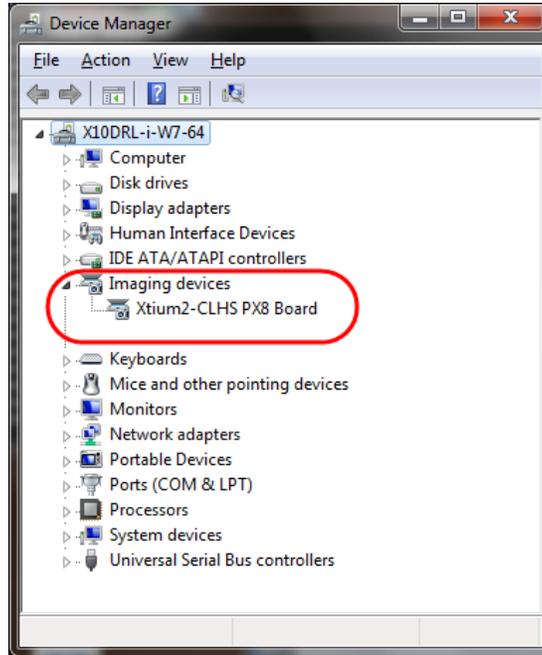


Figure 47: Using Windows Device Manager

BSOD (blue screen) Following a Board Reset

There are cases where a PC will falsely report a hardware malfunction when resetting the Xtium2-CLHS PX8 board. Ensure that you are using Sapera LT 7.50 or later.

Sapera and Hardware Windows Drivers

Any problem seen after installation, such as an error message running CamExpert, first make certain the appropriate Teledyne DALSA drivers have started successfully during the boot sequence. Example, click on the **Start • Programs • Accessories • System Tools • System Information • Software Environment** and click on **System Drivers**. Make certain the following drivers have started for the **Xtium2-CLHS PX8**.

Device	Description	Type	Started
CorXtium2CLHSPX8	Xtium2-CLHS PX8 messaging	Kernel Driver	Yes
CorLog	Sapera Log viewer	Kernel Driver	Yes
CorMem	Sapera Memory manager	Kernel Driver	Yes
CorPci	Sapera PCI configuration	Kernel Driver	Yes
CorSerial	Sapera Serial Port manager	Kernel Driver	Yes

Teledyne DALSA Technical Support may request that you check the status of these drivers as part of the troubleshooting process.

Recovering from a Firmware Update Error

This procedure is required if any failure occurred while updating the Xtium2-CLHS PX8 firmware on installation or during a manual firmware upgrade. If on the case the board has corrupted firmware, any Sopera application such as CamExpert or the grab demo program will not find an installed board to control.

Possible reasons for firmware loading errors or corruption are:

- Computer system mains power failure or deep brown-out
- PCI bus or checksum errors
- PCI bus timeout conditions due to other devices
- User forcing a partial firmware upload using an invalid firmware source file

When the Xtium2-CLHS PX8 firmware is corrupted, the board will automatically run from the Safe load after a PC reset.

Solution: Update the board using the standard method described in section Firmware Update: Automatic Mode.

Driver Information via the Device Manager Program

The Device Manager program provides a convenient method of collecting information about the installed Xtium2-CLHS PX8. System information such as operating system, computer CPU, system memory, PCI configuration space, plus Xtium2-CLHS PX8 firmware information is displayed or written to a text file (default file name – BoardInfo.txt). Note that this program also manually uploads firmware to the Xtium2-CLHS PX8 (described elsewhere in this manual).

Execute the program via the Windows Start Menu shortcut .

Start • Programs • Teledyne DALSA • Xtium2-CLHS PX8 Device Driver • Device Manager.

If the Device Manager Program does not run, it will exit with a board was not found message.

Possible reasons for an error are:

- Board is not in the computer
- Board driver did not start or was terminated
- PCI conflict after some other device was installed

Information Window

The following figure shows the Device Manager Information screen. Click to highlight one of the board components and its information shows in the right hand window, as described below.

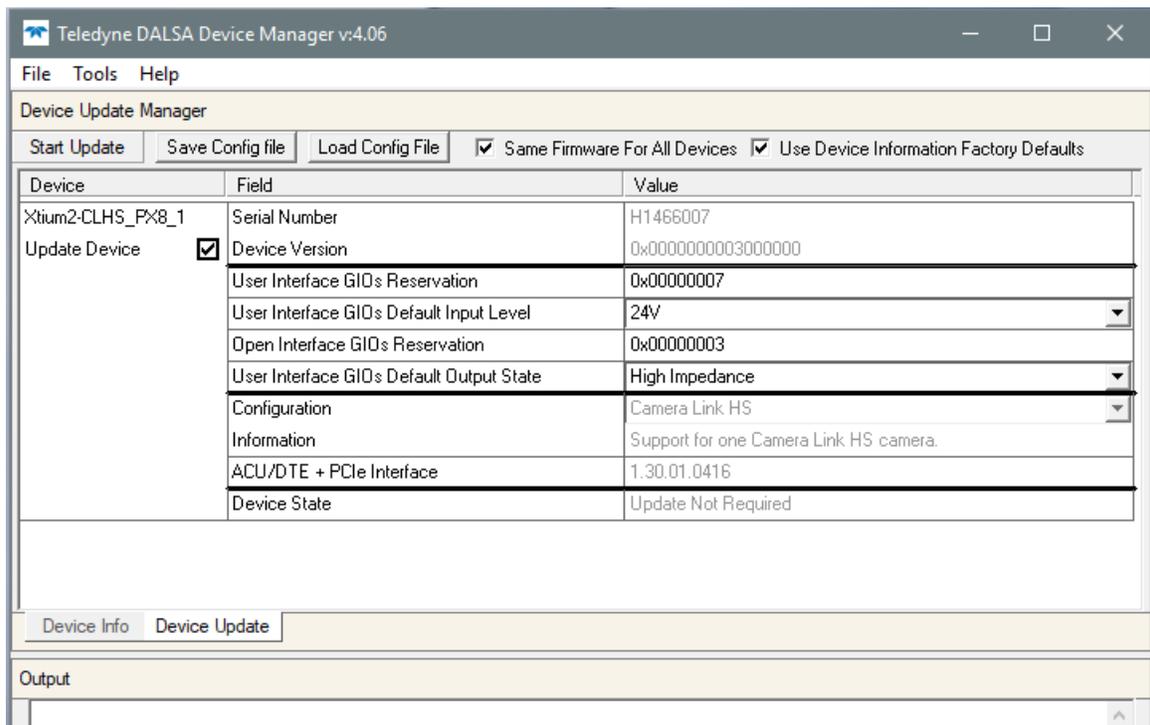


Figure 48: Board Firmware Version

- Select **Information** to display identification and information stored in the Xtium2-CLHS PX8 firmware.
- Select **Firmware** to display version information for the firmware components.
- Select one of the firmware components to load *custom* firmware when supplied by Teledyne DALSA engineering for a future feature.
- Click on **File • Save Device Info** to save all information to a text file. Email this file when requested by Technical Support.

Teledyne DALSA Log Viewer

The third step in the verification process is to save in a text file the information collected by the Log Viewer program. Run the program via the Windows Start Menu shortcut

Start • Programs • Teledyne DALSA • Sopera LT • Tools • Log Viewer.

The Log Viewer lists information about the installed Teledyne DALSA drivers. Click on File • Save and you will be prompted for a text file name to save the Log Viewer contents. Email this text file to Teledyne DALSA Technical Support when requested or as part of your initial contact email.

On-board Image Memory Requirements for Acquisitions

The Xtium2-CLHS PX8 by default will allocate the maximum number of buffers that can fit in on-board memory based on the size of the acquired image before cropping, to a maximum of 65535 buffers. Note that an application can change the default number of on-board frame buffers using the Sopera LT API. Usually two buffers will ensure that the acquired video frame is complete and not corrupted in cases where the image transfer to host system memory may be interrupted and delayed by other host system processes. That is, there is no interruption to the image acquisition of one buffer by any delays in transfer of the other buffer (which contains the previously acquired video frame) to system memory.

If allocation for the requested number of buffers fails, the driver will reduce the number of on-board frame buffers requested until they can all fit. If there is not enough memory for 2 on-board buffers, the driver will reduce the size such that it allocates two partial buffers. This mode is dependent on reading out the image data to the host computer faster than the incoming acquisition.

The maximum number of buffers that can fit in on-board memory can be calculated as follows:

- $(\text{Total On-Board memory} / (\text{Buffer Size in Bytes} + 256 \text{ Bytes used to store the DMA}))$.

For example, assuming 512MB of on-board memory and acquiring 1024 x 1024 x 8 bit images, the number of on-board buffers would be:

- $512 \text{ MB} / [(1024 \times 1024) + 256] = 511.875 \Rightarrow 511 \text{ on-board buffers.}$

Symptoms: CamExpert Detects no Boards

- When starting CamExpert, with no Teledyne DALSA board detected, CamExpert will start in offline mode. There is no error message and CamExpert is functional for creating or modifying a camera configuration file. If CamExpert should have detected an installed board frame grabber, troubleshoot the installation problem as described below.

Troubleshooting Procedure

When CamExpert detects no installed Teledyne DALSA board, there could be a hardware problem, a system bus problem, a kernel driver problem, or a software installation problem.

- Make certain that the card is seated in PCIe slot.
- Perform all installation checks described in this section before contacting Technical Support.
- Try the board in a different PCIe slot if available.

Symptoms: Xtium2-CLHS PX8 Does Not Grab

Sapera CamExpert does start but you do not see an image and the frame rate displayed is 0.

- Verify the camera has power.
- Verify the Camera Link HS cable is connected to the camera.
- Verify the camera and timing parameters with the camera in free run mode.
- Verify you can grab with the camera in free run mode.
- Make certain that you provide an external trigger if the camera configuration file requires one. Use the software trigger feature of CamExpert if you do not have a trigger source.
- Make certain that the camera configuration is the required mode. This must match the camera configuration file. Refer to your camera datasheet.
- Try to snap one frame instead of continuous grab.
- Perform all installation checks described in this section before contacting Technical Support.

Symptoms: Card grabs black

You are able to use Sapera CamExpert, the displayed frame rate is as expected but the display is always black.

- Set your camera to manual exposure mode and set the exposure to a longer period, plus open the lens iris.
- Try to snap one frame instead of continuous grab.
- Make certain that the input LUT is not programmed to output all '0's.
- A PCIe transfer issue sometimes causes this problem. No PCIe transfer takes place, so the frame rate is above 0 but nevertheless no image is displayed in CamExpert.
- Make certain that BUS MASTER bit in the PCIe configuration space is activated. Look in PCI Diagnostics for **BM** button under "Command" group. Make certain that the **BM** button is activated.

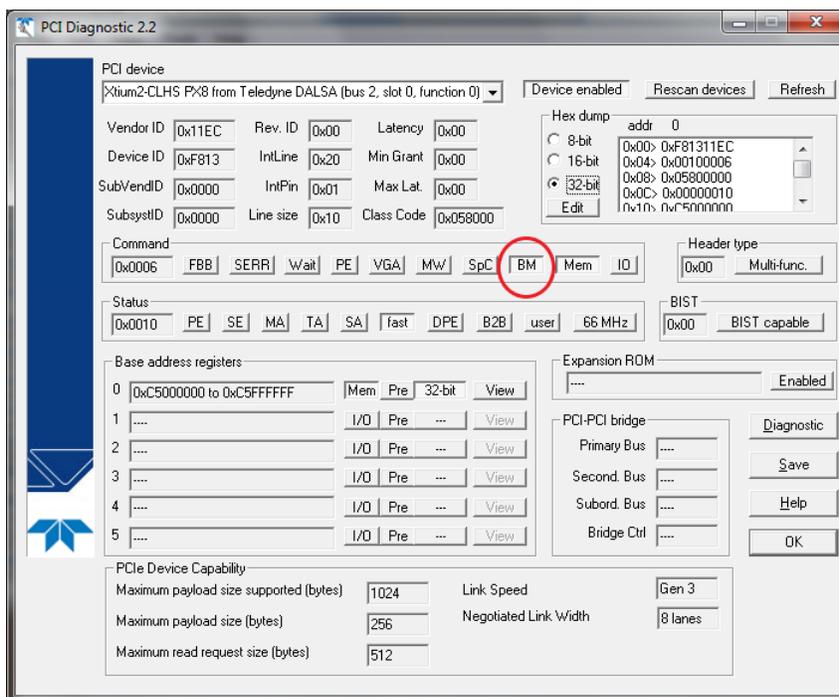


Figure 49: PCI Diagnostic Tool BM Button

- Perform all installation checks described in this section before contacting Technical Support.

Symptoms: Card acquisition bandwidth is less than expected

The Xtium2-CLHS PX8 acquisition bandwidth is less than expected.

- Review the system for problems or conflicts with other expansion boards or drivers.
- Remove other PCI Express, PCI-32 or PCI-64 boards and check acquisition bandwidth again. Engineering has seen this case where other PCI boards in some systems cause limitations in transfers. Each system, with its combination of system motherboard and PCI boards, will be unique and must be tested for bandwidth limitations affecting the imaging application.
- Is the Xtium2-CLHS PX8 installed in a PCI Express x16 slot?
- Note that some computer's x16 slot may only support non x16 boards at x1 or not at all. Check the computer documentation or test an Xtium2-CLHS PX8 installation. The speed at which the board is running can be viewed using the Diagnostic Tool provided with the driver.
- Is the Xtium2-CLHS PX8 installed in a PCI Express Gen1 or Gen2 slot?
- Some older computers only have PCIe Gen1 or Gen2 slots. The Generation at which the board is running is viewed using the [Diagnostic Tool](#) provided with the driver.
- Is the PCI maximum payload size smaller than 256 bytes?
- On some computers, this parameter can be changed in the PC's BIOS.

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