

*Rockchip*  
*Linux Camera Developer Guide*

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# **Preface**

## **Overview**

This document mainly introduces the new driver structure of CIF and ISP of Rockchip chipset, and how to write/port sensor driver, how to apply demos and tools test in the upper layer base on it.

In order to meet customization needs, the CIF, ISP and Camera drivers described in this document all meet V4L2 standard interface as much as possible, providing a richer configuration. At the same time, there are higher requirements for customers writing and porting drivers. Customers need to know more about the underlying topology, V4L2 related concepts and so on.

## **Product version**

<b>Chipset</b>	<b>Kernel</b>	<b>CIF</b>	<b>ISP</b>
PX3SE	4.4	Yes	NO
RK312x	4.4	Yes	NO
RK3288	4.4	Yes	Yes
RK332x	4.4	Yes	Yes
RK3399	4.4	NO	NO

## **Applicable to object**

This document is mainly suitable for the following engineers:

- Field application engineers
- Software development engineers

## Revision history

Date	Version	Author	Revision Description
2019.7.10	V1.0	ZSQ	Initial Release
2019.3.12	V1.1	Leo Wen	Update isp driver description Add gstreamer application programming Update 3A function description, etc.

## Agreement

- Code and commands: the code and commands in this document are filled with gray background
- Command format: the operation commands in the examples in this document use the escape character '\ ' to split a line into multiple lines when there are multiple lines. You can directly copy and paste when using, but if you put the command on one line, please remove the escape character '\ '

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# 1 Camera and driver introduction

## 1.1 Driver version

Camera in this document refers to CIF or ISP of Rockchip chips and the sensor connected to them. And the CIF and ISP driver described in this document refer to new version driver for V4L2 Framework Standards which are based on Media Controller, Async sub device, vb2.

The driver versions and support list are as follows.

Driver name	Type	Kernel version	Platform	Whether it was decribed in this document
Rkisp1	ISP	4.4	Linux	Yes
Rkcif	CIF	4.4	Linux	Yes
Oneframe	CIF	3.10 or 4.4	Linux	No
Rk-isp10	ISP	4.4	Linux	Yes, see the note for details <sup>[1]</sup>

Table 1 Driver version

## 1.2 Acronyms

- 3A, refers to auto focus (AF), auto exposure (AE) and auto white balance (AWB) algorithms, or algorithms .so library
- Async Sub Device, specifically refers to V4L2 sub-device under Media Controller structure.
- Bayer Raw, or Raw Bayer, indicates the format of RGGB, BGGR, GBRG, GRBG output by device (Sensor or ISP), or the data frame of the format.
- Buildroot, specifically refers to a series of Linux SDK base on Buildroot<sup>[2]</sup> released by Rockchip.
- CIF, that is camera interface which is used to receive data from sensor and save it to memory.
- DVP, is a parallel interface, short for Digital Video Port
- Entity, in this document, it refers to each node under Media Controller framework.

<sup>1</sup> □ Rk-isp10 is still in support, but it does not use the structure of media controller, async sub device, is not the focus of this document.

<sup>2</sup> □ Buildroot see its official website: <https://buildroot.org/>

- FCC or FourCC, that is Four Character (FCC) codes, and it refers to the image format represented by 4 characters in Linux Kernel. For details, see [FourCC](#).
- HSYNC, Line sync signal
- ISP, Image Signal Processing, used to receive and process images
- IOMMU, Input-Output Memory Management Unit, in this document, it means iohmu module in Rockchip chips, it is used to map physically fragmented memory pages into visible contiguous memory of cif or isp.
- IQ, Image Quality, in this document, it refers to the xml corresponding to IQ or IQ debugged by bayer raw camera. It is used for 3A tuning
- Media Controller, a media framework for Linux kernel
- MIP, refers to MIPI protocol in this document.
- MIPI-DPHY refers to MIPI-DPHY protocol, or the controller that complies with MIPI-DPHY protocol of Rockchip chips in this document.
- MP, Main Path, refers to an output node of Rockchip ISP, which can output full-resolution images and generally used for taking pictures and grabbing Raw graphs.
- PCLK is Pixel clock
- Pipeline refers to the link formed by the interconnection of each entity under media controller in this document.
- SP, Self Path, refers to an output node of Rockchip ISP, which can only output 1080p resolution and generally used for preview.
- Userspace, that is Linux user space (relative to Linux kernel space), specifically refers to user layer or the program executed at user layer in this document.
- V4L2, Video4Linux2, the video processing module of Linux kernel
- VIP refers to Video Input Processor in Rockchip chips, it once used as an alias for CIF and it is no longer used.
- VSYNC, Field sync signal

## 2 CIF driver and dts configuration

This chapter mainly introduces CIF driver and dts configurations and the test verification of CIF driver on each chip in detail.

CIF is a camera interface, once used the name of VIP (Video Input Processor) in Rockchip series chips. Both of them refer to camera interface.

CIF support information on Linux SDK of each chip is as follows:

Platform	DVP interface	MIPI CSI	Crop	Scale	Mode	Maximum resolution	iommu
PX3SE	support	Not support	support	Not support	Oneframe		No
RK3288	support	Waiting for verification	support	Not support	Oneframe		Yes
RK3326	support	Waiting for verification	support	Not support	Oneframe		Yes

Table 2 CIF verification of each chip

Notice:

- In oneframe mode, if image resolution is higher, such as 1080p, fps may only reach 15fps.
- MIPI CSI, on some platforms, CIF can receive images transmitted from MIPI CSI
- If there is no iommu function and buffer is allocated in mmap mode during reqbuf, kernel is required to retain a larger CMA size. You can modify in kernel defconfig as follows:

```
CONFIG_CMA_SIZE_MBYTES=64
```

### 2.1 CIF driver code introduction

The CIF kernel driver code is located in `drivers/media/platform/rockchip/cif/` directory, and the corresponding device tree binding document is located in `Documentation/devicetree/bindings/media/rockchip-cif.txt`. Whether to compile is controled by compiling switch `CONFIG_VIDEO_ROCKCHIP_CIF`.

The CIF driver performs hardware configuration, frame interrupt processing, and buffer rotation according to media controller, v4l2, and vb2 frameworks. The function contents of each file are as follows

```
$ tree drivers/media/platform/rockchip/cif/
drivers/media/platform/rockchip/cif/
├── capture.c //Mainly perform hardware configuration, related callback under v4l2,
vb2 framework, frame interrupt processing
├── dev.c // Mainly perform probe, sub-device asynchronous (Async) registration,
iommu and clk management
├── dev.h // Driver related structure definition
├── regs.h // Register macro definition
```

- CIF oneframe mode, in oneframe mode, each time the driver receives a frame interrupt, the next frame buffer address is set in the interrupt handler function, and then the next frame data is collected.
- CIF pingpong(Double buffers)mode. The driver has not been implemented.

## 2.2 CIF dts configuration

Please refer to Documentation/devicetree/bindings/media/rockchip-cif.txt first. This document will be updated as the driver code is updated. In dtsi of the chip, the basic information of cif is generally configured, including but not limited to:

- Reg, register offset address
- Clocks, the clocks needed. Clock-names need to be the same as defined in the driver
- Reset, CIF can be reset with CRU software
- Interrupts
- Iommu, if there is iommu in cif, iommu will be enabled.

### 2.2.1 Board level configuration

Firstly, confirm whether there is a new cif driver node definition in the corresponding chip-level dtsi. Please use compatible to distinguish between old and new cif drivers.

- The old cif drive

```
compatible = "rockchip,cif";
```

- The new cif driver

```
compatible = "rockchip,rk3xxx-cif";
```

Then confirm whether cif has iommu function. If there is an iommu node, it needs to be set to "okay" state.

Finally, you need to define Remote Port<sup>[1]</sup> which connects sensor to CIF. During kernel initialization process, sensor registers asynchronously with CIF. The two are finally bound according to Remote Port information in dts.

Example 1, cif dts configuration on px3se evb board

CIF nodes are defined in arch/arm/boot/dts/rk312x.dtsi,

```
cif_new: cif-new@1010a000 {
    compatible = "rockchip,rk3128-cif";
    reg = <0x1010a000 0x200>;
    clocks = <&cru ACLK_CIF>, <&cru HCLK_CIF>,
            <&cru SCLK_CIF_OUT>;
    clock-names = "aclk_cif", "hclk_cif",
                 "sclk_cif_out";
    resets = <&cru SRST_CIF0>;
    reset-names = "rst_cif";
    interrupts = <GIC_SPI 8 IRQ_TYPE_LEVEL_HIGH>;
    /* rk312x has not iommu attached */
    /* iommu = <&cif_mmu>; */
    power-domains = <&power RK3128_PD_VIO>;
    status = "disabled";
};
```

Board level configuration is in arch/arm/boot/dts/px3se-evb.dts, need to reference cif\_new, and modify status state to okay, and finally add port sub-node.

```
&cif_new {
    status = "okay";
```

<sup>1</sup> [More information about Remote Port see Documentation/devicetree/bindings/media/video-interfaces.txt](#)

```

port {
    cif_in: endpoint {
        remote-endpoint = <&adv7181_out>;
        vsync-active = <0>;
        hsync-active = <1>;
    };
};
};

```

The Port subnode defines cif\_in node and declares that the remote node to which it is linked is adv7191\_out. Because adv7181 uses dvp interface, it also specifies the valid state of vsync, hsync here, where 0 means active low and 1 means active high.

## 2.3 CIF Driver debug and frequently asked questions

This chapter describes how to judge the status of CIF device, how to turn on debug switch, and use v4l2-ctl to capture frames, use mplayer to play back images, gstreamer previews, and frequently asked questions.

Commands in this chapter are based on px3se-evb boards. Other boards may be different. In particular, the serial numbers of /dev/media0 and /dev/video0 device nodes may be different. Even the serial number of video0 device may be changed on px3se-evb board. Please refer to the method of how to obtain video device number in the chapter of [whether cif probes successfully or not](#).

### 2.3.1 Whether cif probes successfully or not

If CIF probes successfully, there will be video and media devices in /dev/ directory. For example, /dev/media0<sup>[1]</sup> device.

There may be several /dev/video devices in a system. You can query video node corresponding to cif through the node under /sys.

```

[root@px3se:~]# grep -H " /sys/class/video4linux/video*/name
/sys/class/video4linux/video0/name:stream_cif

```

It can be seen that cif device corresponds to video0 node, in other words, /dev/video0

<sup>1</sup> [1] If there are multiple media devices, the number is not necessarily 0. For example, if CIF and ISP are enabled at the same time on 3288, there will be two media devices: /dev/media0 and /dev/media1.

is cif device.

In addition, you can also print topology through media-ctl to see if pipeline is normal. Please refer to [media-ctl and topology](#).

If there are bugs, please check cif-related error log from kernel log. E.g,

```
[root@px3se:/]# dmesg | grep -i cif
```

Note:

- If you need to report cif bugs or issues to Rockchip, please provide the full kernel log. The more complete the Log, the more helpful to analyze problems.

### 2.3.2 Determine if sensor and CIF are bound

As mentioned above, CIF and sensor are asynchronously loaded (probe) respectively. If both drivers are loaded successfully, they will be bound together. At this point, it will prompt accordingly in kernel log.

```
[root@px3se:/]# dmesg | grep Async  
[ 2.681364] rkCIF: Async subdev notifier completed
```

If you see "Async subdev notifier completed", it means sensor and CIF are successfully bound.

At the same time, users can still view media topology, there should be cif and sensor two entities. Please refer to [media-ctl and topology](#).

If asynchronous registration is found to be unsuccessful, that is, there is no "Async subdev notifier completed" log, please check whether cif and sensor probe are wrong. Frequently encountered case is sensor driver power-on timing is wrong, Sensor I2C communication failure.

### 2.3.3 Turn on debug switch

The CIF driver contains some v4l2\_dbg() logs. The log switch can be turned on by command, as follows.

```
echo 1 > /sys/module/video_rkcif/parameters/debug
```

Turned on vb2 related log which mainly includes buffer rotation, such as reqbuf, qbuf, dqbuf and buffer state changes, as follows. Note that vb2 module switch is a general

switch. Other related logs that use vb2 (such as VPU/ISP, etc.) will also enable output.

```
echo 7 > /sys/module/videobuf2_core/parameters/debug
```

Turn on v4l2 related log, such as ioctl call. The following command will turn on all v4l2 related logs.

```
echo 0x1f > /sys/class/video4linux/video0/dev_debug
```

It is also possible to turn on only a small part of log. The following macro<sup>[1]</sup> defines which logs each bit will enable. Turn on the bit corresponding to required log.

```
/* Just log the ioctl name + error code */
#define V4L2_DEV_DEBUG_IOCTL      0x01
/* Log the ioctl name arguments + error code */
#define V4L2_DEV_DEBUG_IOCTL_ARG  0x02
/* Log the file operations open, release, mmap and get_unmapped_area */
#define V4L2_DEV_DEBUG_FOP        0x04
/* Log the read and write file operations and the VIDIOC_(D)QBUF ioctls */
#define V4L2_DEV_DEBUG_STREAMING  0x08
/* Log poll() */
#define V4L2_DEV_DEBUG_POLL       0x10
```

### 2.3.4 Frequently ask questions and answers

---

1 [1]These macros are defined in kernel header file include/media/v4l2-ioctl.h



## 3 RKISP1 driver and dts configuration

ISP is more complicated than CIF, and its functions are richer. This chapter mainly introduces driver code structure, dts configuration, and debug method of RKISP1. Like CIF, ISP driver conforms to media controller, v4l2, and vb2 frameworks, and is independent of mipi-dphy and sensor and is registered asynchronously.

### 3.1 RKISP1 Driver code structure and its block diagram

RKISP1 driver code described in this chapter is located in `driver/media/platform/rockchip/isp1/` directory of kernel. It mainly implements hardware configuration, interrupt processing, control buffer rotation, control subdevice (such as mipi dphy and sensor) to power on and off according to v4l2 / media framework. Briefly introduce the contents of each file in the driver as follows.

```
$ tree drivers/media/platform/rockchip/isp1/
drivers/media/platform/rockchip/isp1/
├── capture.c // Include mp/sp configuration and vb2, frame interrupt processing
├── dev.c // Contains probe, asynchronous registration, clock, pipeline, iommu and
media/v4l2 framework
├── isp_params.c // 3A Related parameters setting
├── isp_stats.c // 3A Related statistics
├── regs.c // Registers related read and write operations
├── rkisp1.c // Corresponding to isp_sd entity node, including receiving data from
mipi, crop function

$ ls drivers/phy/rockchip/phy-rockchip-mipi-rx.c
drivers/phy/rockchip/phy-rockchip-mipi-rx.c # mipi dphy driver
```

The block diagram below briefly describes the internal structure of ISP.

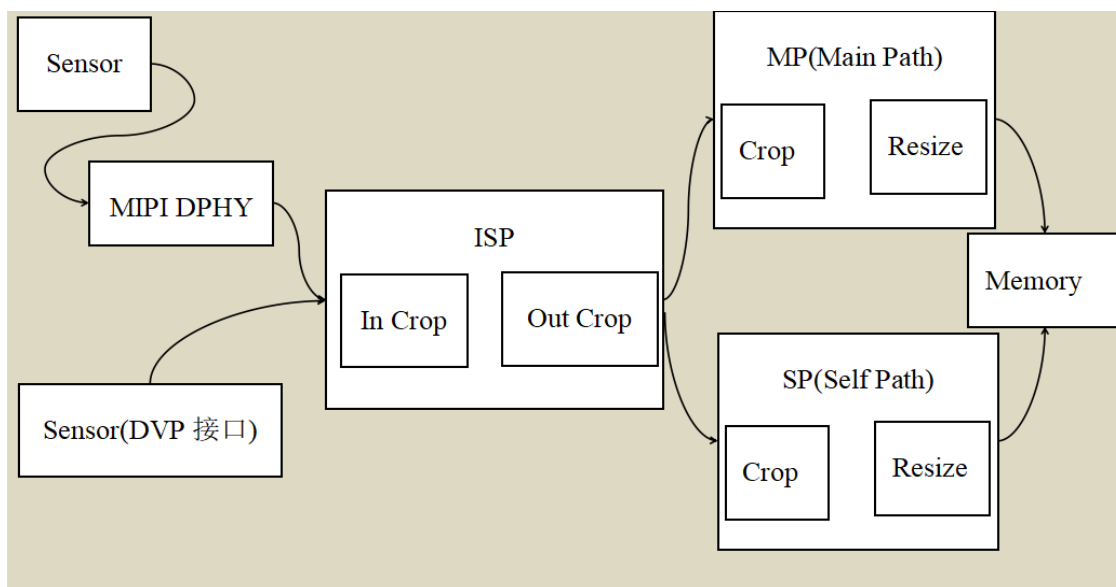


Figure 1 RKISP1 brief block diagram

The above block diagram is mainly used to reflect the functional characteristics of ISP input and output for users to understand.

- ISP can adapt DVP interface
- ISP can adapt MIPI interface, but need mipi dphy
- After an image is input to ISP, it can be divided into two MP and SP output. MP and SP are the same image, but resize, crop can be different, and the output format can be different.
- MP, MP is short for Main Path. It can output full resolution images up to 4416x3312
- MP can output yuv or raw images, and only MP can output raw images
- SP, that is Self Path. Supports up to 1920x1080 resolution
- SP can output yuv or rgb images, but can not output raw images
- Both MP and SP have the function of crop and resize, and they do not affect each other.

Output device	Maximum resolution	Support format	Crop/Resize
SP	1920 x 1080	YUV, RGB	Support
MP	4416 x 3312	YUV, RAW	Support

Table 3 MP and SP output function comparison

## 3.2 RKISP1 dts configuration

Like CIF, there is also a complete document of RKISP1 DTS binding located in Documentation/devicetree/bindings/media/rockchip-isp1.txt. Please refer to this document first, it will keep up with the driver update. When a RK Linux SDK is released, if the chip supports ISP, the rkisp1 node is already defined in dtsi, such as the isp node in rk3288-rkisp1.dtsi, the rkisp1\_0, rkisp1\_1 node in rk3399.dtsi. The following table describes the information of each chip ISP.

	ISP quantity	Dts node name	Corresponding mipi dphy	Iommu node
RK3288	1	isp	RX0 or RX1	Support, isp_mmu
RK3399	2	rkisp1_0	RX0	Support, isp0_mmu
		rkisp1_1	TX1RX1	Support, isp1_mmu

Table 4 ISP dts node information of each chip

Note:

- RK3288.dtsi also registered isp node, but it corresponds to the old driver. The new driver is registered in the rk3288-rkisp1.dtsi file. Please include this file in board configuration
- Multiple isp nodes are also registered in RK3399.dtsi. Please note what this chapter described are rkisp1\_0 and rkisp1\_1.
- Iommu needs to be enabled or disabled with isp
- If there are multiple isp (such as rk3399), please note to choose the right iommu node

### 3.2.1 Board level configuration of Rkisp1 dts

The board-level configuration is similar to CIF. The isp, mipi-dphy, and sensor are separately defined nodes. The three are connected to each other through remote endpoints. On the block diagram, mipi-dphy connects isp and sensor. The following example is based on the dts board level configuration on RK3399 excavator and can be found in the file rk3399-sapphire-excavator-edp.dts. On this board, both ISPs of RK3399 are enabled, only take rkisp1\_0 as an example here.

First, set rkisp1\_0 node to "okay" state.

```
&isp0 {
    status = "disabled";
};

&rkisp1_0 {
    status = "okay";
    port {
        #address-cells = <1>;
        #size-cells = <0>;
        isp0_mipi_in: endpoint@0 {
            reg = <0>;
            remote-endpoint = <&dphy_rx0_out>;
        };
    };
};
```

Note,

- The node state of other versions of isp driver needs to be disabled. Otherwise two different drivers will conflict
- The rkisp1\_0 is defined in the Port node to be interconnected with dphy\_rx0\_out node.

Secondly, the iommu corresponding to rkisp1\_0 also needs to be "okay" status.

```
&isp0_mmu {
    status = "okay";
};
```

Thirdly, sensor is mipi interface, so mipi dphy needs to be enabled as well.

```
&mipi_dphy_rx0 {
    status = "okay";
    ports {
        #address-cells = <1>;
        #size-cells = <0>;
        port@0 {
```

```
        reg = <0>;
        #address-cells = <1>;
        #size-cells = <0>;
        mipi_in_ucam0: endpoint@1 {
            reg = <1>;
            remote-endpoint = <&ucam_out0>;
            data-lanes = <1 2>;
        };
    };
    port@1 {
        reg = <1>;
        #address-cells = <1>;
        #size-cells = <0>;
        dphy_rx0_out: endpoint@0 {
            reg = <0>;
            remote-endpoint = <&isp0_mipi_in>;
        };
    };
};
```

Note:

- Dphy connects both isp and Sensor. So it has two endpoints. Mipi\_in\_ucam0 is connected to Sensor, and dphy\_rx0\_out is connected to isp
- The data-lanes is declared in mipi\_in\_ucam0, indicating that sensor uses two lanes. If there are 4 lanes, it should be defined as <1 2 3 4>. And so on. At last, board-level sensor node is defined, and the port sub node needs to be declared to connect to dphy\_rx0\_out of mipi dphy.

### 3.3 RKISP1 debug and frequently asked questions

This chapter mainly introduces how to debug ISP and judge whether driver is loaded successfully and frequently asked questions and answers. Because ISP is similar to CIF in

structure and uses the same framework, users can also refer to [CIF driver debug and frequently asked questions](#).

### 3.3.1 Driver probe status judgement

If RKISP1 probe successfully, there will be video and media devices in /dev/ directory. There may be multiple /dev/video devices in a system. You can query the video node registered by RKISP1 through /sys. The following is the execution command and result<sup>[1]</sup> (with deletion) on RK3399 Dru Chrome Table.

```
localhost ~ # grep " /sys/class/video4linux/video*/name
/sys/class/video4linux/video3/name:rkisp1_selfpath
/sys/class/video4linux/video4/name:rkisp1_mainpath
/sys/class/video4linux/video5/name:rkisp1-statistics
/sys/class/video4linux/video6/name:rkisp1-input-params
```

The RKISP1 driver registers four devices, selfpath, mainpath, statistics, and input-params. The first two are for frame output, and the last two are for 3A parameter setting and statistics. By looking up the sys node under video4linux, we got RKISP1 information of RK3399 Dru as shown in the following table.

Device node	Name	Functions
/dev/video3	SP(Self Path)	Video output
/dev/video4	MP(Main Path)	Video output
/dev/video5	Statistics	3A statistics
/dev/video6	Input-params	3A parameter settings

Table 5 Rkisp1 registered video devices

Note:

- Rkisp1 driver registers four /dev/video devices with continuous numbers.
- If the two isps of RK3399 platform are enabled at the same time, a total of 8 /dev/video devices will be registered. The first 4 belong to one isp and the last 4 belong to another isp. It is not possible to distinguish the order of two isp

<sup>1</sup> □ 不同的板子返回会有差异，特别是当 VPU/CIF 等设备也有启用时。他们都是基于 v4l2 框架。

registrations by software.

- In this example, the video number starts with 3. Because there are still vpu devices occupying 0, 1, 2 three video nodes

Users can also print topology through media-ctl to see if pipeline is normal. Please refer to [media-ctl and topology](#).

If the above two methods return errors, please check kernel log for cif-related error log. E.g,

```
[root@px3se:/]# dmesg | grep -i isp
```

Note:

- If users need to report related bugs or issues to Rockchip, please provide the full kernel log. The more complete the Log, the more helpful to analyze problems.

### 3.3.2 Judge whether sub-device is successfully bound

Please use media-ctl print topology to see if the sensor registered by dts are asynchronously registered as an Entity. And when all sensors are registered, kernel will print the following log.

```
localhost ~ # dmesg | grep Async  
[ 0.682982] rkisp1: Async subdev notifier completed
```

If there is no Async subdev notifier completed this line log in kernel, or the topology does not match expected, please first check whether the sensor has an error, and whether I2C communication is successful.

### 3.3.3 Turn on debug switch

We will introduce three debugging switches, v4l2\_dbg switch for rkisp1 driver, log switch for vb2 module, and log switch for v4l2 frame layer.

The Rkisp1 driver contains some v4l2\_dbg, such as format, size parameter settings, and dropped frames in interrupt, as follows

```
echo 1 > /sys/module/video_rkisp1/parameters/debug
```

The log switch of Vb2 module and v4l2 frame layer is the same as CIF. Please refer to [turn on debug switch](#). The two points as follows have to note.

- All modules that use vb2, such as isp, vpu, cif, are enabled and output by vb2 log switch.

- Log of V4l2 framework layer is for a specific /dev/video node, so only certain video devices are enabled. For information on how to find video device required by users, please refer to [the probe driver status judgment](#) chapter.

### 3.3.4 Frequently ask questions and answers



## 4 Sensor driver development and port

The sensor driver is located in `drivers/media/i2c` directory. Note that the sensor driver described in this chapter are with media controller attribute, so the driver in the `drivers/media/i2c/soc_camera` directory is not applicable.

The sensor driver is completely independent of CIF or RKISP1 driver, the two are registered asynchronously, and finally the connection is established via remote-endpoint. Therefore, the sensor driver described in this chapter applies to both CIF and RKISP1.

Under Media Controller structure, sensor is generally used as a sub-device and linked to cif, isp or mipi phy via a pad. This chapter mainly introduces the sensor driver code<sup>[1]</sup>, dts configuration, and how to verify the correctness of sensor driver.

This chapter summarizes the development of sensor driver development into five parts.

- Write power-on sequence according to the datasheet, including vdd, reset, powerdown, clk, etc.
- Configure sensor registers to output the desired resolution and format.
- Write the callback function required by struct `v4l2_subdev_ops`, generally including `set_fmt`, `get_fmt`, `ov5695_s_stream`
- Add v4l2 controller to set such as fps, exposure, gain, test pattern
- Write `.probe()` function and add media control and v4l2 sub device initialization code

As a good habit, after completing driver encoding, you need to add the corresponding documentation. You can refer to `Documentation/devicetree/bindings/media/i2c/`. The board level dts can be quickly configured according to this document.

In the board level dts, following items are generally required when using sensor driver:

- Configure correct clk, io mux
- Set regulator and gpio required for power-on sequence according to the schematic
- Add a port sub node to establish a connection with cif or isp

This chapter will take ov5695 and ov2685 as examples, and simply analyzes sensor driver.

---

<sup>1</sup> [1] Sensor driver development requires users to understand some basic knowledge of v4l2 framework. This chapter only briefly analyzes and describes outline based on the existing code. In the actual development process, you may encounter various problems, most of which cannot be explained here.

## 4.1 Power-on timing sequence

Different sensors have different power-on timing requirements, such as OV Camera. Most of OV Camera may not have strict timing requirements. As long as mclk, vdd, reset or powerdown status is correct, I2C communication can be performed correctly and images can be output. However, there are still a small number of sensors that have strict requirements for power-on. For example, OV2685 must be powered on in strict timing sequence.

In dataSheets provided by sensor manufacturer, there are usually power-on sequence diagrams, which only need to be configured in order. Take OV5695 as an example, where `__ov5695_power_on()` is used to power up sensor. As follows (with deletion).

```
static int __ov5695_power_on(struct ov5695 *ov5695)
{
    ret = clk_prepare_enable(ov5695->xvclk);
    if (!IS_ERR(ov5695->reset_gpio))
        gpiod_set_value_cansleep(ov5695->reset_gpio, 1);
    ret = regulator_bulk_enable(OV5695_NUM_SUPPLIES, ov5695->supplies);
    if (!IS_ERR(ov5695->reset_gpio))
        gpiod_set_value_cansleep(ov5695->reset_gpio, 0);
    if (!IS_ERR(ov5695->pwn_gpio))
        gpiod_set_value_cansleep(ov5695->pwn_gpio, 1);
    /* 8192 cycles prior to first SCCB transaction */
    delay_us = ov5695_cal_delay(8192);
    usleep_range(delay_us, delay_us * 2);
    return 0;
}
```

The power-on sequence of OV5695 is briefly described as follows

- First provide xvclk (mclk)
- Next enable reset pin
- Each VDD power on. Regulator\_bulk is used here for vdd, vodd, avdd are not strictly ordered. If there are strict requirements between vdd, it need to be handled

separately, please refer to OV2685 driver code.

- After Vdd is powered on, cancel Sensor Reset and powerdown status. Reset and powerdown may only need one, if sensor package is different, there may be differences
- Finally, according to timing requirements, after 8192 clk cycles, power-on is completed.

Note that although many sensors can work when do not follow the datasheet requirements, the timings recommended by manufacturer are undoubtedly the most reliable.

Similarly, there will be a Power Down Sequence in the datasheet, which is also available on request.

#### 4.1.1 Wether power-on sequence is correct

During .probe() process, it will try to read chip id, such as ov5695\_check\_sensor\_id() of ov5695. If chip id can be read correctly, it is generally considered that power-on sequence is correct and sensor can perform i2c communication normally.

## 4.2 Sensor initialization registers list

In OV5695 and OV2685, struct ov5695\_mode and struct ov2685\_mode are defined to indicate different initialization modes of sensor. Mode can include resolution, mbus code, register initialization list, and so on.

Registers initialization list, please fill in directly according to manufacturers. It should be noted that the list ends with REG\_NULL.

## 4.3 V4l2\_subdev\_ops callback function

V4l2\_subdev\_ops callback function is the core of logic control in sensor driver. The callback function includes a lot of functions, you can check the kernel code include/media/v4l2-subdev.h for details. It is recommended that sensor driver include at least the following callback function.

- .open, in this way the upper layer can open /dev/v4l-subdev? node. When the upper layer needs to set v4l control separately for sensor, .open() must be implemented.
- .s\_stream, that is, set stream, including stream on and stream off, generally

configure registers here to output images.

- `.enum_mbus_code`, enumerate driver-supported `mbus_code`
- `.enum_frame_size`, enumeration driver supported resolution
- `.get_fmt`, returns format/size selected by current sensor. If `.get_fmt` is missing, `media-ctl` tool cannot view the `fmt` currently configured by sensor entity.
- `.set_fmt`, set format/size of sensor

In the above callback, `.s_stream stream_on` is more complicated. In `ov5695` driver code, it includes `pm_runtime enable` (wake up and power up), configure control information (`v4l2` control may be configured when sensor is powered off) that is `v4l2_ctrl_handler_setup()`, and finally write to `stream on` of register.

## 4.4 V4l2 controller

When `fps`, `exposure`, `gain`, and `blinking` need to be configured, the part of `v4l2` controller is necessary. In the `OV5695` driver code,

- `ov5695_initialize_controls()`, used to declare which controls are supported, and set the maximum and minimum information.
- Struct `v4l2_ctrl_ops`, contains `ov5695_set_ctrl()` callback function to respond to the settings of upper layers

## 4.5 Probe function and media entity, v4l2 subdev

### registration

In the Probe function, firstly parse the `dts` to get the information such as `regulator`, `gpio`, `clk`, etc. which is used to sensor power on and off. Secondly, register media entity, `v4l2 subdev`, and `v4l2` controller information. Note that the registration of `v4l2 subdev` is asynchronous. Below are some key functions call.

- `v4l2_i2c_subdev_init()`, register as a `v4l2 subdev` with a callback function in the parameter
- `ov5695_initialize_controls()`, initialize `v4l2` controls
- `media_entity_init()`, registered as a media entity, `OV5695` has only one output that is Source Pad
- `v4l2_async_register_subdev()`, declare that sensor needs to be registered asynchronously. Since `RKISP1` and `CIF` both use asynchronous registration of sub

devices, this call is required.

## 4.6 A dts example

The dts configurations of snsr are similar. According to the hardware design, it is mainly included pinctl (iomux), clk, gpio, and remote port.

The following example is OV5695 dts node on RK3399 Dru Chrome Tablet

```
wcam: camera@36 {
    compatible = "ovti,ov5695";
    reg = <0x36>;
    pinctrl-names = "default";
    pinctrl-0 = <&wcam_rst &test_clkout1>;
    clocks = <&cru SCLK_TESTCLKOUT1>;
    clock-names = "xvclk";
    avdd-supply = <&pp2800_cam>;
    dvdd-supply = <&pp1250_cam>;
    dovdd-supply = <&pp1800_s0>;
    reset-gpios = <&gpio2 5 GPIO_ACTIVE_LOW>;

    port {
        wcam_out: endpoint {
            remote-endpoint = <&mipi_in_wcam>;
            data-lanes = <1 2>;
        };
    };
};
```

Note:

- Pinctrl, declares the necessary pinctrl, which includes reset pin initialization and clk iomux
- Clock, the specified name is xvclk (driver will read clock named xvclk), that is, 24M clock.
- Vdd supply, OV5695 need three power supplies.

- Port subnode defines an endpoint that declares a connection to mipi\_in\_wcam. Similarly mipi dphy will reference wcam\_out
- Data-lanes specifies that OV5695 uses two lanes

## 4.7 Sensor debug and frequently ask questions

### 4.7.1 Is the sensor registered successfully?

The first key point for sensor debugging is whether i2c can communicate successfully and chip id check is correct. If so, it can generally indicate that there is no problem with power-on sequence. The related log will usually be printed out in driver. Logs of different sensors are not the same, it will not take examples here. Second, check media-ctl topology to see if sensor is already registered as an entity. If so, sensor has been registered successfully.

### 4.7.2 Is there data output from sensor?

Direct measurement of hardware MIPI signal CLK and Data Lane is the most accurate method if conditions permit. Is there a signal output, and whether the signal amplitude is correct, etc.

If there is an interruption in CIF or ISP can be judged by software. For example, if kernel log has errors reported by CIF or ISP.

### 4.7.3 Check if controls are in effect

The v4l2-ctl can be used to set related parameters, such as gain, exposure, blanking and generate images to see if controls of sensors are in effect. For example, increase gain or exposure, whether the brightness of pictures increases; when increase blanking, whether frame rate drops.

### 4.7.4 Frequently asked questions and answers

Q: It has been repeatedly checked that power-on sequence meets the datasheet requirements, but I2c communication is unsuccessful.

A: It has encountered several reasons before, as follows

- Io domain setting is incorrect, causing i2c clk and data output amplitudes to be incorrect (although there are waveforms). For example, power supply is 1.8v, but the io domain is set to 3.3v.

- Regulator start up delay is too large, resulting in the fact that although power-up sequence configured in the code is correct, the actual measurement still does not meet the requirements. For example, the regulator used by OV2685 pp1250\_dvdd on a board is valid from input to output, and has a delay of 740 us, causing power on is too slowly and timing sequence is error.
- I2C slave address configuration is wrong

## 5 The v4l-utils tool and applications

The v4l-utils tool is a V4L2 development kit maintained by Linxxtv<sup>[1]</sup>. It provides a set of V4L2 and media framework related tools for configuring V4L2 sub-device properties, testing V4L2 devices, and providing development libraries such as libv4l2.so and so on.

This chapter mainly introduces two command-line tools in v4l-utils: media-ctl and v4l2-ctl

- media-ctl, used to view and configure topology
- v4l2-ctl, used to configure v4l2 controls, capture frames, set cif, isp, sensor parameters

The format code of different versions of v4l-utils will be different, especially mbus-fmt part. The version used in this document is [v4l-utils-1.14.1](#) integrated in Linux SDK.

### 5.1 Obtain and compile v4l-utils

In the Linux SDK released by Rockchip, v4l-utils package has been integrated by default. Users can turn v4l-utils package on or off with buildroot compile switch. In the buildroot/configs/rockchip\_px3se\_defconfig file of SDK directory, the following line opens v4l-utils compile option:

```
BR2_PACKAGE_LIBV4L_UTILS=y
```

Users can also get the source code compilation on [Linxxtv official website](#). Please refer to [wiki](#) for compilation.

v4l-utils package is under ubuntu system, it can also be installed directly through apt tool, as follows

```
$ sudo apt-get install v4l-utils
```

### 5.2 FourCC

FourCC is short for Four Character Codes, uses 4 characters (that is 32bit) to name image format. In Linux Kernel, it is a macro, and defined as follows:

```
#define v4l2_fourcc(a,b,c,d) \
(((u32)(a)<<0)|((u32)(b)<<8)|((u32)(c)<<16)|((u32)(d)<<24))
```

The format defined by FourCC is the format in which image videos are stored in memory. This point should be distinguished from mbus-fmt below.



The following are a few of formats commonly used in this document. See [videodev2.h](#) of kernel code for details.

Image format	FourCC
V4L2_PIX_FMT_NV12	NV12
V4L2_PIX_FMT_NV21	NV21
V4L2_PIX_FMT_NV16	NV16
V4L2_PIX_FMT_NV61	NV61
V4L2_PIX_FMT_NV12M	NM12
V4L2_PIX_FMT_YUYV	YUYV
V4L2_PIX_FMT_YUV420	YU12
V4L2_PIX_FMT_SBGGR10	BG10
V4L2_PIX_FMT_SGBRG10	GB10
V4L2_PIX_FMT_SGRBG10	BA10
V4L2_PIX_FMT_SRGGB10	RG10

Table 6 Commonly used FourCC code in this document

### 5.3 mbus-fmt

The mbus-fmt is short for [Media Bus Pixel Codes](#) which describes the format used for transmission over physical bus, such as the image format that sensor transmits to ISP via mipi dphy, or the format transmitted between submodules within ISP. In particular, it is necessary to distinguish Mbus-fmt from [FourCC](#) of the previous chapter, which is specifically the image format stored in Memory.

The following table lists several Mbus-fmts commonly used in this document.

Name	Type	Bpp	Bus width	Sampes per Pixel
MEDIA_BUS_FMT_SBGGR10_1X10	Bayer Raw	10	10	1
MEDIA_BUS_FMT_SGBRG10_1X10	Bayer Raw	10	10	1
MEDIA_BUS_FMT_YUYV8_2X8	YUV:422	16	8	2
MEDIA_BUS_FMT_YUYV8_1_5X8	YUV:420	12	8	1.5

Table 7 Several mbus-fmt commonly used in this document

The latest media-ctl can list the supported mbus code as follows:

```
media-ctl --known-mbus-fmts
```

### 5.4 Media-ctl and topology

Media-ctl is a tool in v4l-utils package. It is mainly used to configure fmt, size, and link

nodes of media framework. Users can query the usage method by the following help.

This chapter will also introduce several common examples.

```
[root@px3se:/]# media-ctl --help
media-ctl [options]
-d, --device dev      Media device name (default: /dev/media0)
-e, --entity name     Print the device name associated with the given entity
-V, --set-v4l2 v4l2   Comma-separated list of formats to setup
  --get-v4l2 pad      Print the active format on a given pad
  --set-dv pad        Configure DV timings on a given pad
-h, --help           Show verbose help and exit
-i, --interactive     Modify links interactively
-l, --links links     Comma-separated list of link descriptors to setup
  --known-mbus-fmts  List known media bus formats and their numeric values
-p, --print-topology Print the device topology. If an entity
                    is specified through the -e option, print
                    information for that entity only.
  --print-dot        Print the device topology as a dot graph
-r, --reset          Reset all links to inactive
-v, --verbose        Be verbose
.....
```

### 5.4.1 Media-ctl: topology

If driver supports Media Controller, a media device such as /dev/media0 will be created after CIF or ISP is successfully loaded. Media-ctl is used to print out the current pipeline link.

The next few chapter describe some cases of CIF and ISP topologies.

### 5.4.2 Case 1: CIF topology

CIF topology in figure 2 is cif topological structure of px3se evb board. ADV7181 is linked to CIF Sink as a sub-device source.

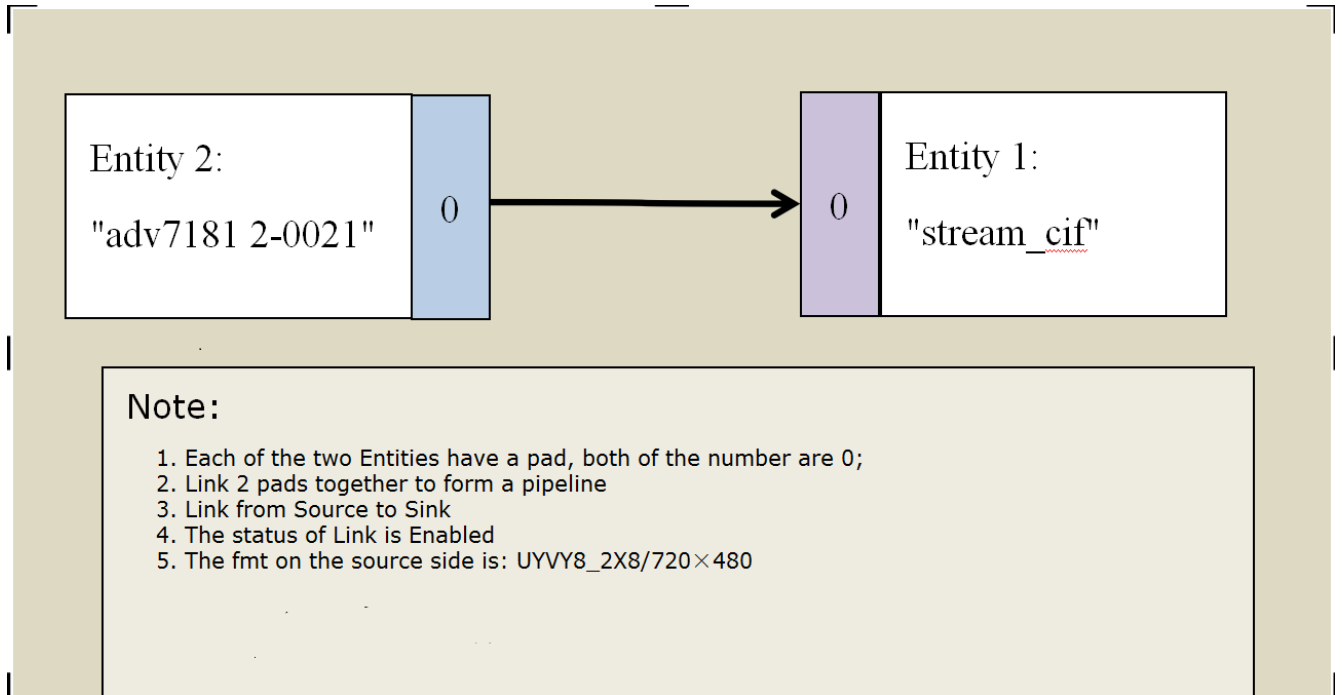


Figure 2 CIF topology

Topology can be printed out via media-ctl as follows (with deletion).

```
[root@px3se:/]# media-ctl -p /dev/media0
Media controller API version 0.1.0
-----
driver      rkCIF
Device topology
- entity 1: stream_cif (1 pad, 1 link)
    type Node subtype V4L flags 0
    device node name /dev/video0
    pad0: Sink
        <- "adv7181 2-0021":0 [ENABLED]
- entity 2: adv7181 2-0021 (1 pad, 1 link)
    type V4L2 subdev subtype Sensor flags 0
    device node name /dev/v4l-subdev0
    pad0: Source
        [fmt:UYVY8_2X8/720x480 field:none colorspace:smpte170m]
        -> "stream_cif":0 [ENABLED]
```

### 5.4.3 Case 2: ISP camera topology

Taking RK3326 EVB as an example, sensor Ov5695 is connected to mipi dphy via mipi bus; after ISP collects mipi data, the corresponding image processing is performed by isp entity, such as demosaicing; mp, sp can configure the format and resolution of respective output frame data.

Print out more information through media-ctl, such as the input and output format and size of current entity, whether it has crop and resize capabilities. The following is the media topology of RK3326 EVB

```
[root@rk3326_64:/]# media-ctl -d /dev/media1 -p
Media controller API version 0.1.0

Media device information
-----
driver      rkisp1
model      rkisp1
serial
bus info
hw revision  0x0
driver version 0.0.0

Device topology
- entity 1: rkisp1-isp-subdev (4 pads, 5 links)
  type V4L2 subdev subtype Unknown flags 0
  device node name /dev/v4l-subdev0
  pad0: Sink
    [fmt:SBGGR10_1X10/2592x1944 field:none
    crop.bounds:(0,0)/2592x1944
    crop:(0,0)/2592x1944]
    <- "rockchip-mipi-dphy-rx":1 [ENABLED]
  pad1: Sink
```

```
<- "rkisp1-input-params":0 [ENABLED]
pad2: Source
    [fmt:YUYV8_2X8/2592x1944 field:none
    crop.bounds:(0,0)/2592x1944
    crop:(0,0)/2592x1944]
-> "rkisp1_selfpath":0 [ENABLED]
-> "rkisp1_mainpath":0 [ENABLED]
pad3: Source
    -> "rkisp1-statistics":0 [ENABLED]

- entity 2: rkisp1_mainpath (1 pad, 1 link)
    type Node subtype V4L flags 0
    device node name /dev/video1
pad0: Sink
    <- "rkisp1-isp-subdev":2 [ENABLED]

- entity 3: rkisp1_selfpath (1 pad, 1 link)
    type Node subtype V4L flags 0
    device node name /dev/video2
pad0: Sink
    <- "rkisp1-isp-subdev":2 [ENABLED]

- entity 4: rkisp1-statistics (1 pad, 1 link)
    type Node subtype V4L flags 0
    device node name /dev/video3
pad0: Sink
    <- "rkisp1-isp-subdev":3 [ENABLED]

- entity 5: rkisp1-input-params (1 pad, 1 link)
    type Node subtype V4L flags 0
    device node name /dev/video4
```

```
pad0: Source
    -> "rkisp1-isp-subdev":1 [ENABLED]

- entity 6: rockchip-mipi-dphy-rx (2 pads, 2 links)
    type V4L2 subdev subtype Unknown flags 0
    device node name /dev/v4l-subdev1
    pad0: Sink
        [fmt:SBGGR10_1X10/2592x1944 field:none]
        <- "ov5695 2-0036":0 [ENABLED]
    pad1: Source
        [fmt:SBGGR10_1X10/2592x1944 field:none]
        -> "rkisp1-isp-subdev":0 [ENABLED]

- entity 7: ov5695 2-0036 (1 pad, 1 link)
    type V4L2 subdev subtype Sensor flags 0
    device node name /dev/v4l-subdev2
    pad0: Source
        [fmt:SBGGR10_1X10/2592x1944@10000/300000 field:none]
        -> "rockchip-mipi-dphy-rx":0 [ENABLED]
```

#### 5.4.4 Media-ctl: entity, pad and link

Entity represents a node in Media Controller. It contains one or more input and output pads. Link represents a link that connects multiple different pads. Multiple links form a complete pipeline.

The name of Entity can be viewed from topology. For example, the following are the names of entity.

- ov5695 2-0036
- rkisp1-isp-subdev
- rkisp1\_mainpath

Pad is represented by a number. An Entity can contain multiple pads, either Source or

Sink.

Link connects two "entities": pad, such as the link shown below,

- "rkisp1-isp-subdev":2->"rkisp1\_mainpath":0
- "rkisp1-isp-subdev":3->"rkisp1-statistics":0

The status of link can be Active or In-Active.

Media Controller provides a flexible configuration of pipeline. In CIF and ISP driver initialization process, Link is completely established according to configurations. If there are multiple sensors, one of them will be activated.

You can use media-ctl command to modify active state of Link. You can also modify format and size of Pad.

### 5.4.5 Media-ctl: In-/Active Link

The following error: The reference source is not found, two sensors are connected to the same mipi dphy, and sensor can be enabled or disabled by userspace. Ov5695 and Ov2685 sensors are connected to mipi dphy via mipi bus. The two sensors in this Case can only have one be enabled at a time.

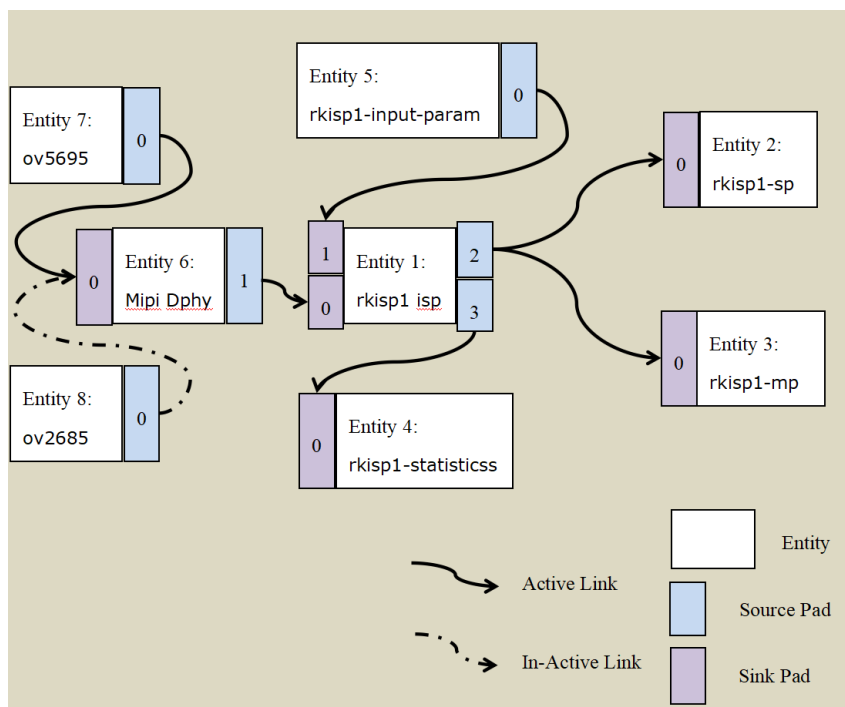


Figure 3 ISP Dual Camera topology

Error: The reference source was not found. There are multiple sensors connected to the same Mipi D-Phy, and only one of them can be active. The following example sets ov2659 to active

```
#First set ov5695 to In-Active
media-ctl -d /dev/media1 -l "'ov5695 2-0036':0->'rockchip-mipi-dphy-rx':0[0]"
#Then set ov2685 to Active
media-ctl -d /dev/media1 -l "'ov2685 2-003c':0->'rockchip-mipi-dphy-rx':0[1]"
```

Note:

- Format: `media-ctl -l "'entity name':pad->'entity name':pad[Status]'`
- The entire link needs to use single quotes because there are special characters like `> [ ]`
- Entity name needs to use double quotes because there is a space in between
- Status with 0 or 1 indicates Active or In-Active and need to use brackets `[ ]`

#### 5.4.6 Media-ctl: modify fmt/size

Error: reference source is not found, the following example shows how to modify fmt/size

Example 1, modify the size of ov5695 output to 640x480 (The precondition is that ov5695 driver already supports 640x480 output, otherwise the setting will not succeed), and set the input and output resolution of the entire pipeline to 640x480, and the format of isp entity is YUYV.

```
# Set the sensor output to 640x480
```

```
media-ctl -d /dev/media0 \
--set-v4l2 "'ov5695 7-0036':0[fmt:SBGGR10_1X10/640x480]"
```

# Set isp receiving (from mipi dphy) format and size, the format requirements are the same as sensor output

```
media-ctl -d /dev/media0 \
--set-v4l2 "'rkisp1-isp-subdev':0[fmt:SBGGR10_1X10/640x480]"
```

```
# isp Receiving size can be cropped, but still keep 640x480 here
```

```
media-ctl -d /dev/media0 \
--set-v4l2 "'rkisp1-isp-subdev':0[crop:(0,0)/640x480]"
```

```
# Set isp output, YUV format can only be YUYV2X8
```

```
media-ctl -d /dev/media0 \
```



```
--set-v4l2 "'rkisp1-isp-subdev':2[fmt:YUYV8_2X8/640x480]'
```

```
# isp output also has crop function, but also keep 640x480
```

```
media-ctl -d /dev/media0 \
```

```
--set-v4l2 "'rkisp1-isp-subdev':2[crop:(0,0)/640x480]'
```

Note:

- Different versions of v4l-utils may have different fmt codes, preferably use media-ctl

```
media-ctl --known-mbus-fmts
```

- Pay attention to special characters, single or double quotes is needed
- Be careful not to leave spaces in quotes, and don't leave more spaces.
- Please use media-ctl --help to see more detailed help

## 5.5 The fmt, controls and grab frames Configurations by v4l2-ctl

The operation of Media-ctl tool is through media devices such as /dev/media0, which manages the format, size, and link of each node in the topology of media. V4l2-ctl tool is for video devices such as /dev/video0, /dev/video1, and it performs set\_fmt, reqbuf, qbuf, dqbuf, stream\_on, stream\_off and other operations on video devices.

In this document, we mainly use v4l2-ctl to collect frame data, and set v4l2\_control such as exposure, gain, VTS, etc.

First of all, it is recommended to first check the help file of v4l2-ctl. Help document contents are so much and divided into many parts, we are more concerned about streaming, vidcap.

View help document outline as follows

```
$ v4l2-ctl --help
```

See the full help document below with a lot of contents.

```
$ v4l2-ctl --help-all
```

View the parameters related to streaming as follows.

```
$ v4l2-ctl --help-streaming
```

View parameters related to vidcap as follows. It mainly includes get-fmt, set-fmt and

so on.

```
$ v4l2-ctl --help-vidcap
```

### 5.5.1 Set fmt and grab frames

For specific use of V4l2-ctl, please refer to v4l-utils tool and application. Only px3se-evb board is taken as an example here. Generally, CIF media topology is very simple, with only one sensor and cif two entities. If the output format and size of sensor do not need to be modified and the default value is used, you do not need media-ctl configuration to grab a frame directly using v4l2-ctl. The following only need to specify the related parameters such as fmt, count.

```
v4l2-ctl -d /dev/video0 \  
--set-fmt-video=width=720,height=480,pixelformat=NV12 \  
--stream-mmap=3 \  
--stream-skip=3 \  
--stream-to=/tmp/cif.out \  
--stream-count=1 \  
--stream-poll
```

Note of the parameters:

- -d, specify the operation object as /dev/video0 device
- --set-fmt-video, specify width and height and pxief format
- NV12, that is, pixelformat represented by FourCC. See [FourCC](#) code above for details.
- --stream-mmap, specified buffer type as mmap, which is physical continuous or iohmu mapped buffer allocated by kernel.
- --stream-skip, specify the first 3 frames of discard (not saved to file)
- --stream-to, specify the file path where frame data is saved
- --stream-count, specifies the number of frames to grab, excluding the number of --stream-skip drops
- --stream-poll, this option indicates v4l2-ctl uses asynchronous IO, in other word, using the select until frame data is complete before dqbuf to ensure that dqbuf does not block. Otherwise dqbuf will block until a data frame arrives.

### 5.5.2 Set control such as exposure, gain, etc.

If sensor driver has implemented v4l2 control, such as exposure, gain, etc. can be set by v4l2-ctl before an image is acquired.

CIF or ISP will inherit control of sub device, so you can see v4l2 control of sensor through /dev/video3. The following are the related settings of OV5695 viewed on Dru machine, including exposure, gain, blanking, test\_pattern, etc.

```
localhost /tmp # v4l2-ctl -d /dev/video3 -l
User Controls
exposure (int)  : min=4 max=2020 step=1 default=1104 value=1104
gain (int)     : min=0 max=16383 step=1 default=1024 value=1024
Image Source Controls
vertical_blanking (int)  : min=40 max=31795 step=1 default=40 value=80
horizontal_blanking (int) : min=1664 max=1664 step=1 default=1664
analogue_gain (int)     : min=16 max=248 step=1 default=248 value=248
Image Processing Controls
link_frequency (intmenu): min=0 max=0 default=0 value=0 flags=read-only
pixel_rate (int64)     : min=0 max=180000000 step=1 default=180000000
value=180000000 flags=read-only
test_pattern (menu)    : min=0 max=4 default=0 value=0
```

These controls can be modified with v4l2-ctl. Such as modifying exposure and analogue\_gain as follows

```
v4l2-ctl -d /dev/video3 --set-ctrl 'exposure=1216,analogue_gain=10'
```

Note:

- If there are special characters, it require single quotes
- If multiple cameras are connected to the same ISP, only the control of the first sensor can be viewed and modified. Are there bugs in V4l2-ctl, or is it because the driver does not implement G/S\_INPUT?

### 5.5.3 Play back frames on Ubuntu with mplayer

After the captured frame data is saved to a file, images can be played back on PC. For

example, on ubuntu you can play with mplayer.

```
W=720; H=480; mplayer /tmp/cif.out -loop 0 -demuxer rawvideo -fps 25 \  
-rawvideo w=${W}:h=${H}:size=$(( ${W} * ${H} * 3 / 2 )):format=nv12
```

For more detailed usage of mplayer, please refer to mplayer manual<sup>[1]</sup>, or online tutorial.

#### 5.5.4 Set fmt and grab raw data of Raw Bayer

The rkisp driver will synchronize format/size information of currently connected sensor, and set on nodes of each pipeline. You do not need to go through the upper layer settings. If you need to set custom format/size to each pipeline, refer to the following example.

For example, grab raw data of Raw Bayer from sensor OV5695 output. The format is SBGGR10\_1X10 and the size is 2592x1944.

```
media-ctl -d /dev/media1 --set-v4l2 "ov5695 2-0036":0[fmt:SBGGR10_1X10/2592x1944]'  
media-ctl -d /dev/media1 --set-v4l2 "rkisp1-isp-subdev":0[fmt:SBGGR10_1X10/2592x1944]'  
media-ctl -d /dev/media1 --set-v4l2 "rkisp1-isp-subdev":0[crop:(0,0)/2592x1944]'  
media-ctl -d /dev/media1 --set-v4l2 "rkisp1-isp-subdev":2[fmt:SBGGR10_1X10/2592x1944]'  
media-ctl -d /dev/media1 --set-v4l2 "rkisp1-isp-subdev":2[crop:(0,0)/2592x1944]'  
v4l2-ctl -d /dev/video1 --set-ctrl 'exposure=1216,analogue_gain=10' \  
--set-selection=target=crop,top=0,left=0,width=2592,height=1944 \  
--set-fmt-video=width=2592,height=1944,pixelformat=BG10 \  
--stream-mmap=3 --stream-to=/tmp/mp.raw.out --stream-count=1 --stream-poll
```

Note:

- media-ctl in Line 4 sets the isp-subdev output format to be consistent with sensor
- Lines 3 and 5 set crop to be the same size as sensor, in other word, not cropped.
- On line 6, if the graph is too dark, you can adjust exposure and gain to increase brightness. Optional, and sensor driver needs to implement v4l2 control
- On line 7, v4l2-ctl sets selection not to crop, and output pixelformat FourCC is BG10.

<sup>1</sup> [1] If mplayer is installed on Ubuntu, use the command `man mplayer` to view mplayer manual.

- It is important to note that although ISP does not process raw graph, it will still fill the low bit of 10 bit data with 0 to form 16bit. Regardless of whether sensor input is 10bit, 12bit, the upper layer is always 16bit per pixel.

### 5.5.5 Bayer Raw graph converted to PGM

Adding PGM sign to the head of Bayer Raw file to change to pgm graph which can be directly opened under Ubuntu<sup>[1]</sup>, only need to add three rows of PGM headers. Users often get a carriage return error when adding a pgm header. One more empty line will cause failing to open pgm graph. The following command can be used directly to generate pgm header and append raw to the end of pgm header. Append bayer raw data to the end of raw.pgm as follows. In this way /tmp/raw.pgm can be viewed directly. Note that file appends require two '>'s.

You can write raw2pgm.sh script as follows

```
#!/bin/bash
cat > /tmp/raw.pgm << EOF
P5
2592 1944
65535
cat $1 >> /tmp/raw.pgm
```

Note,

- Line 1, P5 is a fixed identifier
  - Line 2, which represents the resolution of Raw graph, that is length and width, separated by a space character.
  - Line 3, indicating depth, 65535 is 16 bits. If it is 8bit, change it to 255 accordingly.
- Just add a frame of RAW file to be converted after script.

```
./raw2gpm.sh mp.raw
```

---

<sup>1</sup> [1] It seems to need to install other tools to find pgm files under Windows. You can also open the bayer raw map with photoshop, but you also need to set the width and height, bpp.

## 6 GStreamer preview

### 6.1 gst-launch-1.0 command

Under Rockchip latest Linux SDKs, GStreamer commands are the same. Whether they are CIF/ISP or UVC Cameras, GStreamer can capture camera images from V4L2 devices. For preview tests without 3A effects, you can use the following command to preview camera images with GStreamer, the precondition is that it can use v4l2-ctl to capture images. RKISP1 driver layer will configure pipeline according to the properties of connected sensor, set isp-subdev input and output size, etc. If you need to customize resolution format and other attributes, please read the previous chapter.

#### 6.1.1 gst-launch-1.0 command preview

```
export XDG_RUNTIME_DIR=/tmp/.xdg
gst-launch-1.0 --gst-debug=3 v4l2src device=/dev/video1 ! videoconvert ! \
video/x-raw,format=NV12,width=640,height=480 ! kmssink
```

Please refer to docs documents published with SDK for the use of GStreamer.

--gst-debug=3: Print level, the higher the value, the higher the print information.

Device=/dev/video1: specifies camera device node that is open, is video0 by default

Videoconvert: converts src data format to a data format that sink can display

Video/x-raw, format=NV12, width=640, height=480: display data format of sink

Kmssink: display plugin

#### 6.1.2 Save a file by gst-launch-1.0 command

To save a local file, just replace sink plugin, take 10 frames of data as an example:

```
gst-launch-1.0 v4l2src device=/dev/video1 num-buffers=10 ! \
video/x-raw,format=NV12,width=640,height=480, framerate=30/1 ! \
videoconvert ! filesink location=/tmp/test.yuv
```

## 6.2 GStreamer application programming

The Linux SDKs released by Rockchip are integrated with GStreamer and can be used to preview images. This chapter describes how to write a simple camera preview program using GStreamer.

First, you should call `gst_init()` in the main function to complete the corresponding initialization works, so that the parameters input by users from command line are passed to GStreamer function library. One typical GStreamer initialization application is as follows:

```
#include <gst/gst.h>

int main(int argc, char *argv[]) {
    /* Initialize GStreamer */
    gst_init (&argc, &argv);
}
```

Create a `GMainLoop` object with `g_main_loop_new()`.

```
/* create main loop, start to loop after running g_main_loop_run */
loop = g_main_loop_new(NULL, -1);
```

Pipeline is used to contain and manage element in GStreamer framework. The following code creates a new pipeline called `uvc-camera`:

```
pipeline = gst_pipeline_new("uvc-camera");
```

Create a data source element by using `v4l2src`, the element is responsible for obtaining data from camera

```
source = gst_element_factory_make("v4l2src", "camera-input");
```

Set some properties of `v4l2src`

```
/* set source parameters */
g_object_set(G_OBJECT(source), "device", argv[1], NULL);

source_capsfilter = gst_element_factory_make("capsfilter", "source_capsfilter");
source_caps = gst_caps_new_simple ("video/x-raw",
    "format", G_TYPE_STRING, "YUY2",
    "width", G_TYPE_INT, 640,
    "height", G_TYPE_INT, 480,
    NULL);
g_object_set(G_OBJECT(source_capsfilter),"caps", source_caps, NULL);
```

Create converter element and sink element.

```
/* create converter element */
```

```
converter = gst_element_factory_make("videoconvert", "video-converter");  
  
/* create sink element */  
  
sink = gst_element_factory_make("autovideosink", "camera-output");
```

Add a message handler function `bus_call` to monitor the generated message.

```
/* Wait until error or EOS */  
  
bus = gst_element_get_bus (pipeline);  
  
gst_bus_add_watch(bus, bus_call, loop);  
  
gst_object_unref(bus);
```

The three elements that have been created need to be all added to pipeline and connected in order.

```
/* add elements to pipeline */  
  
gst_bin_add_many(GST_BIN(pipeline), source, source_capsfilter, converter, sink, NULL);  
  
/* connect elements sequentially */  
  
gst_element_link_many(source, source_capsfilter, converter, sink, NULL);
```

After all the preparations are completed, you can start the data processing of the entire pipeline by switching the state of pipeline to `PLAYING` state.

```
gst_element_set_state(pipeline, GST_STATE_PLAYING);
```

Enter the main loop, it will block here until it is allowed to exit. When there is an event, it deals with the event and sleeps when there is no event.

```
/* start to loop */  
  
g_main_loop_run(loop);
```

Quit pipeline and release resources

```
/* quit loop and return */  
  
g_print("Returned, stopping playback\n");  
  
gst_element_set_state(pipeline, GST_STATE_NULL);  
  
gst_object_unref(GST_OBJECT(pipeline));
```

You can test the program directly with a PC and the compile command is as follows. The development board test has to use the cross-compilation toolchain to compile.

```
gcc gst-video.c -o gst-video `pkg-config --cflags --libs gstreamer-1.0`
```



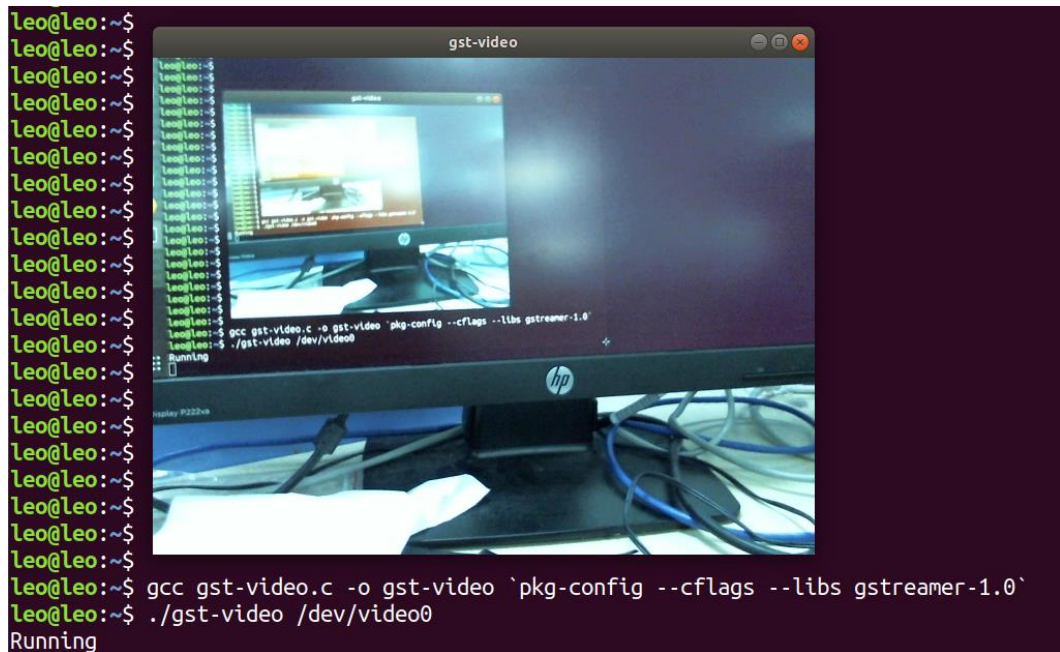


Figure 4 The gst-video application preview

The whole code is as follows

```
#include <gst/gst.h>

#include <glib.h>

#include <stdio.h>

#include <stdbool.h>

/* message processing */

static gboolean bus_call(GstBus * bus, GstMessage * msg, gpointer data)
{
    GMainLoop *loop = (GMainLoop *) data;

    switch (GST_MESSAGE_TYPE(msg))
    {

        case GST_MESSAGE_EOS:
            g_print("End of stream\n");
            g_main_loop_quit(loop);
            break;

        case GST_MESSAGE_ERROR:
```

```
{
    gchar *debug;

    GError *error;

    gst_message_parse_error(msg, &error, &debug);

    g_free(debug);

    g_printerr("ERROR:%s\n", error->message);

    g_error_free(error);

    g_main_loop_quit(loop);

    break;
}

default:
    break;
}

return 1;
}

int main(int argc, char *argv[]) {

    GMainLoop *loop;

    GstElement *pipeline, *source, *converter, *sink, *vqueue;

    GstElement *source_capsfilter;

    GstCaps *source_caps;

    GstBus *bus;

    /* Initialize GStreamer */
    gst_init (&argc, &argv);

    if (argc < 2)
    {
        g_printerr("Usage:%s [camera device name] for camera capture. eg(./gst-video
/dev/video0)\n", argv[0]);
    }
}
```

```
    return -1;
}

/* create main loop, start to loop after running g_main_loop_run */
loop = g_main_loop_new(NULL, -1);

/* create pipeline and element */
pipeline = gst_pipeline_new("uvc-camera");
source = gst_element_factory_make("v4l2src", "camera-input");

/* set source parameters */
g_object_set(G_OBJECT(source), "device", argv[1], NULL);

source_capsfilter = gst_element_factory_make("capsfilter", "source_capsfilter");
source_caps = gst_caps_new_simple ("video/x-raw",
    "format", G_TYPE_STRING, "YUY2",
    "width", G_TYPE_INT, 640,
    "height", G_TYPE_INT, 480,
    NULL);
g_object_set(G_OBJECT(source_capsfilter), "caps", source_caps, NULL);

/* create converter element */
converter = gst_element_factory_make("videoconvert", "video-converter");

/* create sink element */
sink = gst_element_factory_make("autovideosink", "camera-output");

if (!pipeline || !source || !source_capsfilter || !converter || !sink)
{
    g_printerr("One element could not be created.Exiting.\n");
    return -1;
}

/* Wait until error or EOS */
bus = gst_element_get_bus (pipeline);
gst_bus_add_watch(bus, bus_call, loop);
```

```
gst_object_unref(bus);

/* add elements to pipeline */

gst_bin_add_many(GST_BIN(pipeline), source, source_capsfilter, converter, sink, NULL);

/* connect elements sequentially */

gst_element_link_many(source, source_capsfilter, converter, sink, NULL);

gst_element_set_state(pipeline, GST_STATE_PLAYING);

g_print("Running\n");

/* start to loop */

g_main_loop_run(loop);

/* quit loop and return */

g_print("Returned, stopping playback\n");

gst_element_set_state(pipeline, GST_STATE_NULL);

gst_object_unref(GST_OBJECT(pipeline));

return 0;
```

## 7 3A Function integration

The sensor output is Bayer Raw which is converted to YUV format application case after ISP processing, later need to use ISP's 3A function tuning IQ. IQ tuning requires customers to submit an application to Rockchip via sales window, providing typical modules and machines to be debugged by Rockchip. Please consult sales for details.

The compilation, installation and use of the main 3A libraries in this chapter are described in the docs/Develop reference documents/CAMERA/

"camera\_engine\_rkisp\_user\_manual\_v1.0.pdf" document published with Linux SDK. Please read this document first, no detailed explanation will be given here.

Finally, an xml file is generated for sensor (including lens) (assuming it is named OV5695.xml). At the same time, four so libraries will be provided which is generated by the camera\_engine\_rkisp project and located in the external directory<sup>[1]</sup>, Buildroot will automatically copy the four libraries to the corresponding directory, If there is no 3A library in Debian, please install it by yourself.

- OV5695.xml: 3A tuning IQ file. Please put it in the /etc/files/ directory. The etc/init.d/S50link\_iq script in buildroot will match the name of the sensor connected by ISP after booting, match the xml of the same name in the /etc/files/ directory, and create a link file cam\_iq.xml, for squash read-only file systems, script is invalid.
- librkisp.so: The main function of core engine is to obtain driving data stream and implement upper layer frame parameter control, such as 3A mode. The 3A statistics are obtained from ISP driver, and 3A library is called to implement 3A adjustment. The class interface provided for upper layer is DeviceManager which is saved in a /usr/lib/ directory on development boards.
- librkisp\_aec.so: The auto-exposure library implemented by RK is implemented as a dynamic loading library with a standard interface, which is saved in /usr/lib/rkisp/ae/ directory on development boards.
- librkisp\_af.so: The autofocus library implemented by RK is implemented as a dynamic loading library with a standard interface, which is saved in /usr/lib/rkisp/af/ directory of development boards.

---

<sup>1</sup> [1] If there is no rkisp\_demo in user's Linux SDK, please update or request the source code from FAE.

- `librkisp_awb.so`: The white balance library implemented by RK is implemented as a dynamic load library with a standard interface. Which is saved in `/usr/lib/rkisp/awb/` directory on development boards.

How applications calls 3A related functions, can also refer to the docs/Develop reference documents/CAMERA/ "camera\_engine\_rkisp\_user\_manual\_v1.0.pdf" released with Linux SDK. Simple demo, you can also refer to [Applications development and demo](#).

## 7.1 Applications development and demo

There is an external/camera\_engine\_rkisp repository with the Linux SDK released, the `camera_engine_rkisp/tests/rkisp_demo.c` simply uses v4l2 interface to configure device and simply calls 3A interface. Please refer to the source code directly.

Applications development, you can also directly refer to v4l2-utils source package (`libv4l-1.14.1/utils/v4l2-ctl`), the the so provided by which can also be used directly.

Or simply refer to the official website <https://linuxtv.org/downloads/v4l-dvb-apis-new/uapi/v4l/v4l2.html>

Note: The above buff type of the official website application only supports `V4L2_BUF_TYPE_VIDEO_CAPTURE`, and the buff type used by RKisp driver layer is `V4L2_BUF_TYPE_VIDEO_CAPTURE_MPLANE` which is used for video capture devices in multi-plane storage format, so the buff of application layer also has to match this type, and `rkisp_demo.c` and `v4l2-ctl` also add this type.

## 7.2 Gstreamer-1.0 3A plug-in

Rockchip has integrated 3A function into plug-in. The above "camera\_engine\_rkisp\_user\_manual\_v1.0" document described the use of 3A library and the included gstreamer plug-in (`libgstrkisp.so`) in details.

A new plug-in `rkv4l2src` based on gstreamer-1.14 has been wrote by Rockchip. The project is located in `external/gst-plugins-rockchip`. The `rkv4l2src` is a simple elements plug-in which collects data based on v4l2 protocol and adds 3A function provided by `camera_engine_rkisp`. This plug-in can be run under Buildroot and Debian (gstreamer upgrade 1.14).

1. Whether it is Buildroot or Debian, you must first confirm whether the 3A library exists. For rkisp1 driver, there are four 3A libraries: librkisp.so, librkisp\_aec.so, librkisp\_af.so, librkisp\_awb.so.

2. Storage path of Gstreamer plugin of Buildroot and Debian are different, Buildroot is stored in /usr/lib/gstreamer-1.0/libgstrkv4l2.so, Debian is stored in /usr/lib/aarch64-linux-gnu/gstreamer-1.0/libgstrkv4l2.so. After confirming that libgstrkv4l2.so exists, you can view the plugin details through `gst-inspect-1.0 rk4l2src`

```
gst-inspect-1.0 rk4l2src
```

```
[root@rk3326_64:/]# gst-inspect-1.0 rk4l2src
Factory Details:
Rank                primary (256)
Long-name           Rockchip Video (video4linux2) Source
Klass               Source/Video
Description         Reads frames from a Rockchip Video4Linux2 device
Author              Leo Wen <leo.wen@rock-chips.com>

Plugin Details:
Name                rk4l2
Description         Rockchip elements for Video 4 Linux
Filename            /usr/lib/gstreamer-1.0/libgstrkv4l2.so
Version             1.1.0
License             GPL
Source module       gst-plugins-rockchip
Binary package      GStreamer Plug-ins source release
Origin URL          Unknown package origin

GObject
+----GInitiallyUnowned
  +----GstObject
    +----GstElement
      +----GstBaseSrc
        +----GstPushSrc
          +----GstRKV4l2Src
```

Figure 5 rk4l2src plug-in information

3, After confirming that v4l2src can be previewed, you can test 3A plugin preview directly with `gst-launch-1.0`.

```
gst-launch-1.0 rk4l2src device=/dev/video1 xml-path=/etc/cam_iq.xml ! video/x-raw,format=NV12,width=640,height=480,framerate=30/1 ! videoconvert ! kmssink
xml-path=/etc/cam_iq.xml: Specify 3A xml file, the default path is /etc/cam_iq.xml
```

7.3 Media device development demo

7.4 Video device development demo

7.5 V4l-subdev device development demo



## 8 Rk-isp10 driver introduction

Rk-isp10 does not use media-controller and async sub device, but supports vb2 and v4l2 interfaces. And the rk-isp10 driver integration and the most simplified sensor development. For rk-isp10 (the other name is cif-isp10) driver, please refer to "CIF\_ISP10\_Driver\_User\_Manual\_v1.0.pdf" and "RK\_ISP10\_Camera\_User\_Manual\_v2.2.pdf" released with Linux SDKs.

It mainly introduces the difference between rkisp1 and rk-isp10 here.

First, they are different driver implementations of the same hardware IP.

RKISP1 is based on media controller, async sub device, vb2 and v4l2 interfaces. RK-ISP10 does not have a media controller and async sub device. Therefore, RKISP1 can be considered to provide a more rich and free pipeline setting, while RK-ISP10 provides users with the simplest and quickest use.

RK-ISP10 combines CIF and ISP into one driver. The CIF and ISP described in this document are independent of each other.

RK-ISP10 has a set of sensor-driven frameworks, the code is located at `drivers/media/i2c/soc_camera/rockchip/`. The CIF and ISP described in this document use the drivers that match async sub device in `drivers/media/i2c/` directory.

The Rkisp1 driver coding style is more pithily, and the number of lines of code is only half that of rk-isp10.