



Manual HR CoaXPress

hr25*CX, hr120*CX, hr342*CX

Company Information

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This Operation Manual is based on the following standards:
DIN EN 62079, DIN EN ISO 12100, ISO Guide 37, DIN ISO 3864-2,
DIN ISO 3864-4, DIN ISO 16016:2002-5

This Operation Manual contains important instructions for safe and efficient handling of SVCam Cameras (hereinafter referred to as „camera“). This Operating Manual is part of the camera and must be kept accessible in the immediate vicinity of the camera for any person working on or with this camera.

Read carefully and make sure you understand this Operation Manual prior to starting any work with this camera. The basic prerequisite for safe work is compliant with all specified safety and handling instructions.

Accident prevention guidelines and general safety regulations should be applied.

Illustrations in this Operation Manual are provided for basic understanding and can vary from the actual model of this camera. No claims can be derived from the illustrations in this Operation Manual.

The camera in your possession has been produced with great care and has been thoroughly tested. Nonetheless, in case of any complaint, please contact your local SVS-VISTEK distributor. You will find a list of distributors in your area on www.svs-vistek.com

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1 Legal Information

Information given within the manual accurate as to: February 13, 2019, errors and omissions excepted.

These products are designed for industrial applications only. Cameras from SVS-Vistek are not designed for life support systems where malfunction of the products might result in any risk of personal harm or injury. Customers, integrators and end users of SVS-Vistek products might sell these products and agree to do so at their own risk, as SVS-Vistek will not take any liability for any damage from improper use or sale.



Europe

This camera is CE tested, rules of EN 55022:2010+AC2011 and EN61000-6-2:2005 apply.

The product is in compliance with the requirements of the following European directives:

2014/30/EU	Electromagnetic compatibility (EMC)
2011/65/EU	Restriction of the use of certain hazardous substances in electrical and electronic equipment (RoHS)

All SVS-VISTEK cameras comply with the recommendation of the European Union concerning RoHS Rules



USA and Canada

This device complies with part 15 of the FCC Rules. Operation is subject to the following conditions: (1) This device may not cause harmful interference, and (2) this device must accept any interference received, including interference that may cause undesired operation.

This equipment is compliant with Class A of CISPR 32. Warning: In a residential environment this equipment may cause radio interference. This equipment has been tested and found to comply with the limits for a Class A digital device, pursuant to part 15 of the FCC Rules.

It is necessary to use a shielded power supply cable. You can then use the "shield contact" on the connector which has GND contact to the camera housing. This is essential for any use. If not done and camera is destroyed due to Radio Magnetic Interference (RMI) WARRANTY is void.

- > US/UK and European power line adapter can be delivered. Otherwise use filtered and stabilized DC power supply
- > Shock & Vibration Resistance is tested: For detailed Specifications refer to Specification

2 Getting Started

2.1 Connect the camera

Before connecting your camera to power, make sure your data cable is connected properly. Always connect data cable before power.



CAUTION! – This camera does not support hotplugging

1. First, connect the data cable.
2. Then connect power supply.

Connect the power supply with the Hirose connector. When using your own power supply (voltage range 10 -25 V DC) see also [Hirose 12-](#) pin layout of the power connector. For power input specifications refer to [specifications](#).

2.2 Camera Status LED codes

Latest SVCam CoaXPress cameras provides status information per CXP line. A LED is located close to each CXP connector and will indicate the current status for the appropriate CXP line. The LEDs will change color and rhythm.

The meaning of the CXP line blinking codes is depending whether PoCXP is used and translates as follows:

LED flash code	PoCXP	Indication
	yes	system booting
	yes / no	nothing connected
	yes	connection detection
	no	connection detection
	yes	device / host incompatible
	no	device / host incompatible
	yes	PoCXP overcurrent
	yes / no	connected, no data
	yes / no	connected, waiting for event
	yes / no	connected, data transfer
	yes / no	data transfer error (e.g. CRC)
	yes / no	connection test packages
	yes / no	compliance test mode enabled
	yes / no	system error

2.3 Software

Further information, documentations, release notes, latest software and application manuals can be downloaded in the download area on SVS-Vistek's [download area](#). Depending on the type of camera you bought, several software packages apply.

2.3.1 Software for CoaXPress

CoaXPress is a well defined standard protocol. As there is the need for a grabber, the grabber manufacturer is providing software for CoaXPress cameras.

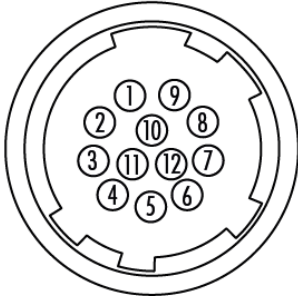
Please refer to the manufacturer of your CoaXPress grabber device. With this software you should be able to access all CoaXPress cameras.

3 Connectors

3.1 Input / output connectors

Hirose™ 12Pin

The Hirose connector provides the connectors to power, inputs and outputs. For detailed information about switching lights from inside the camera, refer to [strobe control](#).

Hirose 12 Pin	
	
1	VIN – (GND)
2	VIN + (10V to 25V DC)
3	IN4 (RXD RS232)
4	OUT4 (TXD RS232)
5	IN1 (0-24V)
6	IN2 (0-24V)
7	OUT1 (open drain)
8	OUT2 (open drain)
9	IN3 + (opto In +)
10	IN3 – (opto In –)
11	OUT3 (open drain)
12	OUT0 (open drain)

Specification

Type	HR10A-10R-12P
Mating Connector	HR10A-10P-12S

4 The HR Camera Series

Focusing on details

The SVCam HR series is a series of industrial machine vision cameras featuring especially on very high image resolutions and interface high speed without compromising on image quality. Camera sensors and interfaces are built to deliver maximum sensor and interface bandwidth.

With this kind of high resolution sensors being already very large, the HR series comes with an M58 mount with the possibility to adapt for any kind of lens.

High end CCD and CMOS image sensors with high resolutions permit swift and effortless capture of a wide field of view, making this camera series your prime choice for demanding applications such as optical metrology, quality monitoring, wide field surveillance or traffic monitoring.

CoaXPress features

CoaXPress (CXP) is the latest development regarding high speed high volume data transfer for imaging. The interface needs a frame grabber. The CoaXPress standard is very precise and is incorporating a lot of features like power-over-CoaXPress (PoCXP) already in the standard definition.

Main advantages of CXP are

- > 6.25 Gbit/s transfer rate (CXP-6) per line
- > Lines can be teamed: a 4-line aggregation delivers up to 25Gbit/s
- > Provides data and power on a single line
- > Very thin and flexible cables
- > 25m data cable supported
- > Extremely low latency times

Please refer to the manufacturer of your CoaXPress frame grabber for software. The frame grabber should come with viewer and grabbing software as well with its own SDK.

Please note, in case you use the [4IO PWM](#) outputs to drive your lights, you need an external power supply as PoCXP is unable to deliver the high currents requested by the lights.

5 Feature description

This chapter covers features of SVCam cameras. Not every feature might be supported by your specific camera model. For information about the features of your specific model, please refer to the specifications area with your exact model.

5.1 Basic Understanding

5.1.1 Global shutter

The shutter is describing the functionality of exposing the light sensitive pixels of the sensor to light for a limited time. With global shutter all pixels are exposed to light at the same time for the same time.

All pixel will be exposed to light at the same starting point, and all pixel light exposure will stop at the same time. Fast moving objects will be captured without showing movement distortion, except motion blur if the moving object is so fast that the same point of the object covers different pixels at start and end while exposing.

Using flash with global shutter is straight forward: just make sure your flash is on while shutter is open, thus all pixels are exposed to light the same time. You might flash at any time within exposure time.

5.1.2 Rolling Shutter

Rolling shutter is a method of reading out a CMOS sensor, where the whole scene is scanned line after line very rapidly. Rolling shutter cameras in general are more sensitive in their light response than global shutter ones.

Despite the speed of scanning one line after the other („rolling“) is very high, it is important to note that the instant of imaging a single line will be different to the point of time of the next line imaging. As this works out without any effect in the final image with still sceneries, with moving objects you get geometric distortions (see example of rotating propeller), showing fast moving structures in an predictable, in the first moment yet surprising way.

As it takes some time to read out a whole sensor (and the whole sensor has always to be read out!) you need to make sure that light conditions are stable while reading the sensor. This restriction applies especially to using PWM driven lights or flash lighting with rolling shutter. Unstable light conditions will result in a horizontal line structured pattern noise.



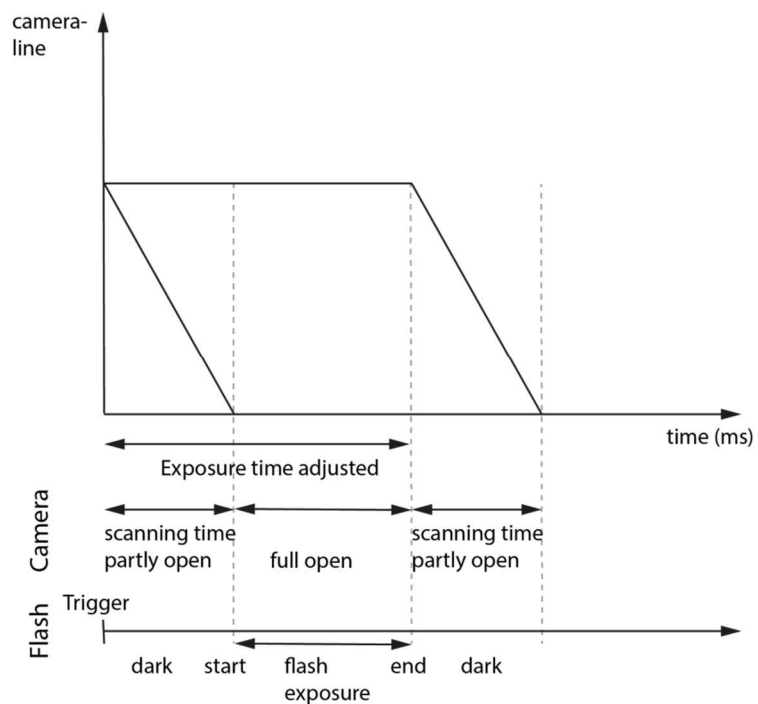
propeller w/ rolling shutter artifacts

Light control with rolling shutter

Scanning sensor lines takes time. Not all sensor lines are sensitive to light at the same time. Make sure your light is ON as long any pixel are going to be exposed.

There are 2 general guidelines for flashing with rolling shutter:

1. Make sure your light is ON and stable **the whole** period of time while scanning/exposing. Minimum flash time is scanning time plus exposure time. In this case, while flashing you will get geometric distortions as mentioned above. Exposure will be determined by camera exposure time and light intensity
2. If flash time is less than scanning time then exposure time has to be at least scanning time + flash time, with a delay of scanning time. In other words, your exposure time will be scanning time plus flash time, while you use a flash delay of scanning time. Thus flash release will start after the delay of scanning time, as soon the sensor is fully open. You should keep the object in total darkness while the first scanning time. In this case, as all lines are sensitive to light at the same time after the first scan time, flashing time can be as short as you like. You will not see the typical geometric rolling shutter distortions as shown above. Imaging will be similar to global shutter. Exposure will be determined by flash time/intensity.



Rolling shutter lines light sensitivity versus time

As shown here, after triggering only part of the sensor is sensitive to light (scanning time). As soon as scanning time has finished, all pixels are sensitive to light, the sensor is fully open. While being fully open this is the time where flashing should happen. In the final scanning time, less and less pixels are sensitive to light until the sensor light sensitivity will finish.

Flashing of rolling shutter sensors is significantly different to global shutter flashing!

PWM lights with rolling shutter

PWM (Pulse Width Modulated) powered light or dimmed light is run at a fixed frequency. Experience teaches us this frequency might be less stable than expected. Unstable frequency might show up as unstable light, creating noise/line structures in the final rolling shutter image (in global shutter images the whole image is just more/less bright)

As a rule of thumb, make sure your PWM lighting frequency is **at least** double or triple the bitdepth of your image (e.g. 8bit image = 256, this means your PWM has to be switched at least $256*2=512$ times) while exposing. If exposure time is 5ms,

Required minimum PWM freq = $5\text{ms}/512 \sim 10\mu\text{s} \sim 100\text{kHz}$

If you have the possibility to use a strobe controller or dimmer with linear regulation, this might be preferable on short exposure times.

Rolling shutter limitations

Due to the principles of rolling shutter, some standard features of SVS-Vistek cameras are not applicable.

- > External exposure control (expose while trigger signal active) does not make sense with rolling shutter
- > ROI with rolling shutter
With rolling shutter the whole sensor has to be read out – always. That means applying ROI will reduce the amount of final data being transmitted out of the camera (and the framerate might rise, due to the limited bandwidth of the interface). Nonetheless, the maximum achievable framerate with applied ROI will be the maximum framerate of the sensor reading the full sensor area (internal full sensor speed), please refer to relating sensor specs.

5.1.3 Exposure

See various exposure and timing modes in chapter: [Basic capture modes](#).

Combine various exposure timings with PWM LED illumination, refer to [sequencer](#).

Setting Exposure time

Exposure time can be set by width of the external or internal triggers or programmed by a given value.

5.1.4 Exposure speed

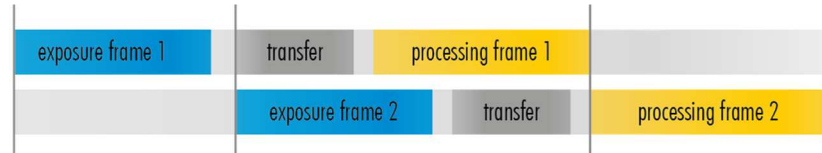
Frames per second, or frame rate describes the number of frames output per second (1/ frame time). Especially GigE and USB cameras cannot guarantee predictable maximum framerates with heavy interface bus load.

Maximum frame rate might depend on

- > Pixel clock
- > Image size
- > Tap structure
- > Data transport limitation
- > Processing time

5.1.5 Acquisition and Processing Time

The camera has to read the sensor, process the data to a valid image and transfer this to the host computer. Some of these tasks are done in parallel. This implies the data transfer does not end immediately after end of exposure, as the image has to be processed and transferred after exposure.



On the other side, while processing and transferring the image the sensor might capture already the next frame.

5.1.6 Auto exposure

Auto Luminance or auto exposure automatically calculates and adjusts exposure time and gain, frame-by-frame.

The auto exposure or automatic luminance control of the camera signal is a combination of an automatic adjustment of the camera exposure time (electronic shutter) and the gain.

The first priority is to adjust the exposure time and if the exposure time range is not sufficient, gain adjustment is applied. It is possible to pre-define the range (min. / max. -values) of exposure time and of gain.

The condition to use this function is to set a targeted averaged brightness of the camera image. The algorithm computes a gain and exposure for each image to reach this target brightness in the next image (control loop). Enabling this functionality uses always both – gain and exposure time.

Limitation

As this feature is based on a control loop, the result is only useful in an averaged, continuous stream of images. Strong variations in brightness from one image to next image will result in a swing of the control loop. Therefore it is not recommended to use the auto-luminance function in such cases.

5.1.7 Bit-Depth

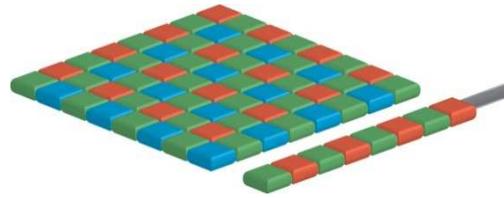
Values of brightness are internally represented by numbers. The number of bits for brightness representation is limiting the number of colour values that can be represented. Bit depth defines the maximum unique colors or grey levels in an image.

No of grey values = $2^{\text{bit depth}}$

All SVCam models support 8-bit format. In most cases, the sensor itself is limiting maximum bit depth. Refer to specifications whether your model is supporting higher bit depth.

5.1.8 Color

Color cameras are identical to the monochrome versions. The color pixels are transferred in sequence from the camera, in the same manner as the monochrome, but considered as “raw”-format.



CCD with Bayer Pattern

The camera sensor has a color mosaic filter called “Bayer” filter pattern named after the person who invented it. The pattern alternates as follows:

E.g.: First line: GRGRGR... and so on. (R=red, B=blue, G=green)
 Second line: BGBGBG... and so on. Please note that about half of the pixels are green, a quarter red and a quarter blue. This is due to the maximum sensitivity of the human eye at about 550 nm (green). De-Bayering is not done in the camera, it has to be done in the client software. See SDK functions as well. Not all sensors do have the same sequence of color. The GenlCam property **PIXELCOLORFILTER** does indicate the sequence of the color pixels when reading color images.

Using color information from the neighboring pixels the R, G and B values of each pixel is interpolated by software. E.g. the red pixel does not have information of green and blue components. The performance of the image depends on the software used.

Camera Link frame grabber need information of the sequence order of the colours. The order depends on sensor type. USB3 and GigE cameras provide this in their XML file.



NOTICE

It is recommended to use an IR cut filter for color applications

White Balance

The human eye adapts to the definition of white depending on the lighting conditions. The human brain will define a surface as white, e.g. a sheet of paper, even when it is illuminated with a bluish light.

White balance of a camera does the same. It defines white or removes influences of a color based on a non-white illumination.

5.1.9 Resolution

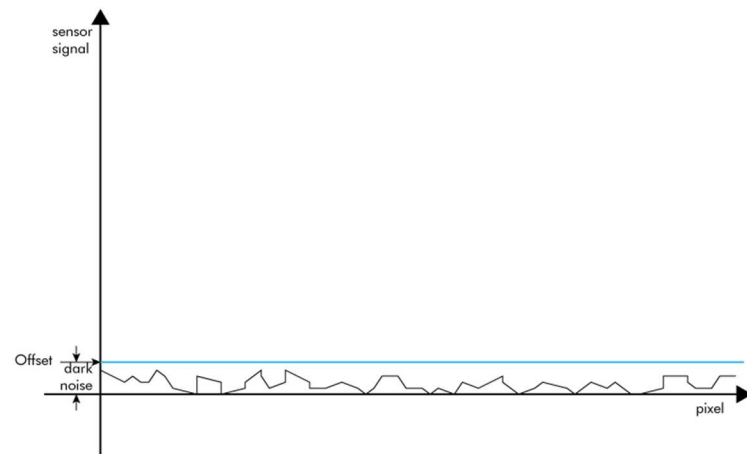
As mentioned in the specifications, there is a difference between the numerical sensor resolution and the camera resolution. Some pixels towards the borders of the sensor will be used only internally to calibrate sensor values (“dark pixels”). The amount of dark current in these areas is used to adjust the [offset](#).

For calculating image sizes, the maximum camera resolution is determining maximum image resolution. See [specifications](#) of your model.

5.1.10 Offset

For physical reasons the output of a sensor will never be zero, even the camera is placed in total darkness or simply closed. Always there will be noise or randomly appearing electrons that will be detected as a signal (dark noise: noise generated without light exposure).

To avoid this dark noise to be interpreted as a valuable signal, an offset will be set.



dark noise cut off by the offset

Most noise is proportional to temperature. To spare you regulating the offset every time the temperature changes. A precedent offset is set by the camera itself. It references certain pixels that never were exposed to light as black. So the offset will be set dynamically and conditioned to external influences.

The offset can be limited by a maximum bit value. If higher values are needed, try to set a look up table.

In case of multi-tap CCD sensors, offset can be altered for each tap separately (see tap balancing).

5.1.11 Gain

Setting gain above 0 dB (default) is a way to boost the signal coming from the sensor. Especially useful for low light conditions. Setting gain amplifies the signal of individual or binned pixels before the ADC. Referring to photography adding gain corresponds to increasing ISO. Increasing gain will increase noise as well.

add 6 dB	double ISO value
6 dB	400 ISO
12 dB	800 ISO
18 dB	1600 ISO
24 dB	3200 ISO

Table of dB and corresponding ISO value



NOTICE

Gain also amplifies the sensor's noise. Therefore, gain should be last choice for increasing image brightness. Modifying gain will not change the camera's dynamic range.



noise caused by too much gain

Auto Gain

For automatic adjustment of Gain please refer to [auto exposure](#).

When using autogain with steps of gain the non-continuous gain adjustment might be visible in final image. Depending on your application it might be preferable to use fixed gain values instead and modify exposure with exposure time.

5.1.12 Flip Image

Images can be mirrored horizontally or vertically. Image flip is done inside the memory of the camera, therefore not increasing the CPU load of the PC.



original image



horizontal flip



vertical flip

5.1.13 Binning

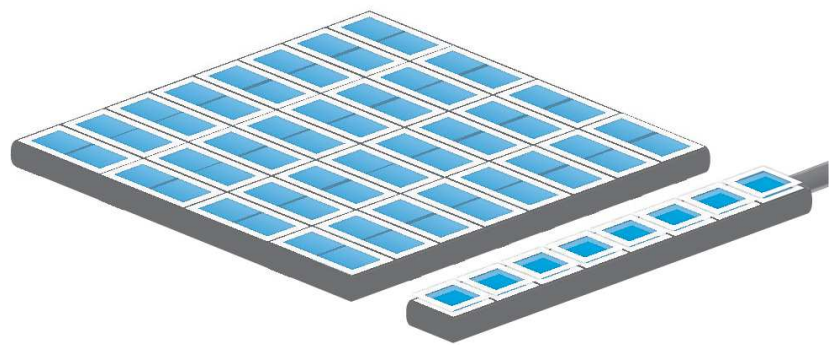
Binning provides a way to enhance dynamic range, but at the cost of lower resolution. Binning combines electron charges from neighboring pixels directly on the chip, before readout.

Binning is only used with monochrome CCD Sensors. For reducing resolution on color sensors refer to [decimation](#).

On CMOS sensors, binning will not affect image quality. In any case, binning will reduce the amount of pixel data to be transferred.

Vertical Binning

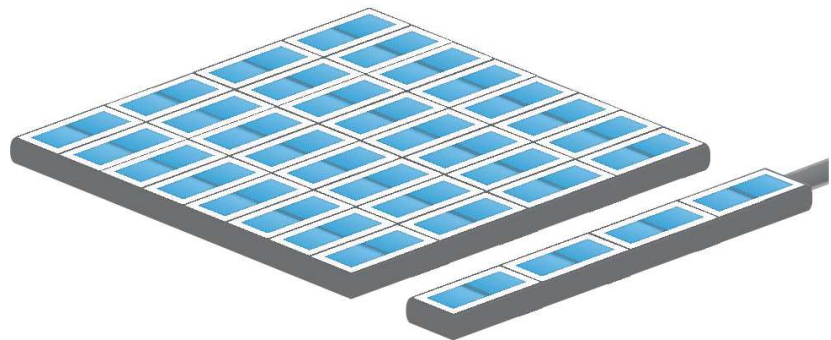
Accumulates vertical pixels.



Vertical binning

Horizontal Binning

Accumulates horizontal pixels.

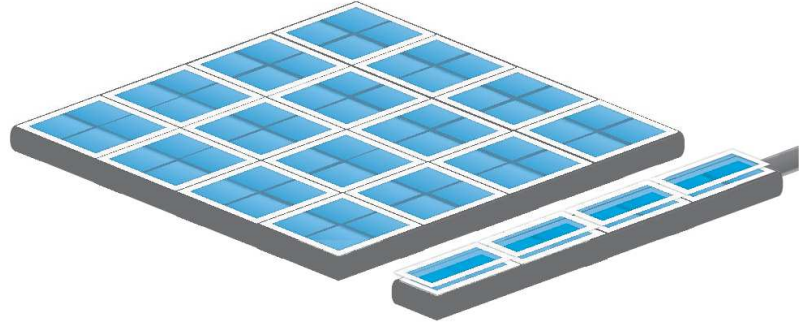


Horizontal binning

2×2 Binning

A combination of horizontal and vertical binning.

When DVAL signal is enabled only every third pixel in horizontal direction is grabbed.



2x2 binning

5.1.14 Decimation

For reducing width or height of an image, decimation can be used. Columns or rows can be ignored.

Refer to AOI for reducing data rate by reducing the region you are interested in.



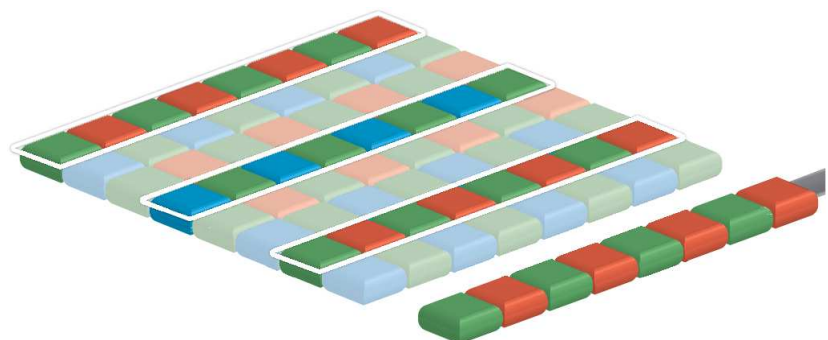
Horizontal decimation



Vertical decimation

Decimation on Color Sensors

The Bayer pattern color information is preserved with 1/3 horizontal and vertical resolution. The frame readout speed increases approx. by factor 2.5.



Decimation on color sensors

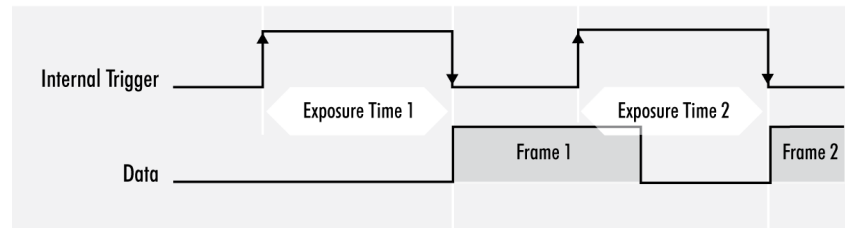
5.2 Camera Features

5.2.1 Basic Capture Modes

Free Running

Free running (fixed frequency) with programmable exposure time. Frames are readout continuously and valid data is indicated by LVAL for each line and FVAL for the entire frame.

Mode 0: Free Running with Programmable Exposure Time



There is no need to trigger the camera in order to get data. Exposure time is programmable via serial interface and calculated by the internal logic of the camera.



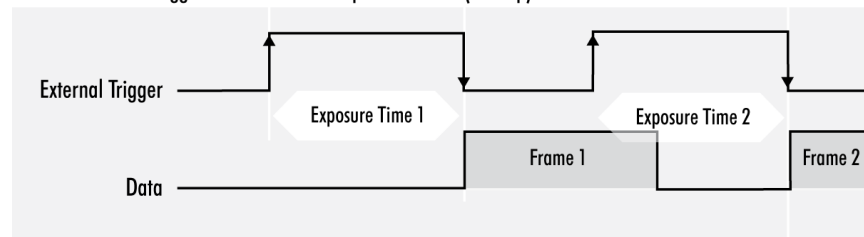
NOTICE

The fundamental signals are:
Line Valid: LVAL, Frame Valid: FVAL,
And in case of triggered modes: trigger input.

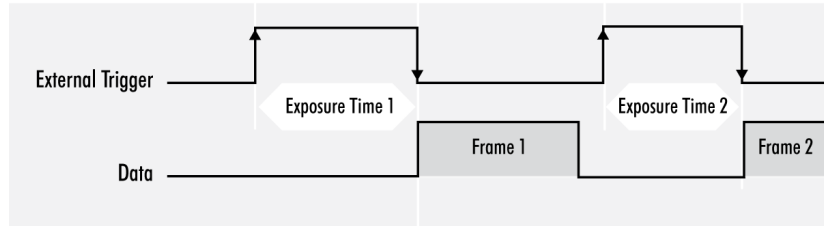
Triggered Mode (pulse width)

External trigger and pulse-width controlled exposure time. In this mode the camera is waiting for an external trigger, which starts integration and readout. Exposure time can be varied using the length of the trigger pulse (rising edge starts integration time, falling edge terminates the integration time and starts frame read out). This mode is useful in applications where the light level of the scene changes during operation. Change of exposure time is possible from one frame to the next.

Mode 1: External Trigger with Pulse Width Exposure Control (overlap)



Exposure time of the next image can overlap with the frame readout of the current image (rising edge of trigger pulse occurs when FVAL is high). When this happens: the start of exposure time is synchronized to the falling edge of the LVAL signal.

Mode 1: External Trigger with Pulse Width Exposure Control (non overlap)

When the rising edge of trigger signal occurs after frame readout has ended (FVAL is low) the start of exposure time is not synchronized to LVAL and exposure time starts after a short and persistent delay.

The falling edge of the trigger signal must always occur after readout of the previous frame has ended (FVAL is low).

Software Trigger

Trigger can also be initiated by software (serial interface).



NOTICE

Software trigger can be influenced by jitter. Avoid Software trigger at time sensitive applications

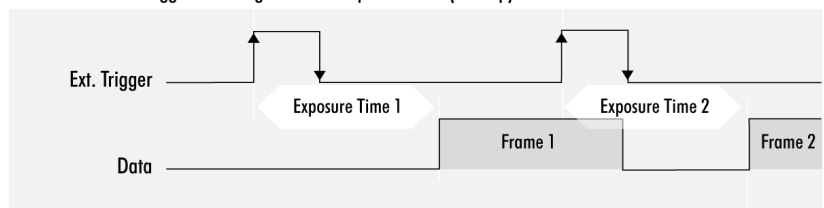
External Trigger (Exposure Time)

External trigger with programmable exposure time. In this mode the camera is waiting for an external trigger pulse that starts integration, whereas exposure time is programmable via the serial interface and calculated by the internal microcontroller of the camera.

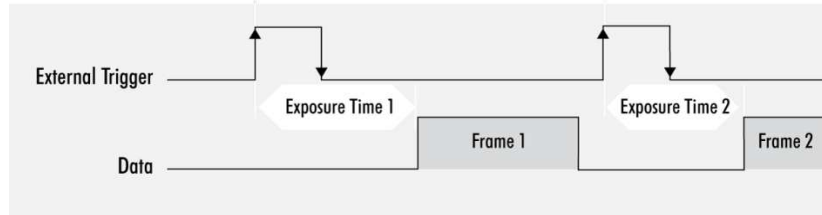
At the rising edge of the trigger the camera will initiate the exposure.

The software provided by SVS-Vistek allows the user to set exposure time e.g. from 60 μ s 60 Sec (camera type dependent).

Exposure time of the next image can overlap with the frame readout of the current image (trigger pulse occurs when FVAL is high). When this happens, the start of exposure time is synchronized to the negative edge of the LVAL signal (see figure)

Mode 2: External Trigger with Programmable Exposure Time (overlap)

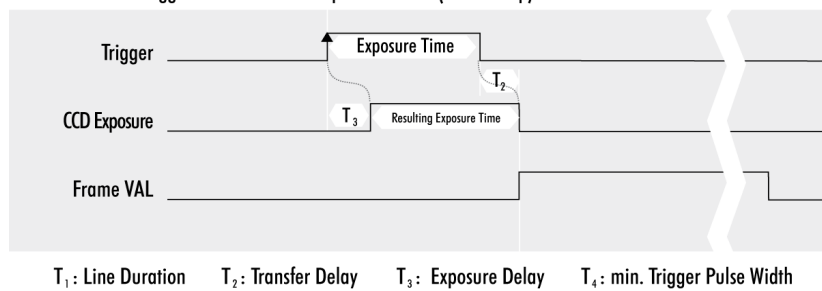
When the rising edge of trigger signal occurs after frame readout has ended (FVAL is low), the start of exposure time is not synchronized to LVAL and exposure time starts after a short and persistent delay.

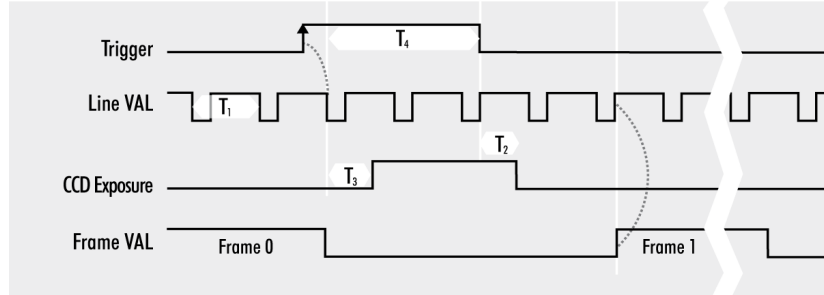
Mode 2: External Trigger with Programmable Exposure Time (non overlap)

Exposure time can be changed during operation. No frame is distorted during switching time. If the configuration is saved to the EEPROM, the set exposure time will remain also when power is removed.

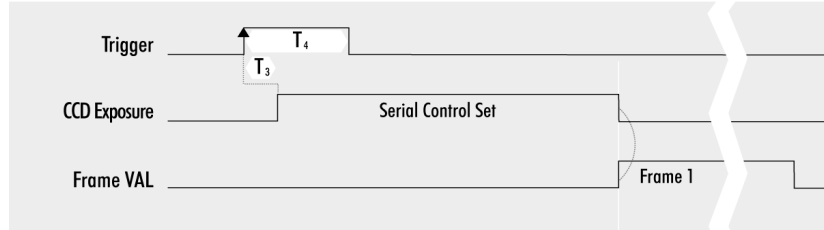
Detailed Info of External Trigger Mode

Dagrams below are equivalent for CCD and CMOS technique.

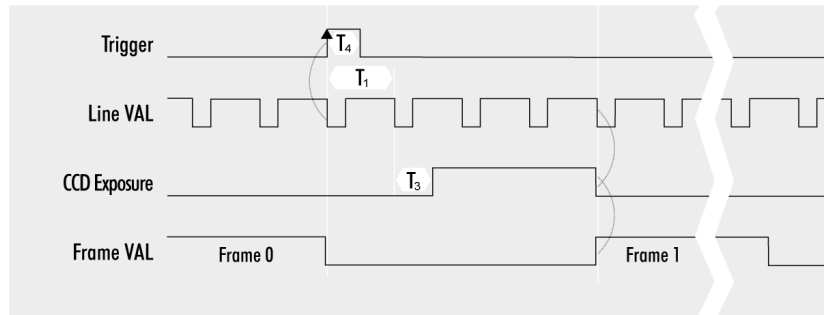
Mode 1: External Trigger with Pulse Width Exposure Control (non overlap)

Mode 1: External Trigger with Pulse Width Exposure Control (overlap)


T_1 : Line Duration T_2 : Transfer Delay T_3 : Exposure Delay T_4 : min. Trigger Pulse Width

Mode 2: External Trigger with Programmable Exposure Time (non overlap)


T_1 : Line Duration T_2 : Transfer Delay T_3 : Exposure Delay T_4 : min. Trigger Pulse Width

Mode 2: External Trigger with Programmable Exposure Time (overlap)


T_1 : Line Duration T_2 : Transfer Delay T_3 : Exposure Delay T_4 : min. Trigger

5.2.2 hr120 trigger modes

The HR120xCX utilizes a CANON rolling shutter sensor and can be operated in 3 different modes.

hr120 trigger mode	max speed (fps)	sync	jitter
free run	9.3	no	n/a
precise mode triggered	4.6	yes	no
fast mode triggered	9.3	yes	max 1/fps

The camera is supporting free run and 2 triggerable operation modes ("precise mode" and "fast mode") which do have effects on camera speed and trigger timing (jitter). Due to sensor architecture, the sensor (rolling shutter) is not supporting to deliver an image immediately after trigger signal.

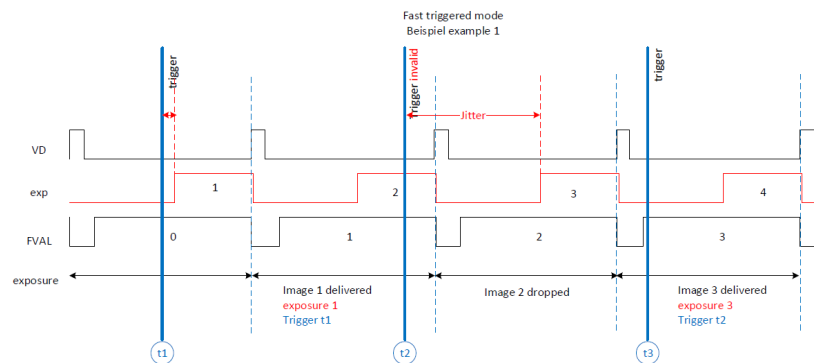
The camera can be set up in the SVCapture GenIcam tree with
Trigger mode -> [Free | Fast | Precise]

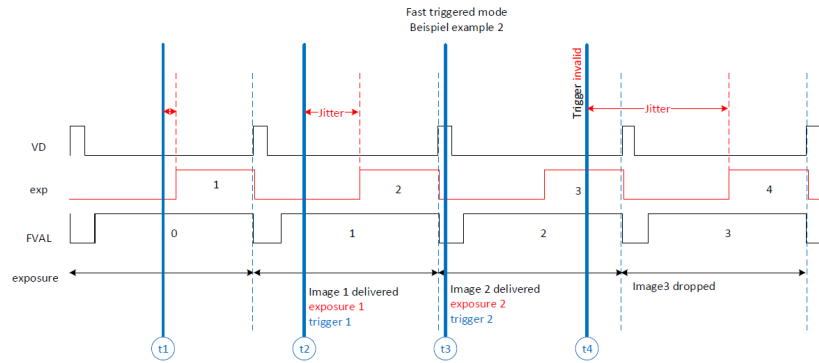
Free run mode

In free run, the camera is running full speed and the driver is delivering any arriving images to the software as soon the image is delivered. There is no sync to any external signal in free run mode.

Fast mode triggered

In fast triggered mode the sensor is running in its speed, taking internally images. Being triggered, the camera will finish current exposure operation and start a new exposure. The image of this (next) new exposure will be delivered as fast mode triggered image.





Both examples above demonstrate if the trigger signal is before exposure time, the camera will deliver a valid exposure OUT signal and the image of the frame cycle where the trigger signal was put.

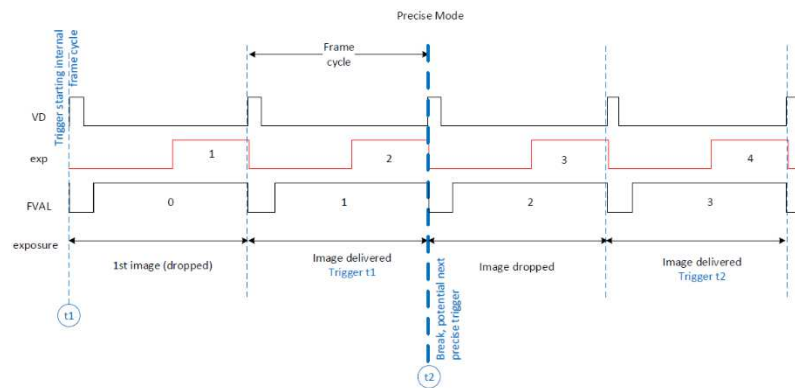
If the trigger arrives while exposure has already started the image of the current frame cycle is dropped. The trigger signal will initiate delivery of the following frame cycle's image.

As it is not possible to determine in advance the time difference between trigger impulse and start of the new image a timing jitter is the result. Given that, maximum jitter is 1/fps.

Precise mode triggered

Precise mode triggering gives you exact knowledge about the start of exposure. Precise mode trigger is requesting the camera to start with exposure, frame cycle starts with trigger. As the sensor has to set up before exposing, the first image cycle or frame is lost and the second image will be delivered. With a static frame cycle, the exposure of the second frame starts with a fixed delay of 1 frame.

Maximum imaging speed will be about half of fast mode triggered. Benefit is the exact knowledge of exposure start time.



5.2.3 System Clock Frequency

Default system clock frequency in almost every SVCam is set to 66.6 MHz. To validate your system frequency refer to: [specifications](#).

Using the system clock as reference of time, time settings can only be made in steps. In this example, the transfer rate is 66.7 MHz, thus resulting in steps of 15 ns.

$$t = \frac{1}{66.6 \text{ MHz}} = \frac{1}{66\,666\,666.6 \frac{1}{s}} = 15 \cdot 10^{-9} \text{ s} = 15 \text{ ns}$$



NOTICE

Use multiples of 15 ns to write durations into camera memory

5.2.4 Temperature Sensor

A temperature sensor is installed on the mainboard of the camera.

To avoid overheating, the temperature is constantly monitored and read. Besides software monitoring, the camera indicates high temperature by a red flashing LED. (See flashing LED codes)

5.2.5 LookUp Table

The LookUp Table Feature (LUT) lets the user define certain values to every bit value that comes from the ADC.

To visualize a LUT a curve diagram can be used, similar to the diagrams used in photo editing software.

The shown custom curve indicates a contrast increase by applying an S-shaped curve. The maximum resolution is shifted to the mid-range. Contrasts in this illumination range is increased while black values will be interpreted more black and more of the bright pixels will be displayed as 100 % white...

For further Information about curves and their impact on the image refer to our homepage: [Knowledge Base – LUT](#)

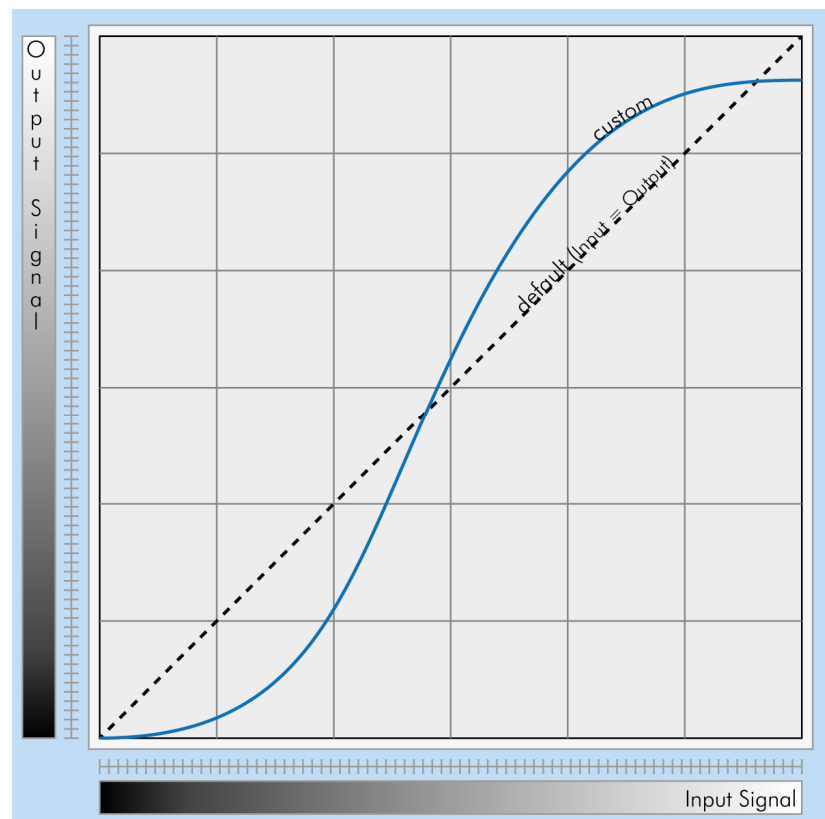


Figure 1: Custom LUT adding contrast to the midtones



NOTICE

LUT implementation reduces bit depth from 12 bit to 8 bit on the output.

Gamma Correction

Using the LookUp Table makes it also possible to implement a logarithmic correction. Commonly called Gamma Correction.

Historically Gamma Correction was used to correct the illumination behavior of CRT displays, by compensating brightness-to-voltage with a Gamma value between 1,8 up to 2,55.

The Gamma algorithms for correction can simplify resolution shifting as shown seen above.

Input & Output signal range from 0 to 1

$$\text{Output-Signal} = \text{Input-Signal}^{\text{Gamma}}$$

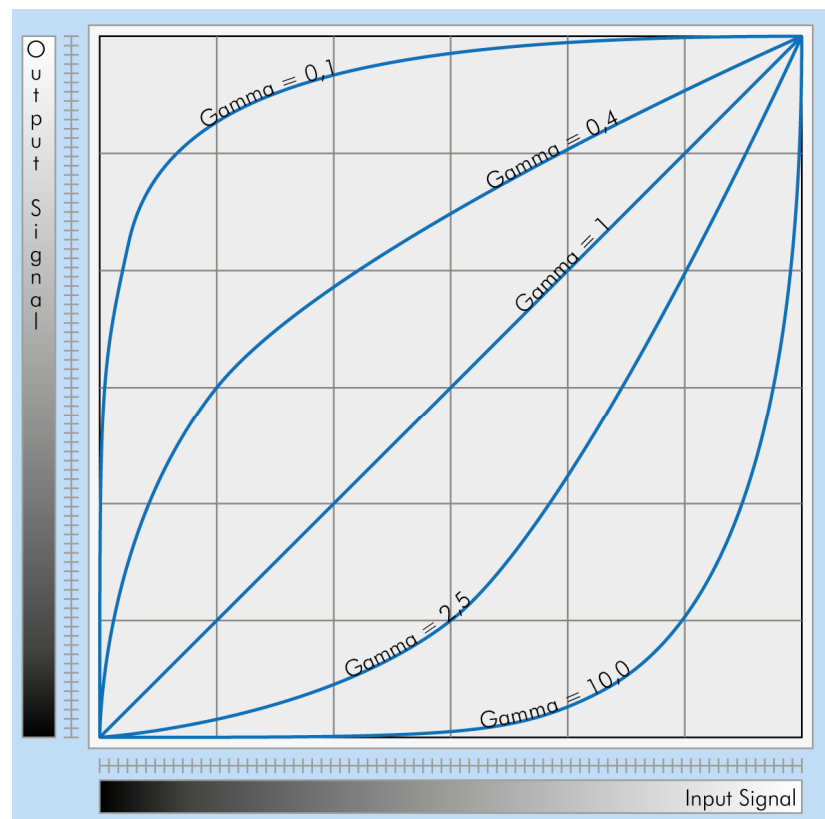


Figure 2: Several gamma curves comparable to a LUT

Gamma values less than 1.0 map darker image values into a wider range.

Gamma values greater than 1.0 do the same for brighter values.

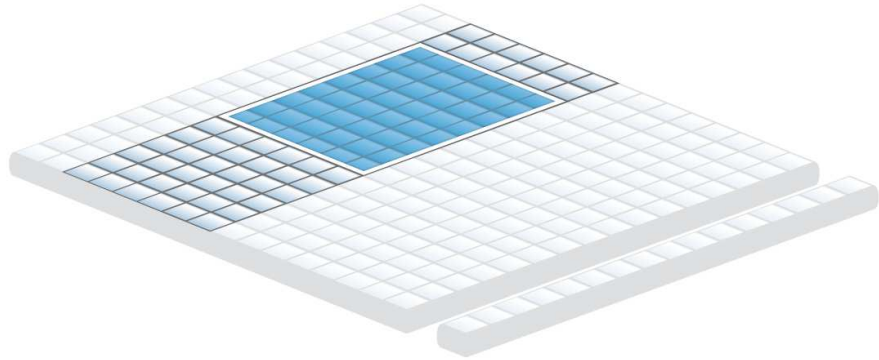


NOTICE

Gamma Algorithm is just a way to generate a LUT. It is not implemented in the camera directly..

5.2.6 ROI / AOI

In Partial Scan or Area-Of-Interest or Region-Of-Interest (ROI) -mode only a certain region of the sensor will be read.



AOI on a CCD sensor

Selecting an AOI will reduce the number of horizontal lines being read. This will reduce the amount of data to be transferred, thus increasing the maximum speed in term of frames per second.

With CCD sensors, setting an AOI on the left or right side does not affect the frame rate, as lines must be read out completely.

With CMOS Sensors, AOI can be selected as well. Please note, most CMOS sensors require the camera to read full horizontal sensor lines internally. Reducing horizontal size with AOI might result in limited fps speed gain.

5.2.7 Defect Pixel Correction

All image sensor have defect pixels in a lesser or greater extent. Type and number of defects determine the quality grade (quality classification) of the sensor.

Defect Pixel Correction is using information from neighboring pixels to compensate for defect pixels or defect pixel clusters (cluster may have up to five defect pixels).

Defect Pixels either be dark pixels, i.e. that don't collect any light, or bright pixels (hot pixel) that always are outputting a bright signal.

The amount of hot pixels is proportional to exposure time and temperature of the sensor.

By default, all known defect pixels or clusters are corrected by SVS-VISTEK as a factory default.

Under challenging conditions or high temperature environments defect pixel behaviour might change. This can be corrected.

- > A factory created defect map (SVS map), defying known defects, is stored in the camera.
- > A custom defect map can be created by the user. A simple txt file with coordinates has to be created. The user must locate the pixel defects manually.
- > The txt file can be uploaded into the camera. Beware of possible Offset!
- > Defect maps can be switched off to show all default defects, and switched back on to improve image quality.

Unlike Shading Correction, Defect Pixel Correction suppresses single pixels or clusters and reconstructs the expected value by interpolating neighboring pixel values. The standard interpolation algorithm uses the pixel to the left or to the right of the defect. This simple algorithm prevents high runtime losses.

More sophisticated algorithms can be used by software.

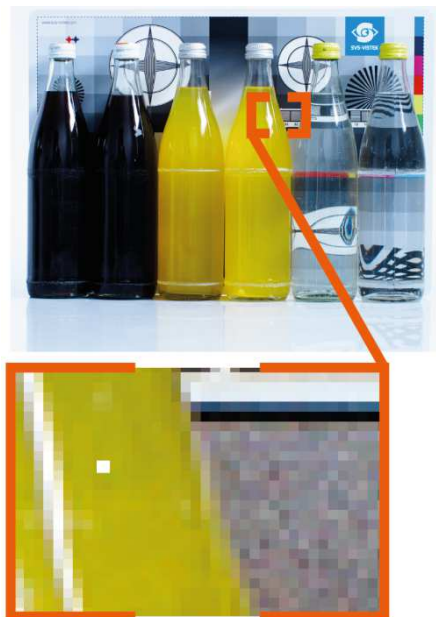
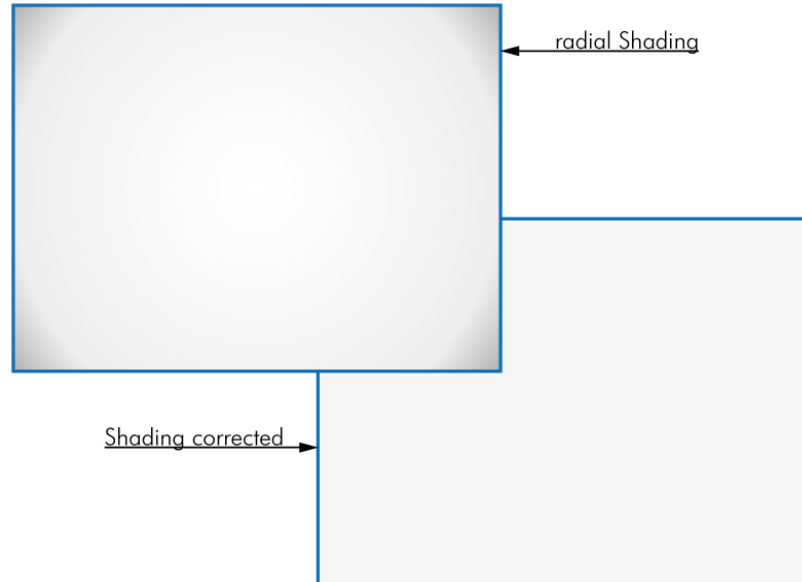


Figure 3: Illustration of a defect pixel

5.2.8 Shading Correction

The interactions between objects, illumination, and the camera lens might lead to a non-uniform flatfield in brightness. Shading describes the non-uniformity of brightness from one edge to the other or center towards edge(s).



Original and shading corrected image

This shading can be caused by non-uniform illumination, non-uniform camera sensitivity, vignetting of the lens, or even dirt and dust on glass surfaces (lens).

Shading correction is a procedure to create a flatfield image out of a non-uniform image regardless of the reasons of the non-uniformity. Before doing shading correction, make sure your lens is clean and in perfect condition. If the lens is not clean or the lighting not uniform, the algorithm tries to compensate these as well – resulting in a wrong shading table and visible artifacts, loss of details or local noise in the final image.

In theory there are several ways to correct shading:

- > IN THE HOST COMPUTER: SIGNIFICANT LOSS OF DYNAMIC RANGE, COLOUR RUPTURES
- > IN THE CAMERA, DIGITAL: BETTER (SMOOTHER) SHADING THAN ON THE COMPUTER SIDE (10 OR 12 BIT), LOSS OF DYN RANGE
- > IN THE CAMERA, ANALOG: CHANGE GAIN/OFFSET LOCALLY ON SENSOR TO GET OPTIMUM SHADING CORRECTION WITH ONLY SMALL CHANGES IN DYNAMIC RANGE

5.2.9 Shading Correction Tool

Images taken with shading correction will seem to have a perfectly balanced illumination. The original idea was to correct the shading of sensor and lens, but it can be used to correct shading of illumination (a non-homogenous illumination) as well.

Shading correction is not a replacement for correct illumination. It is important to have in mind that illumination shading correction might reduce dynamic range of the images taken. By using different gains and offsets on the sensor local noise might be less uniform. Structures in the reference image might lead to visible shading artifacts.

In contrary to any shading correction being done after image recording, the method described here will hardly affect the dynamic range of the image.

The task is done with shading maps. Being applied before final pixel quantization, a significant improvement in image quality is the result.

SVCamImgCorrTool (you might download this from the [SVS-Vistek download center](#)) will help you through this task.

5.3 I/O Features

5.3.1 GenICam

GenICam™ provides a generic programming interface to control all kinds of cameras and devices. Regardless of the interface technology (GigE Vision, USB3 Vision, CoaXPress, Camera Link, etc.) or implemented feature, the application programming interface (API) will always be the same. The SNFC makes sure the feature names are similar throughout the manufacturers, making it more easy to switch camera models.



The GenICam™ standard consists of multiple modules according to the main tasks to be solved:

- > GenApi: configuring the camera
- > SNFC: Standard Feature Naming Convention, a catalogue of standardized names and types for common device features
- > GenTL: transport layer interface, grabbing images
- > GenCP: generic GenICam control protocol
- > GenTL SFNC: recommended names and types for transport layer interface.

The GenICam properties are organized as a tree. Manufacturers can add more features.

With your SVCam, the GenICam tree does have some hardware related extensions, especially in the I/O sector. See the [Quick guide install](#) for a short introduction into SVS-Vistek's GenICam tree.

5.3.2 PWM

Pulse width modulation

Description of the function used within the sequencer or implemented by the pulseloop module

During Pulse Width Modulation, a duty cycle is modulated by a fixed frequency square wave. This describes the ratio of ON to OFF as duty factor or duty ratio.

Why PWM?

Many electrical components must be provided with a defined voltage. Whether it's because they do not work otherwise or because they have the best performance at a certain voltage range (such as diodes or LEDs).

Diode characteristic

Since LEDs have a bounded workspace, the PWM ensures a variable intensity of illumination at a constant voltage on the diodes.

In addition, the lifetime of a diode increases. The internal resistance is ideal in this area. The diode gets time to cool down when operated with a PWM in its workspace.

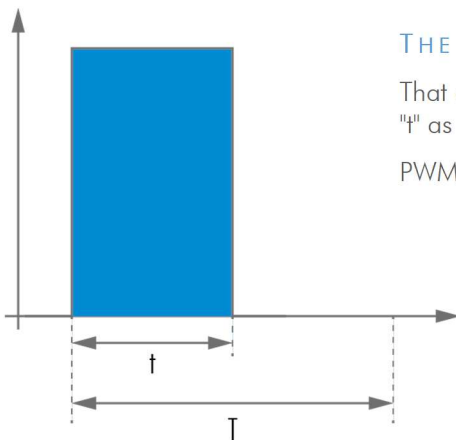
Implementation of PWM

The basic frequency of the modulation is defined by the cycle duration "T".

$$T_{PWM} = \frac{1}{f_{PWM}}$$

Duty cycle "T" is written into the registry by multiple of the inverse of camera frequency. (15 ns steps) Refer to: [Time unit of the camera](#).

$$\begin{aligned} T_{PWM} &= \frac{1}{66,6MHz} \cdot PWMMax[SeqSelector] \\ &= 15 ns \cdot PWMMax[SeqSelector] \end{aligned}$$



THE INTENSITY OF A PWM:

That duty ratio is calculated as: $\Delta\% = t / T$. It is written about the value of "t" as PWMChange0-3[SeqSelector] per sequence into the Registry.

PWMChange0-3[SeqSelector] is to be written as a percentage value.

EXAMPLES OF PWMs:

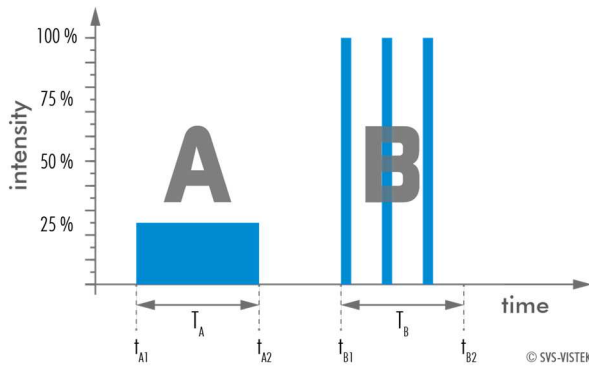


Figure 4: 25% PWM load

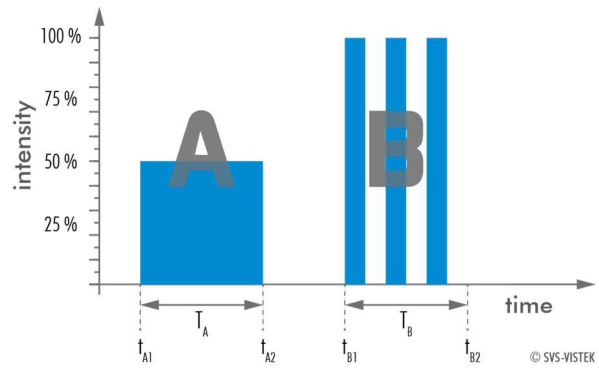


Figure 5: 50% PWM load

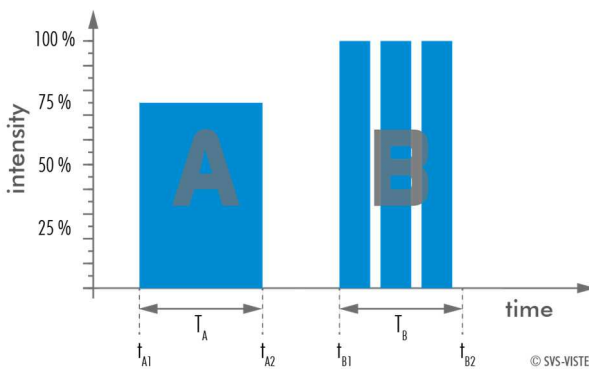


Figure 6: 75% PWM load

The integrals over both periods T_A and T_B are equal.

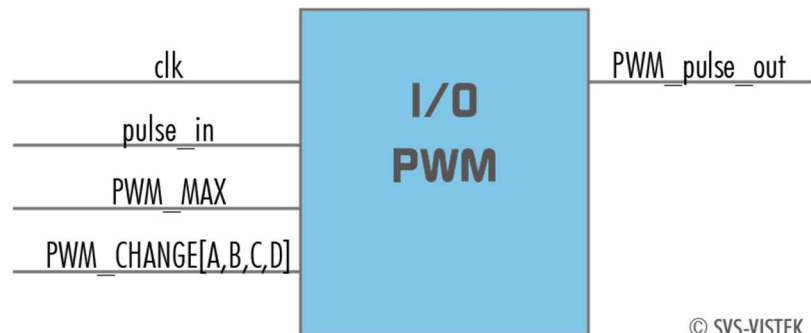
$$\int_{t_{A1}}^{t_{A2}} A = \int_{t_{B1}}^{t_{B2}} B$$

An equal amount of Photons will be emitted. The intensity of light is the same.

$$t_{A2} - t_{A1} = t_{B2} - t_{B1}$$

The periods T_A and T_B are equal in length.

THE PWM MODULE:



© SVS-VISTEK

5.3.3 Driver Circuit Schematics

Camera power supply and power supply for PWM out is 25V max. Power for PWM out has to be supplied via [Hirose connector](#). The open drain outputs are ledged to ground, that means you connect your LED on the positive side to your (light-)power source, the negative LED connector goes to the camera out. This setup requires common ground.

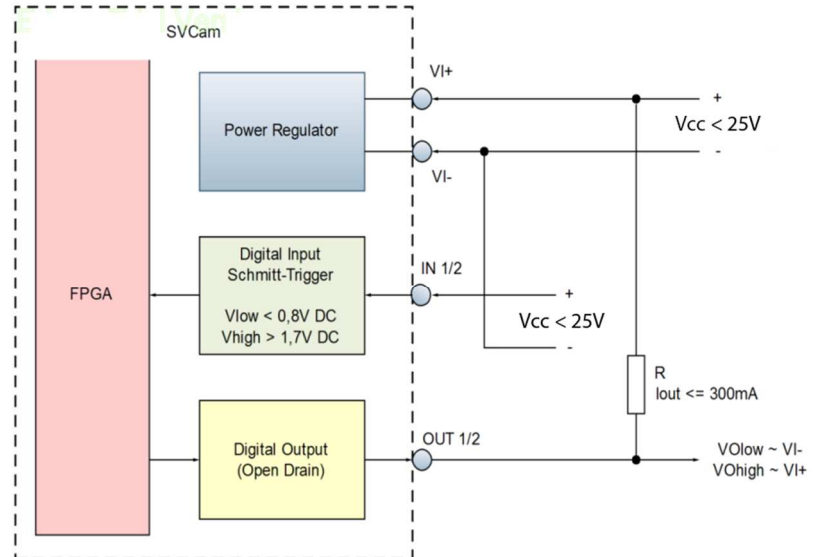


Figure 7: output driver circuit layout

5.3.4 Strobe Control

The SVCam 4I/O concept contains an integrated strobe controller. Its controls are integrated into the GenICam tree. With LED lights attached to the outputs, this enables the user to control the light without external devices. Being controlled via GenICam, any GenICam-compliant 3rd party software is able to control the light as well. Depending on the camera model, up to 4 (see [specifications](#)) independent channels are supported with a peak current of max 1 Amp.

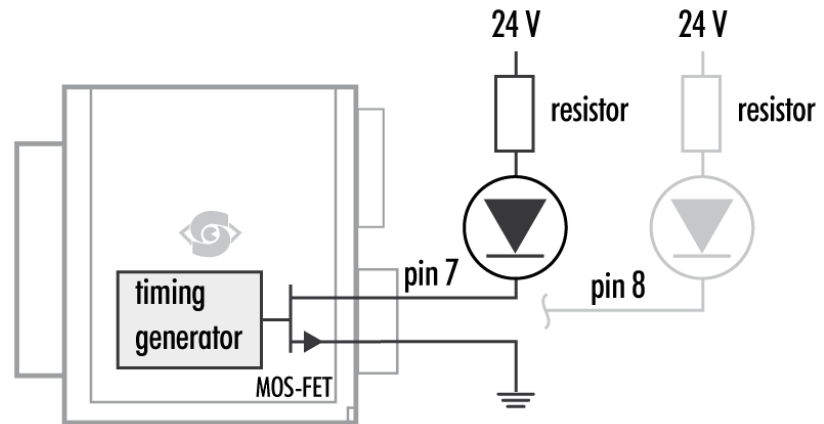


Figure 8: Attach LED lights to camera outputs. For detailed connector pin out refer to [Connectors](#)



USE RIGHT DIMENSION OF RESISTOR!

To avoid destruction of your LED light or camera, make sure to use the right dimension of shunt resistor. If not done so, LEDs and/or Camera might be damaged.

Calculate LED shunt resistors

Shunt resistors are used to limit the LED current. Make sure, neither shunt nor LED are run above specs.

LEDs in Continuous Mode

Example Calculation "No Flash" (CW Mode)	
Voltage drop at 5 LEDs, 2,2 V per LED (see spec. of LED)	11 V
Max. continuous current (see spec. of LED)	250 mA
Voltage Supply	24 V
Voltage drop at Resistor (24 V – 11 V)	13 V
Pull up Resistor $R = \frac{13 V}{250 mA}$	52 Ω
Total Power ($P = U \times I$)	6 W
Power at LEDs (11 V \times 250 mA)	2,75 W
Power Loss at Resistor (13 V \times 250 mA)	3,25 W

LEDs in Flash Mode

Most LED lights can cope with currents higher than specs. This gives you higher light output when light is ON. Please refer to your LED specs if LED overdrive is permitted.

By controlling the duty cycle the intensity of light and current can be controlled. See sequencer example how to adjust the values in the GenlCam tree for strobe control.



NOTICE

The shorter the „time on“ – the higher current can be used when driving LEDs with current higher than spec

Strobe vocabulary

For an example how to enable and adjust the integrated strobe controller refer to [sequencer](#). Times and frequencies are set in tics. 1 tic = 15ns.

Exposure Delay

A tic value, representing the time between the (logical) positive edge of trigger pulse and start of integration time.

Strobe Polarity

Positive or negative polarity of the hardware strobe output can be selected.

Strobe Duration

The exposure time of LED lights can be set in **tics**. The min duration is 1 μ sec. The longest time is 1 second.

Strobe Delay

The delay between the (logical) positive edge of trigger pulse and strobe pulse output.

5.3.5 Sequencer

The sequencer is used when different exposure settings and illuminations are needed in a row.

Values to set	Description
Sequencer interval	Duration of the interval
Exposure start	Exposure delay after interval start
Exposure stop	Exposure stop related to interval Start
Strobe start	Strobe delay after interval start
Strobe stop	Strobe stop related to interval Start
PWM frequency	Basic duty cycle (1 / Hz) for PWM
PWM change	Demodulation results

In the current GenlCam implementation, all values have to be entered in tic values.

1 tic = 15 ns

Every adjustment (times, frequencies) has to be recalculated into tics and done in tics. See the example below.

When setting “Exposure Start” and “Stop” consider ‘read-out-time’ of the sensor. It has to be within the Sequencer interval.

For physical input and output connections refer to pinout or specifications or see example below. After trigger signal all programmed intervals will start. Up to 16 intervals can be programmed.

Sequencer settings can be saved to camera EEPROM.

Example

For demonstration, imagine following task to be done:

Scenario

An object should be inspected with a monochrome camera. For accentuating different aspects of the image, 4 images should be taken in a row with 4 different colours of light: Red, Green, Blue, White. White light should be generated from the RGB lights being activated at the same time. Basis is a dark environment without other light sources.

Camera wiring

- 3 LED lights are physically connected to the camera on out 0-2 (red, green, blue)
- Out 3 is not used

I/O matrix

- 4 images to be taken (RGBW) result in 4 sequences
- RGB PWM change with different intensities (duty cycle) taking care for differences in spectral response of the camera sensor
- PWM change 0-2 is connected to out 0-2
- Seq pulse A is driving the exposure (trigger)
- Seq pulse B is driving the strobe
- Seq pulse B in WHITE sequence is reduced down to 33% as light intensities of 3 lights (RGB) will add up

Notes

- Different exposure / strobe timings are used for illustration. In most cases they will show values same as exposure
- The resulting exposure time shows the period of sensor light exposure. ("masking" of exposure time by creating strobe light impulses shorter than exposure time). This value is not adjustable at the camera
- PWM change is shown with reduced height for demonstrating reduced intensity. In reality though, PWM change will be full height (full voltage, shunt resistor might be necessary) with the adjusted duty cycle
- Use a PWM frequency high enough not to interfere with your timings (here: 1000 Hz)

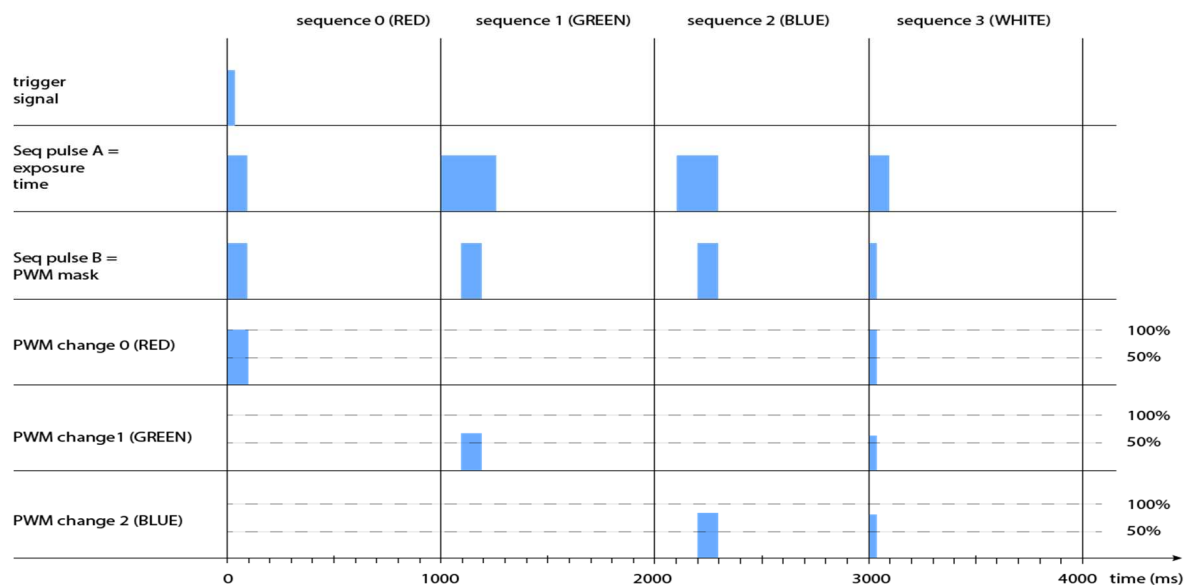
Scenario values	Interval 0 (RED)	Interval 1 (GREEN)	Interval 2 (BLUE)	Interval 3 (WHITE)
Sequencer Interval	1000 ms	1000 ms	1000 ms	1000 ms
Seq pulse A start	0 ms	0 ms	100 ms	0 ms
Seq pulse A stop	100 ms	300 ms	300 ms	100 ms
Seq pulse B start	0 ms	100 ms	200 ms	0 ms
Seq pulse B stop	100 ms	200 ms	300 ms	33 ms
PWM Frequency f	1000 Hz	1000 Hz	1000 Hz	1000 Hz
PWM change 0 (RED)	100%	0%	0%	100%
PWM change 1 (GREEN)	0%	70%	0%	70%
PWM change 2 (BLUE)	0%	0%	80%	80%
PWM change 3	-	-	-	-

As being said before, all these values have to be entered into the camera's GenICam tree as tic values.

The timing values translate like this into tics:

Values to set in GenICam properties	Interval 0 (RED)	Interval 1 (GREEN)	Interval 2 (BLUE)	Interval 3 (WHITE)
Sequencer Interval	6666667 tic (1000 ms)	6666667 tic (1000 ms)	6666667 tic (1000 ms)	6666667 tic (1000 ms)
Seq pulse A start	0 tic (0 ms)	0 tic (0 ms)	6666667 tic (100 ms)	0 tic (0 ms)
Seq pulse A stop	6666667 tic (100 ms)	20000000 tic (300 ms)	20000000 tic (300 ms)	6666667 tic (100 ms)
Seq pulse B start	0 tic (0 ms)	6666667 tic (100 ms)	13333333 tic (200 ms)	0 tic (0 ms)
Seq pulse B stop	6666667 tic (100 ms)	13333333 tic (200 ms)	20000000 tic (300 ms)	2200000 tic (33 ms)
Effective exposure time	100 ms	100 ms	100 ms	33 ms
PWM Frequency f	66667 tic (1000 Hz)	66667 tic (1000 Hz)	66667 tic (1000 Hz)	66667 tic (1000 Hz)
PWM change 0 (RED)	66667 tic (100% of 1000 Hz)	0 tic	0 tic	66667 tic (100% of 1000 Hz)
PWM change 1 (GREEN)	0 tic	46667 tic (70% of 1000 Hz)	0 tic	46667 tic (70% of 1000 Hz)
PWM change 2 (BLUE)	0 tic	0 tic	53333 tic (80% of 1000 Hz)	53333 tic (80% of 1000 Hz)
PWM change 3	-	-	-	-

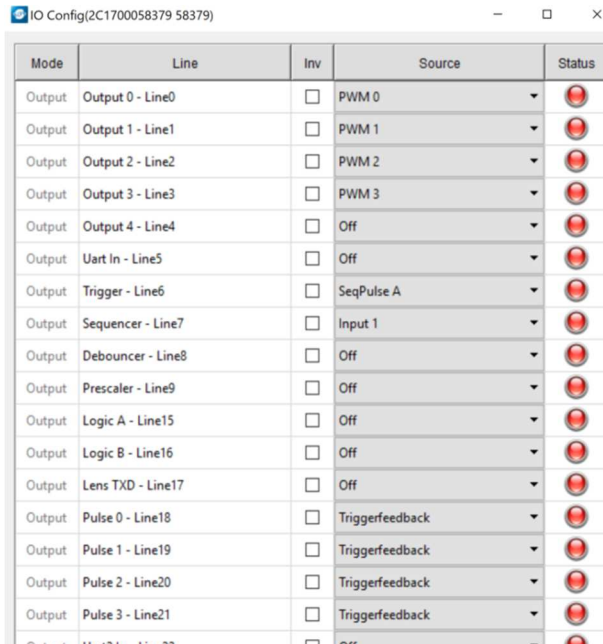
In a timings diagram, the sequence values above will look like this



Sequencer setup with SVCapture

Starting with SVCapture 2.5.2, there is a sequencer assistant, providing easy setup of the sequencer settings. The assistant will help you to setup timings for start exposure and lighting and so on. The PWMs are connected to the physical outputs (e.g. for driving LED lights)..

For making the sequencer work in general, have a look into the GenICam tree or even more simple into the I/O assistant. Connect the the I/O lines as below:



IO Config(2C1700058379 58379)

Mode	Line	Inv	Source	Status
Output	Output 0 - Line0	<input type="checkbox"/>	PWM 0	
Output	Output 1 - Line1	<input type="checkbox"/>	PWM 1	
Output	Output 2 - Line2	<input type="checkbox"/>	PWM 2	
Output	Output 3 - Line3	<input type="checkbox"/>	PWM 3	
Output	Output 4 - Line4	<input type="checkbox"/>	Off	
Output	Uart In - Line5	<input type="checkbox"/>	Off	
Output	Trigger - Line6	<input type="checkbox"/>	SeqPulse A	
Output	Sequencer - Line7	<input type="checkbox"/>	Input 1	
Output	Debouncer - Line8	<input type="checkbox"/>	Off	
Output	Prescaler - Line9	<input type="checkbox"/>	Off	
Output	Logic A - Line15	<input type="checkbox"/>	Off	
Output	Logic B - Line16	<input type="checkbox"/>	Off	
Output	Lens TXD - Line17	<input type="checkbox"/>	Off	
Output	Pulse 0 - Line18	<input type="checkbox"/>	Triggerfeedback	
Output	Pulse 1 - Line19	<input type="checkbox"/>	Triggerfeedback	
Output	Pulse 2 - Line20	<input type="checkbox"/>	Triggerfeedback	
Output	Pulse 3 - Line21	<input type="checkbox"/>	Triggerfeedback	

You may start the sequence with a hardware trigger input signal (sequencer is connected to Input 1). As an alternative you might use a software trigger. For software trigger setup, adjust as below:

Feature Name	Feature Value
Acquisition Control - Acquisition Mode	Continuous
Acquisition Control – Trigger Selector - Trigger Mode	On
Acquisition Control – Trigger Selector - Trigger Source	Line 1
Acquisition Control – Trigger Selector – Exposure Mode	Trigger Width
Enhanced IO – PWMEnable	On
Enhanced IO – SeqEnable	On

The Exposure mode „trigger width“ makes exposure start at a certain timing (Seq pulse A) and stop at Seq pulse B. In the GenICam tree this

will reflect as following:

Property	Value
> Device Control	
> Image Format Control	
> Acquisition Control	
Acquisition Mode	Continuous
> Trigger Selector	Acquisition Start
Trigger Mode	On
Generate Software Trigger	(command)
Trigger Source	Line 1
Trigger Activation	Rising Edge
Trigger Delay	0 us
Exposure Mode	Trigger Width
Acquisition Frame Rate	10 Hz
Exposure Time	99871 us
Exposure Auto	Off
Exposure First	<input type="checkbox"/> Off
ExposureTimeMin	1000 us
ExposureTimeMax	300000 us
Sensor Shutter Mode	Global Shutter
> Strobe Control	
> Enhanced IO	
PWMEnable	<input checked="" type="checkbox"/> On
SeqTrigger	(command)
SeqTriggermode	Trigger on high level
> SeqSelector	3
SeqInterval	6700000
SeqPulseAStart	0
SeqPulseAStop	6666666
SeqPulseBStart	0
SeqPulseBStop	6666666
PWMMax	66666
PWMChange0	0
PWMChange1	0
PWMChange2	0
PWMChange3	66666
SeqCount	4
SeqEnable	<input checked="" type="checkbox"/> On
SeqLoop	<input type="checkbox"/> Off
DebounceDuration	66666
PrescaleDivisor	2
> LUT Control	

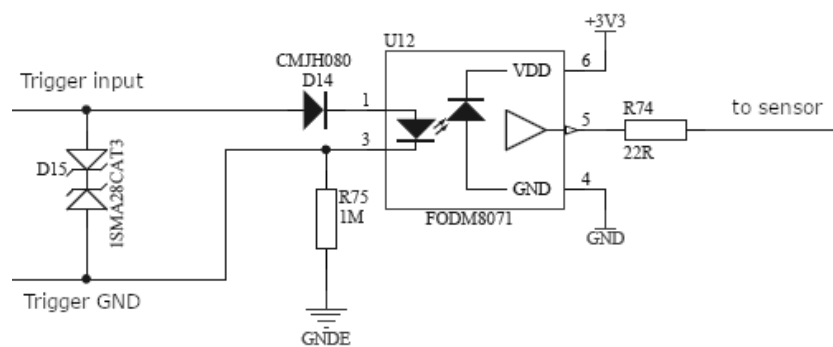
5.3.6 Optical Input

In many trigger signals you find noise, transients and voltage spikes. These are able to damage components in the camera and trigger signal interpretation might be difficult.

An optical input separates the electrical trigger and camera circuits. The benefit of such an optical input is to avoid all these kinds of interaction from power sources or switches. The disadvantage of an optical input is that it is slower in terms of signal transmission and slew rate than a direct electrical connection.

If you need super fast response from the camera, direct electrical access is your choice. If your camera trigger is in the ms range or slower, we recommend to use the optical input.

An optical input needs some current for operation. The SVS-Vistek optical input is specified to 5-24V, 8mA.



The opto coupler galvanically separates electrical circuits by emitting light on one side and interpreting light in the other. There is no direct electric interaction between both electrical circuits.

5.3.7 Serial data interfaces

(ANSI EIA/) TIA-232-F

RS-232 and RS-422 (from EIA, read as Radio Sector or commonly as Recommended Standard) are technical standards to specify electrical characteristics of digital signaling circuits.

In the SVCam's these signals are used to send low-power data signals to control light or lenses (MFT).

Table 1: serial interface parameter – RS-232 and RS-422

Serial interface Parameter	RS-232	RS-422
Maximum open-circuit voltage	±25 V	±6 V
Max Differential Voltage	25 V	10 V
Min. Signal Range	±3 V	2 V
Max. Signal Range	±15V	10 V

RS-232

It is splitted into 2 lines receiving and transferring Data.

RXD receive data
TXD transmit data

Signal voltage values are:

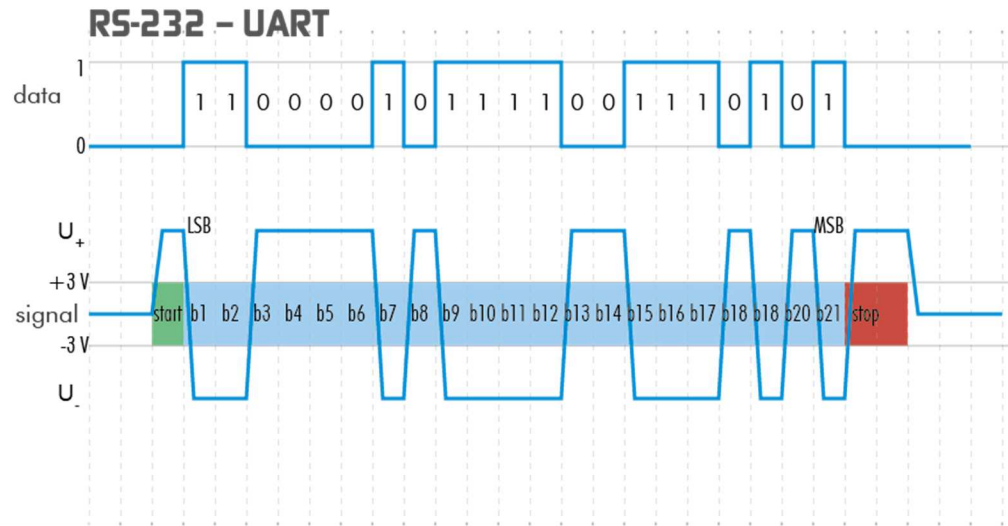
low: -3 ... -15 V
high: +3 ... +15 V

With restrictions: refer to Table: serial interface parameter above.

Data transport is asynchronous. Synchronization is implemented by first and last bit of a package. Therefore the last bit can be longer, e.g. 1.5 or 2 times the bit duration). Data rate (bits per second) must be defined before transmission.

UART

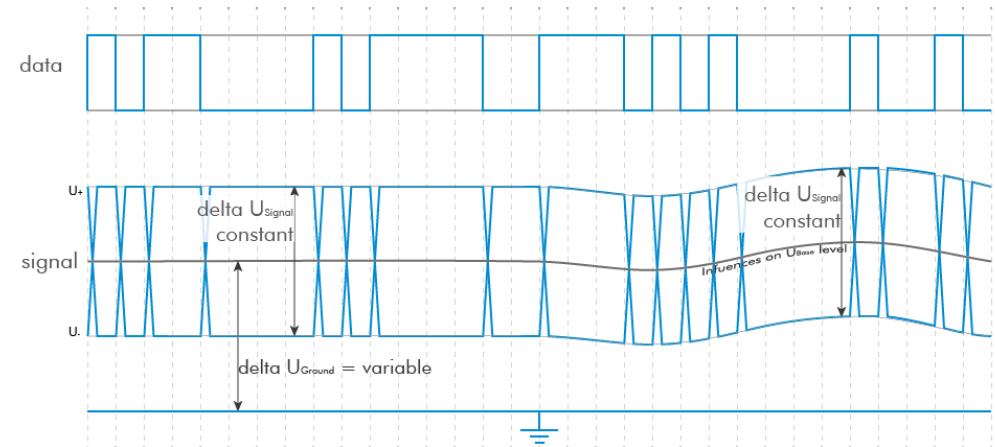
Packaging Data into containers (adding start and stop bits) is implemented by the UART (Universal Asynchronous Receiver Transmitter)



UART encoding of a data stream

RS-422

RS-422 is a differential low voltage communication standard.

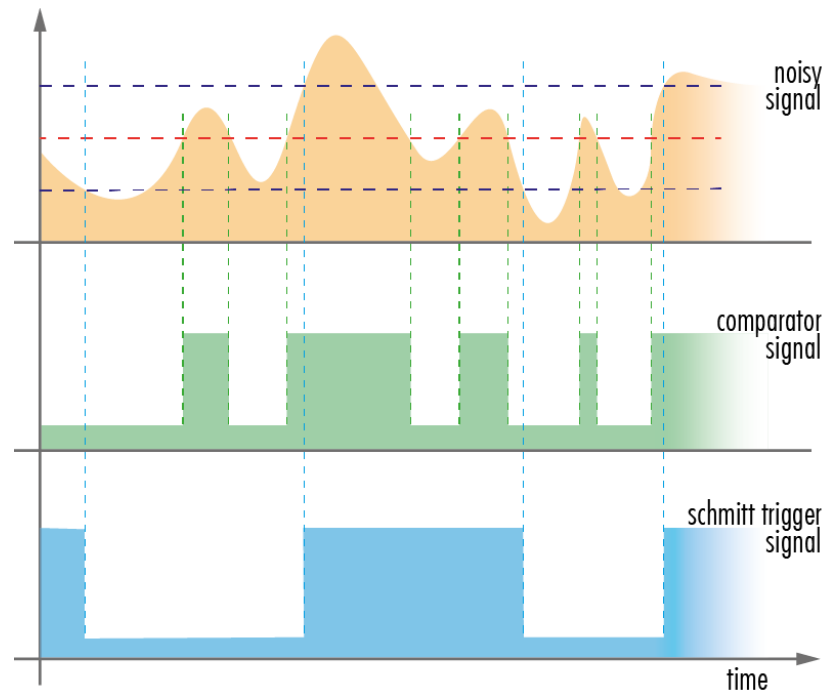


LVDS signal – no return to zero volt

Refer to [specifications](#) to see if RS-422 is implemented in your camera.

5.3.8 Trigger-Edge Sensitivity

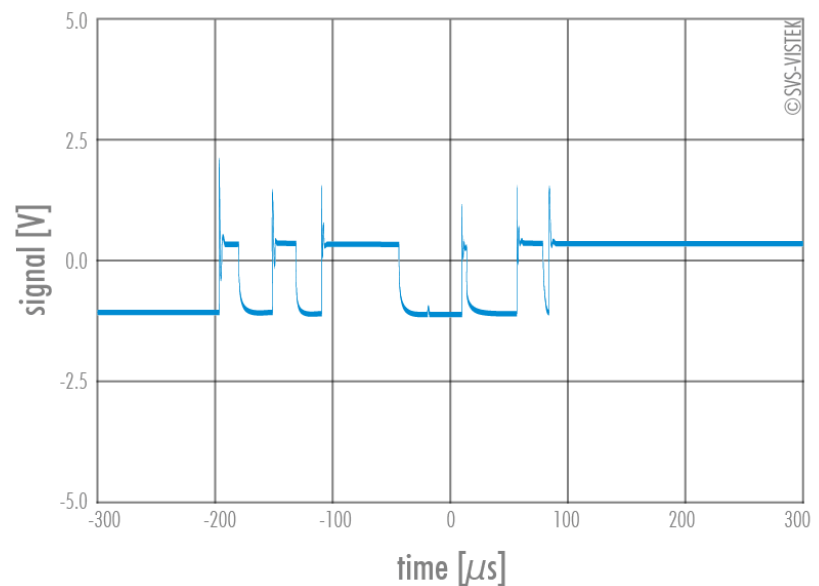
Trigger-Edge Sensitivity is implemented by a “schmitt trigger”. Instead of triggering to a certain value Schmitt trigger provides a threshold.



Schmitt trigger noise suppression

5.3.9 Debouncing Trigger Signals

Bounces or glitches caused by a switch can be avoided by software within the SVCam.

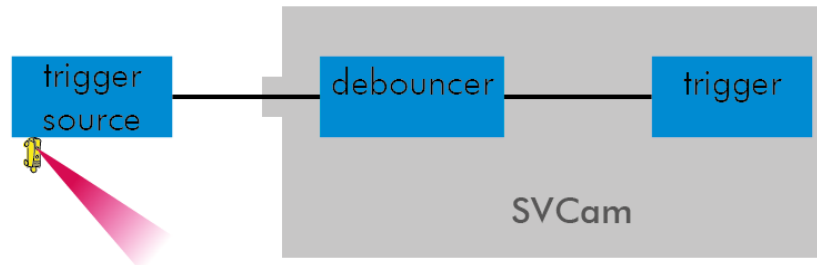


bounces or glitches caused by a switch

Therefore the signal will not be accepted till it lasts at least a certain time.

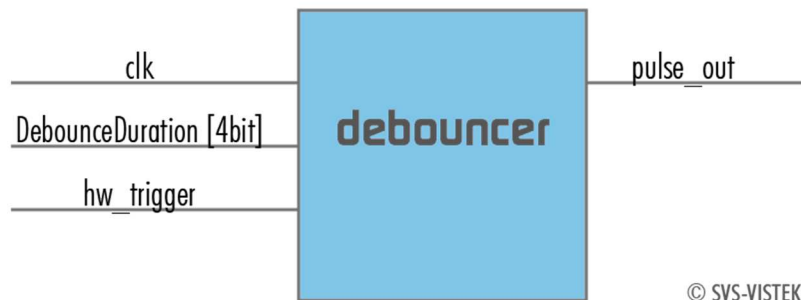
Use the IO Assignment tool to place and enable the debouncer module in between the "trigger" (schmitt trigger) and the input source (e.g.: line 1).

DebounceDuration register can be set in multiples of 15ns (implement of system clock). E.g. 66 666 \approx 1 ms



debouncer between the trigger source and trigger

The Debouncer module

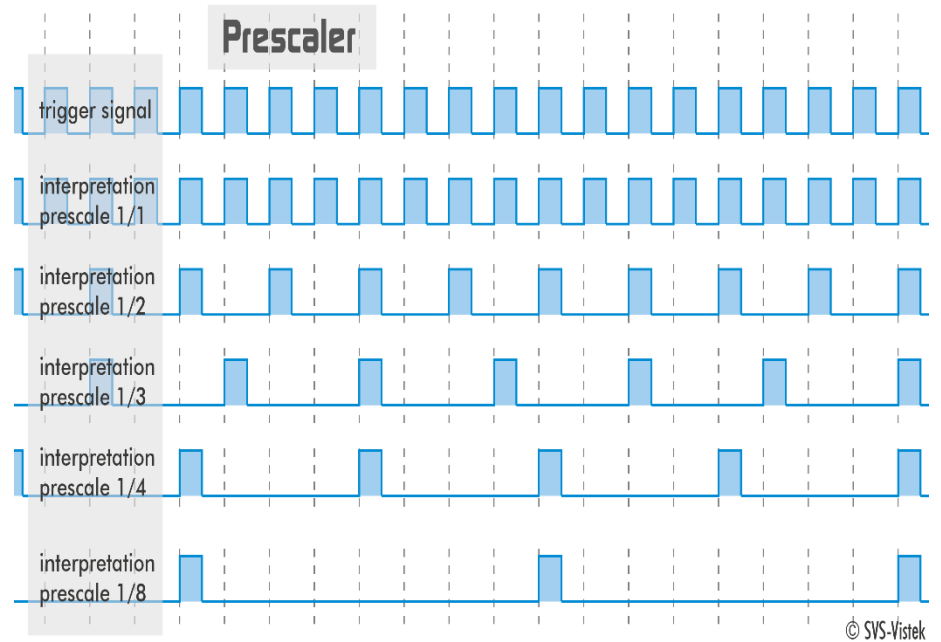


the debouncer module

5.3.10 Prescaler

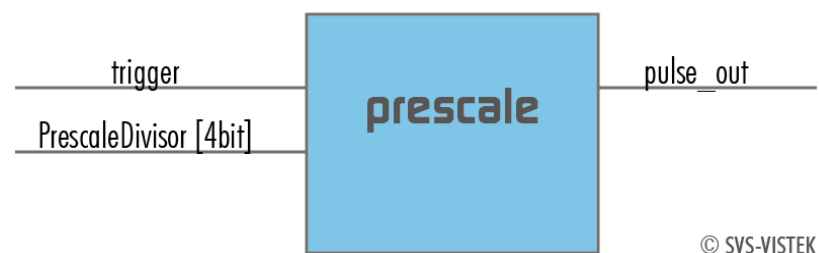
The Prescaler function can be used for masking off input pulses by applying a divisor with a 4-bit word, resulting in 16 unique settings.

- > Reducing count of interpreted trigger signal
- > Use the prescaler to ignore a certain count of trigger signals.
- > Divide the amount of trigger signals by setting a divisor.
- > Maximum value for prescale divisor: is 16 (4 bit)



Prescale values and their result on trigger signal

The prescale module



the prescale module

6 Specifications

All specifications can be viewed as well on our website, www.svs-vistek.com. We are proud to have ongoing development on our cameras, so specs might change and new features being added. Spectral response curves are sensor only and do not include camera spectral response modifications due to filters or cover glass.

6.1 hr25*CX

Model	hr25MCX	hr25CCX
family	HR	HR
active pixel w x h	5120 x 5120	5120 x 5120
max. frame rate	80 fps	80 fps
chroma	mono	color
interface	CXP-6 4 Lanes	CXP-6 4 Lanes

sensor name	NOIP1SN025KA-GDI	NOIP1SE025KA-GDI
sensor manufacturer	ON Semiconductor	ON Semiconductor
sensor architecture	Area CMOS	Area CMOS
shutter type	global	global
equivalent format	35 mm	35 mm
diagonal	32.6 mm	32.6 mm
pixel w x h	4.5x4.5 μ m	4.5x4.5 μ m
optic sensor w x h	23.04x23.04 mm	23.04x23.04 mm
exposure time	50 μ s / 1s	50 μ s / 1s
max. gain	18 dB	18 dB

dynamic range

S/N Ratio

frame buffer	512MB RAM 160MB Flash	512MB RAM 160MB Flash
CL geometry	-	-
frequency select	-	-
exp. time adjustment	manual;auto;external	manual;auto;external
px format 8 / 12 / 16	x / - / -	x / - / -
packed readout	-	-
max binning h / v	2 / 2	2 / 2
LUT	10to8(1)	10to8(1)
ROI	-	-
white balancing	-	auto;manual
tap balancing	-	-
gain	auto;manual	auto;manual
black level	manual	manual
PIV	-	-
readout control	-	-
flat field correction	x	x
shading correction	external	external
defect pixel correction	-	-
image flip	horizontal;vertical	horizontal;vertical
trigger int / ext / soft	x / x / x	x / x / x
trigger edge high / low	x / x	x / x
sequencer	x	x

PWM power out	x	x
trigger IN TTL-24 V	2	2
outputs open drain	4	4
optical in / out	1 / -	1 / -
RS-232 in / out	1 / 1	1 / 1
RS-422 in / out	- / -	- / -
power supply	10...25 V	10...25 V

lens mount	M58x0.75	M58x0.75
dynamic lens control	-	-
size w / h / d (1)	70x70x56.3 mm	70x70x56.3 mm
weight	380 g	380 g
protection class	IP30	IP30
power consumption	13.0 W	13.0 W
operating temperature	-10...60°C	-10...60°C
humidity non-condensing	10...90 %	10...90 %
status	production	production

(1) please refer to drawings

Spectral Sensitivity Characteristics

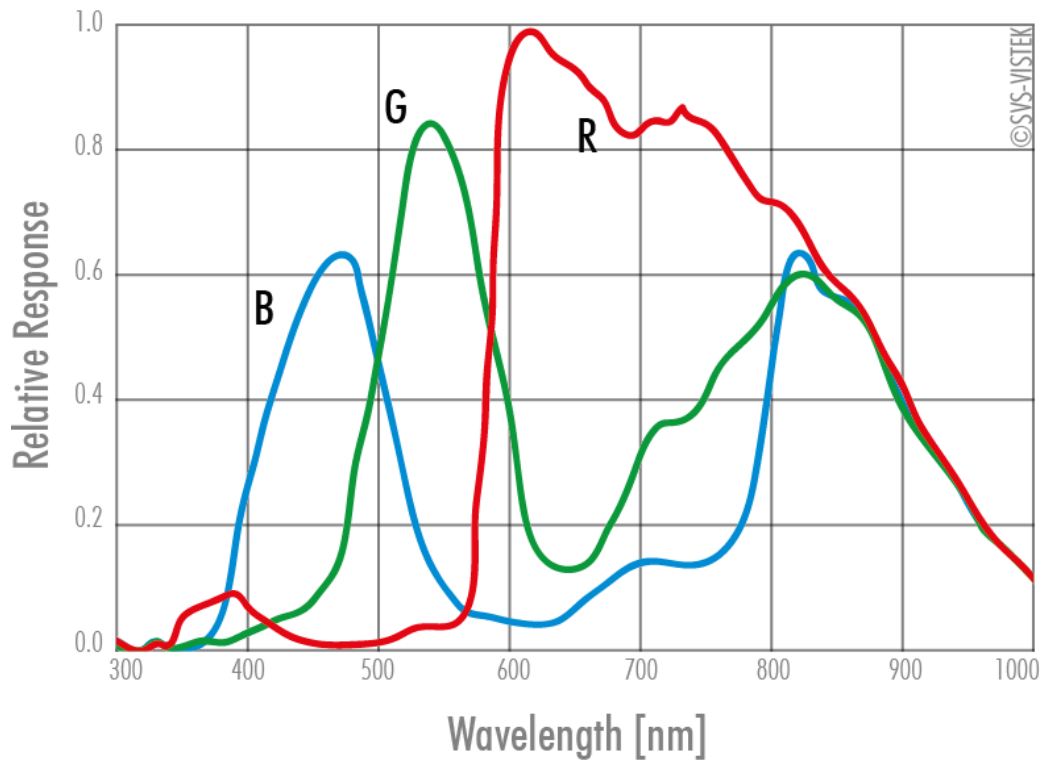


Figure 9: Spectral Sensitivity Characteristics NOIP1SN025KA

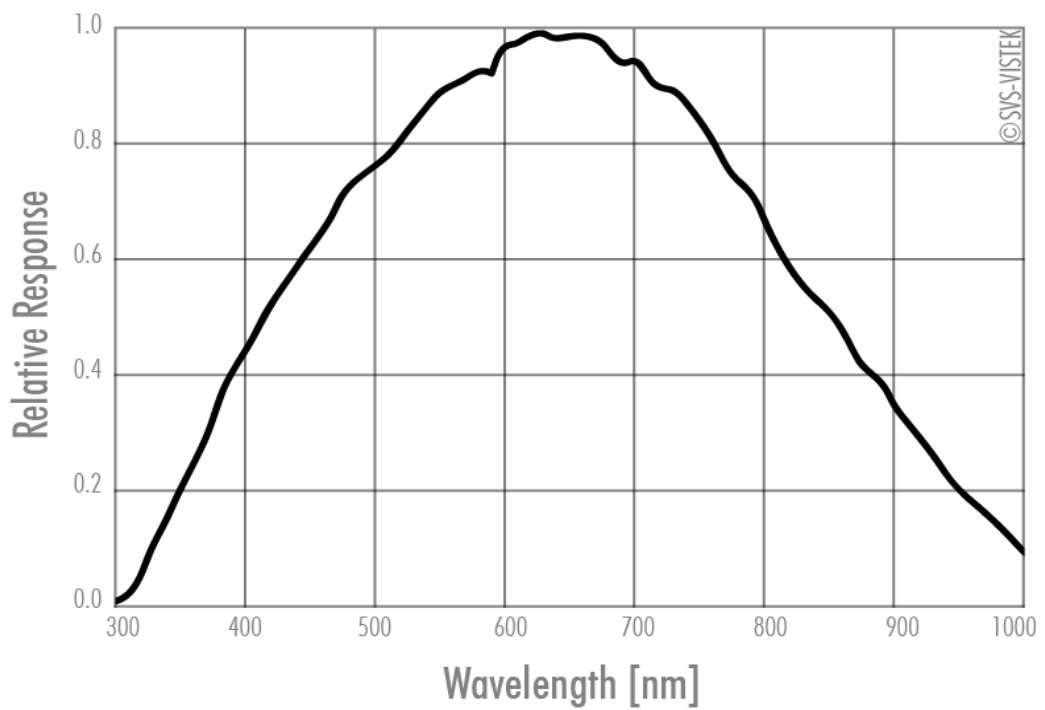


Figure 10: Spectral Sensitivity Characteristics NOIP1SE025KA

6.2 hr120*CX

Model	hr120MCX	hr120CCX
family	HR	HR
active pixel w x h	13264 x 9176	13264 x 9176
max. frame rate	9.3 fps	9.3 fps
chroma	mono	color
interface	CXP-6 4 Lanes	CXP-6 4 Lanes

sensor name	120MXSM	120MXSC
sensor manufacturer	Canon	Canon
sensor architecture	Area CMOS	Area CMOS
shutter type	rolling	rolling
equivalent format	APS-H	APS-H
diagonal	0.0 mm	0.0 mm
pixel w x h	2.2x2.2 μ m	2.2x2.2 μ m
optic sensor w x h	29.2x20.19 mm	29.2x20.19 mm
exposure time	40 μ s / 1s	40 μ s / 1s
max. gain	0 dB	0 dB
dynamic range		

S/N Ratio

frame buffer	512MB RAM 160MB Flash	512MB RAM 160MB Flash
CL geometry	-	-
frequency select	-	-
exp. time adjustment	manual;auto	manual;auto
px format 8 / 12 / 16	x / - / -	x / - / -
packed readout	-	-
max binning h / v	2 / 2	2 / 2
LUT	12to8(1)	12to8(1)
ROI	1	1
white balancing	auto;manual	auto;manual
tap balancing	-	-
gain	auto;manual	auto;manual
black level	manual	manual
PIV	-	-
readout control	-	-
flat field correction	x	x
shading correction	external	external
defect pixel correction	x	x
image flip	horizontal	horizontal
trigger int / ext / soft	x / x / x	x / x / x
trigger edge high / low	- / -	- / -
sequencer	x	x
PWM power out	x	x
trigger IN TTL-24 V	2	2

outputs open drain	4	4
optical in / out	1 / -	1 / -
RS-232 in / out	1 / 1	1 / 1
RS-422 in / out	- / -	- / -
power supply	10...25 V	10...25 V

lens mount	M58	M58
dynamic lens control	-	-
size w / h / d (1)	70x70x51 mm	70x70x51 mm
weight	380 g	380 g
protection class	IP30	IP30
power consumption	14.0 W	14.0 W
operating temperature	-10...55°C	-10...55°C
humidity non-condensing	10...90 %	10...90 %
status	production	production

(1) please refer to drawings

Spectral Sensitivity Characteristics

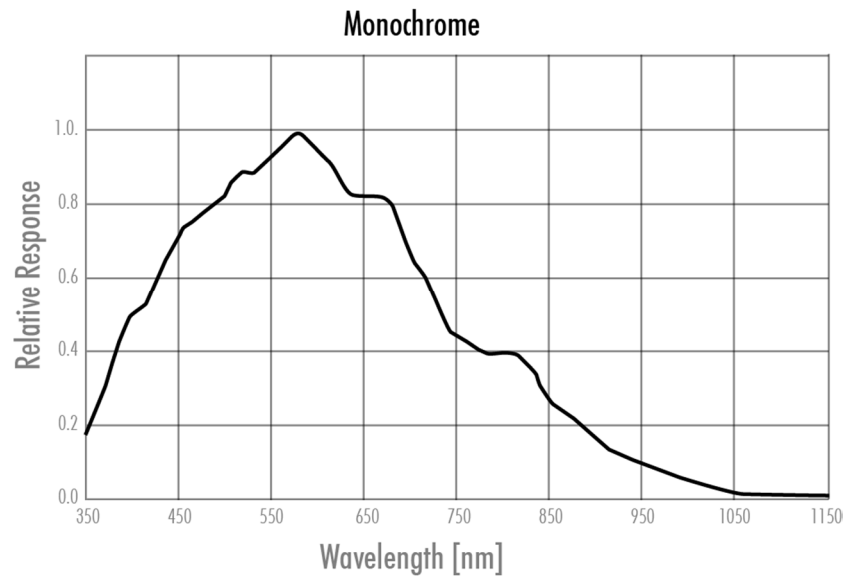


Figure 11: Spectral Sensitivity Characteristics 120MXSM

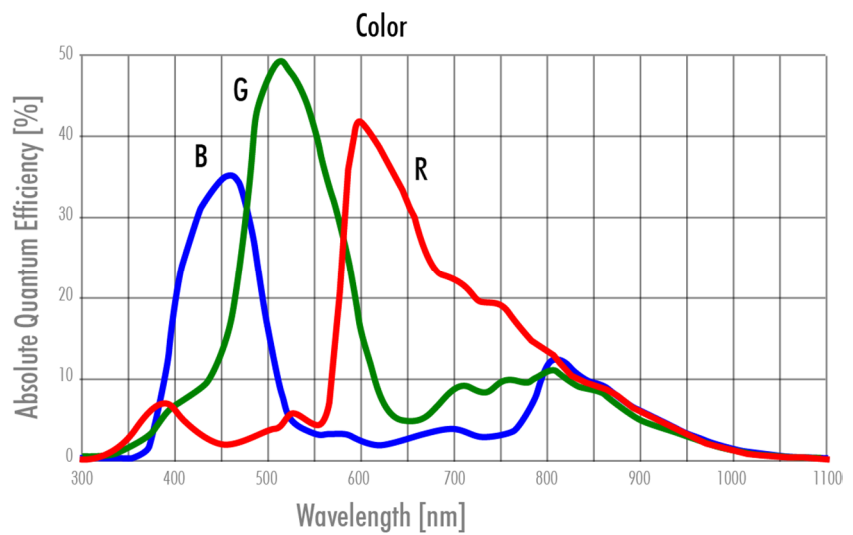


Figure 12: Spectral Sensitivity Characteristics 120MXSC

6.3 hr342*CX

Model	hr342MCX	hr342CCX
family	HR2	HR2
active pixel w x h	6464 x 4852	6464 x 4852
max. frame rate	35.4 fps	35.4 fps
chroma	mono	color
interface	CXP-6 4 Lanes	CXP-6 4 Lanes

sensor name	IMX342LLA	IMX342LQA
sensor manufacturer	Sony	Sony
sensor architecture	Area CMOS	Area CMOS
shutter type	global	global
equivalent format	27.9mm (APS-C)	27.9mm (APS-C)
diagonal	27.9 mm	27.9 mm
pixel w x h	3.45x3.45 μ m	3.45x3.45 μ m
optic sensor w x h	22.3x16.74 mm	22.3x16.74 mm
exposure time	21 μ s / 1s	21 μ s / 1s
max. gain	24 dB	24 dB
dynamic range		

S/N Ratio

frame buffer	512MB RAM 160MB Flash	512MB RAM 160MB Flash
CL geometry	-	-
frequency select	-	-
exp. time adjustment	manual;auto	manual;auto
px format 8 / 12 / 16	x / x / x	x / x / x
packed readout	-	-
max binning h / v	2 / 2	2 / 2
LUT	12to8(1)	12to8(1)
ROI	1	1
white balancing	auto;manual	auto;manual
tap balancing	-	-
gain	auto;manual	auto;manual
black level	manual	manual
PIV	-	-
readout control	-	-
flat field correction	x	x
shading correction	external	external
defect pixel correction	x	x
image flip	horizontal	horizontal
trigger int / ext / soft	x / x / x	x / x / x
trigger edge high / low	- / -	- / -

sequencer	x	x
PWM power out	x	x
trigger IN TTL-24 V	2	2
outputs open drain	4	4
optical in / out	1 / -	1 / -
RS-232 in / out	1 / 1	1 / 1
RS-422 in / out	- / -	- / -
power supply	10...25 V	10...25 V

lens mount	M58x0.75	M58x0.75
dynamic lens control	-	-
size w / h / d (1)	70x70x55.4 mm	70x70x55.4 mm
weight	320 g	320 g
protection class	IP30	IP30
power consumption	0.0 W	0.0 W
ambient temperature	-10...45°C	-10...45°C
humidity non-condensing	0...0 %	0...0 %
status	production	production

(1) please refer to drawings

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February 13, 2019

February 13, 2019

7 Dimensions

All length units in mm.

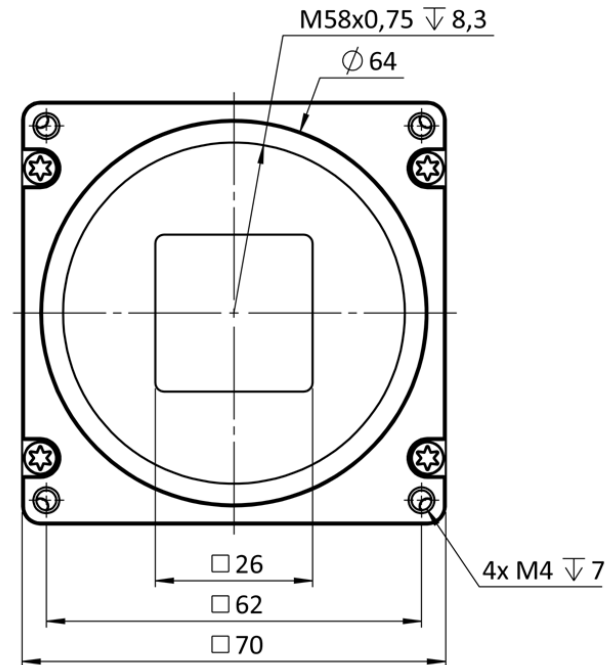
Find drawings in the web download area at

<https://www.svs-vistek.com/en/support/svs-support-download-center.php>

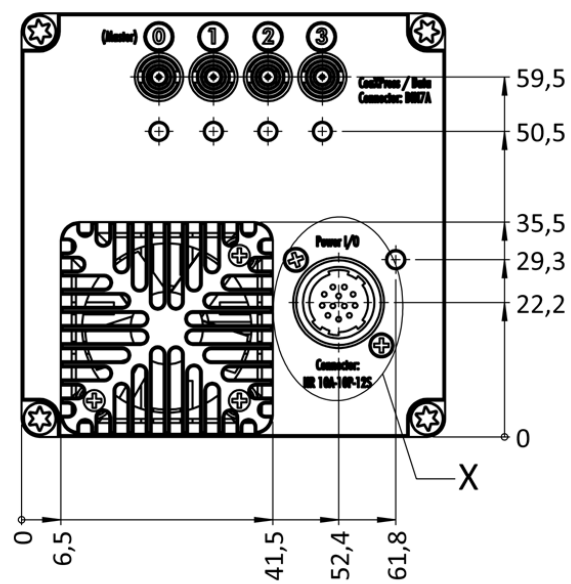
CAD step files available with valid login at [SVS-VISTEK.com](https://www.svs-vistek.com)

7.1 hr25*CX

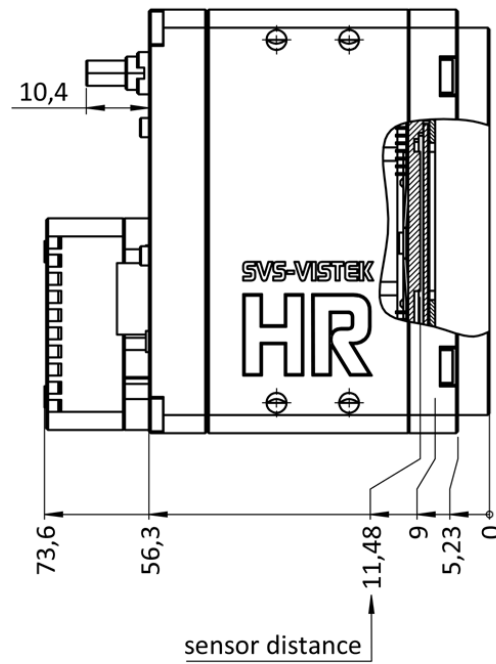
front view



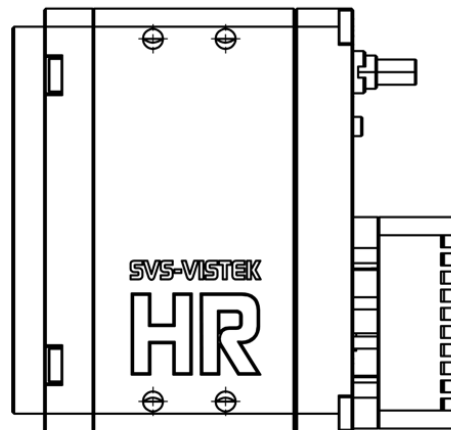
back view



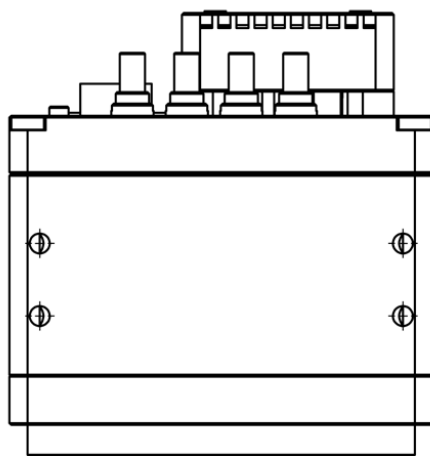
cross section



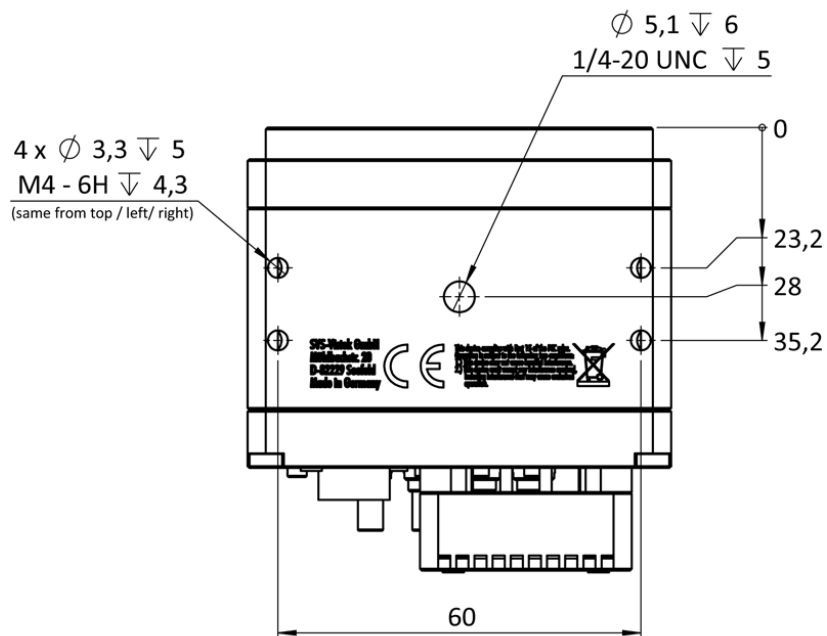
right view



top view



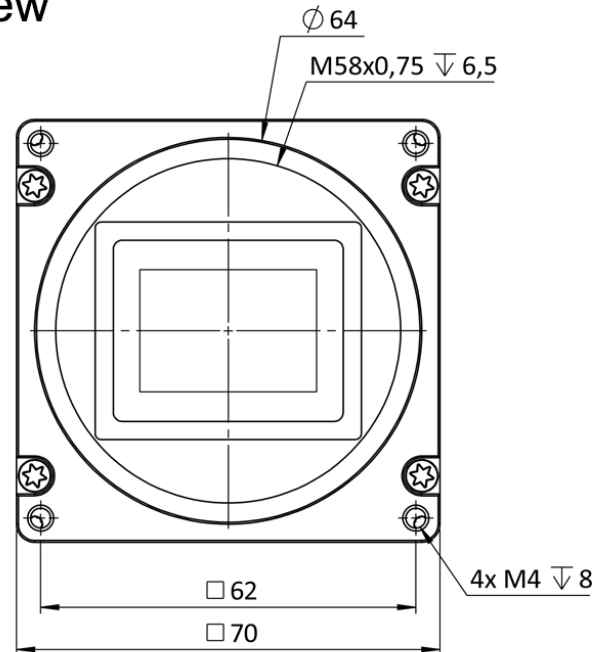
bottom view



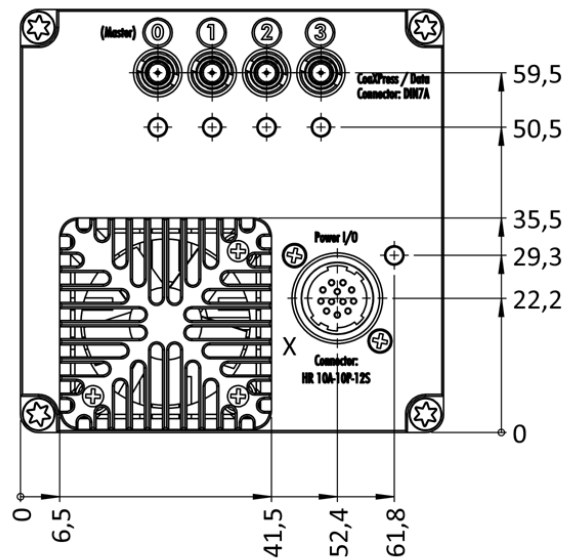
7.2 hr120*CX

The HR120 can be ordered with different mount options. The most general approach is M58, as outlined in the drawing below. Additional mounts (Birger mount, Moritex mount) on request.

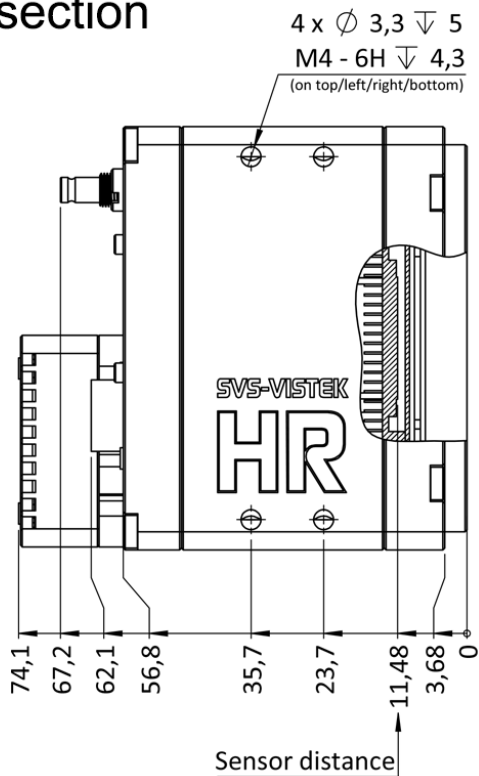
front view



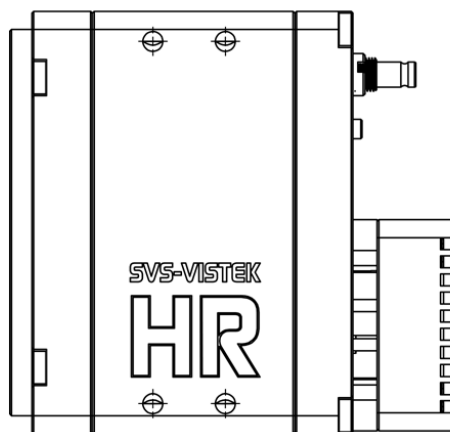
back view



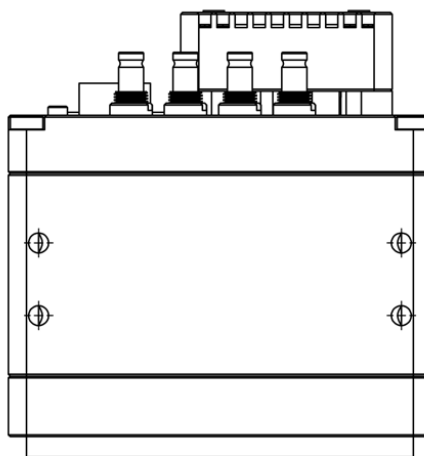
cross section



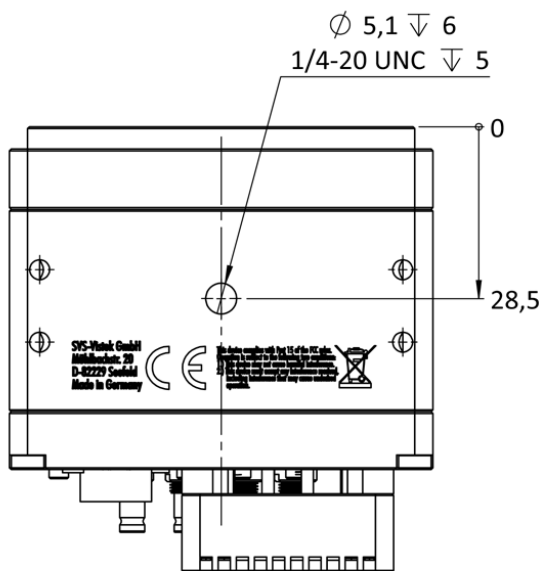
right view



top view

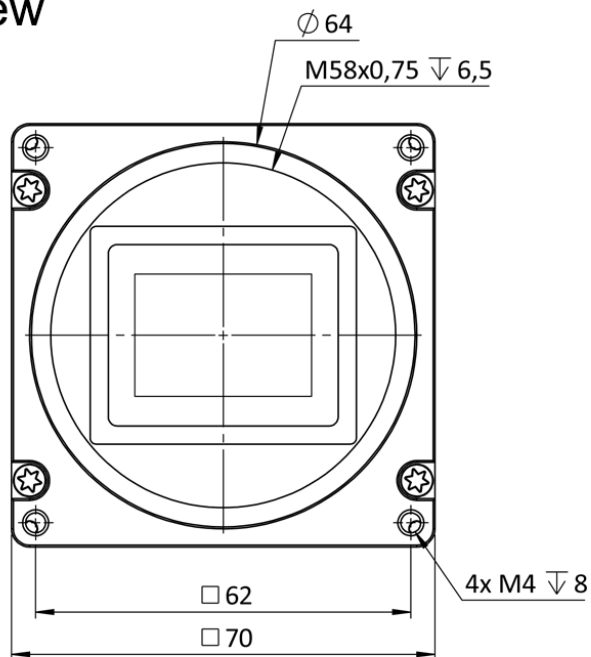


bottom view

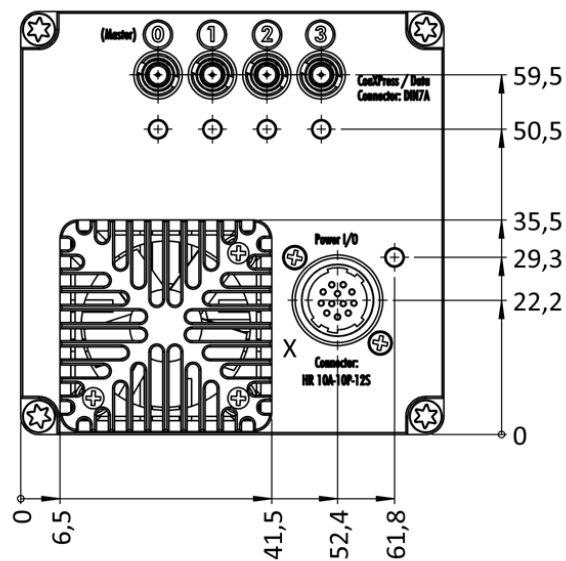


7.3 hr342*CX

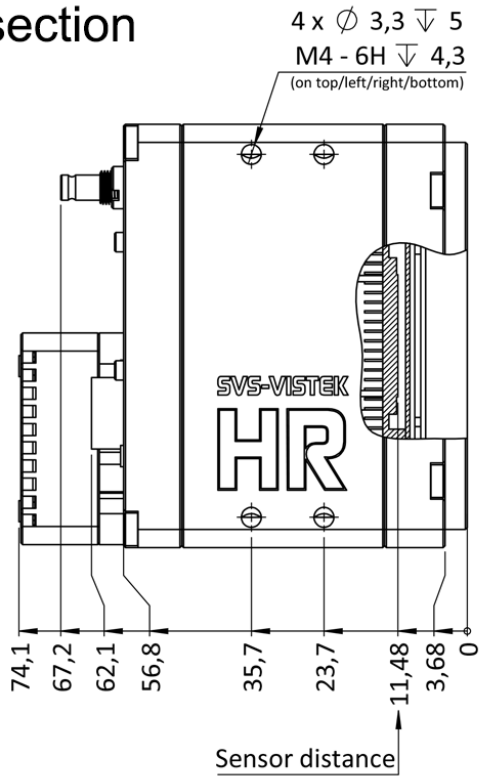
front view



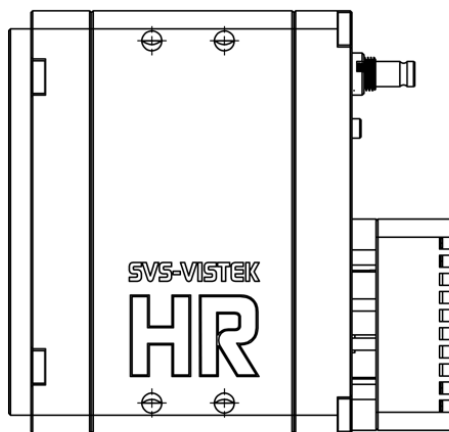
back view



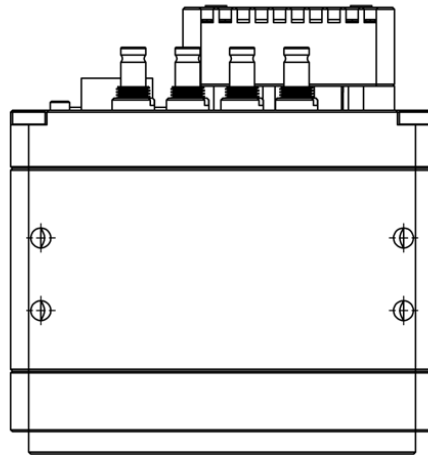
cross section



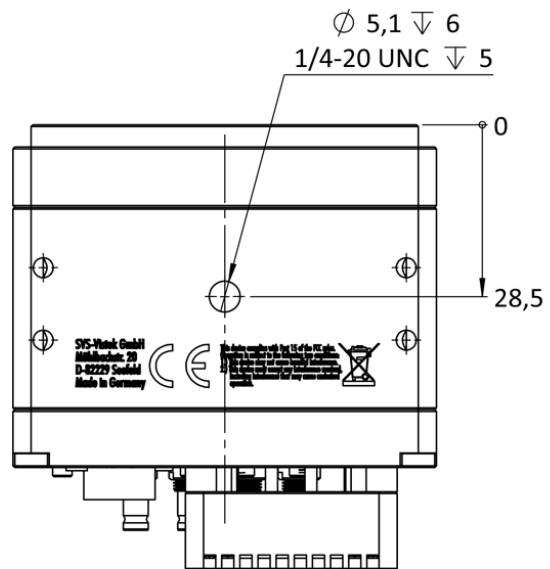
right view



top view



bottom view



7.4 M58 mount

Diameter 58 mm

Thread pitch 0.75 mm

Back focus distance from sensor to flange of the camera: 11.48 mm

Distance from sensor surface to lens differs depending on lens specifications and how far the lens is screwed in.

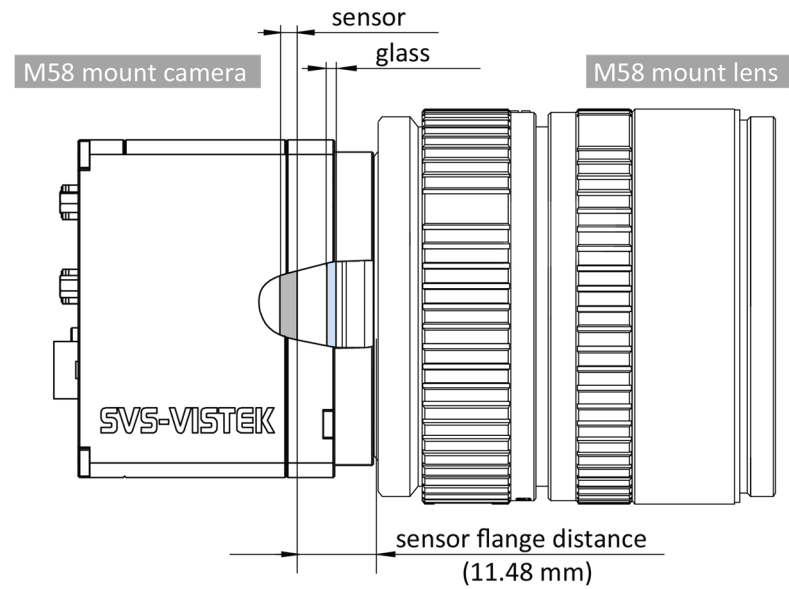


Figure 13: M58-mount

8 Terms of warranty

Standard Products Warranty and Adjustment	<p>Seller warrants that the article to be delivered under this order will be free from defects in material and workmanship under normal use and service for a period of 2 years from date of shipment. The liability of Seller under this warranty is limited solely to replacing or repairing or issuing credit (at the discretion of Seller) for such products that become defective during the warranty period. In order to permit Seller to properly administer this warranty, Buyer shall notify Seller promptly in writing of any claims,; provide Seller with an opportunity to inspect and test the products claimed to be defective. Such inspection may be on customer's premises or Seller may request return of such products at customer's expense. Such expense will subsequently be reimbursed to customer if the product is found to be defective and Buyer shall not return any product without prior return authorization from Seller. If a returned product is found to be out of warranty or found to be within the applicable specification, Buyer will have to pay an evaluation and handling charge, independent of possible repair and/or replacement costs. Seller will notify Buyer of the amount of said evaluation and handling charges at the time the return authorization is issued. Seller will inform Buyer of related repair and/or replacement costs and request authorization before incurring such costs. Buyer shall identify all returned material with Sellers invoice number, under which material has been received. If more than one invoice applies, material has to be clearly segregated and identified by applicable invoice numbers. Adjustment is contingent upon Sellers examination of product, disclosing that apparent defects have not been caused by misuse, abuse, improper installation of application, repair, alteration, accident or negligence in use, storage, transportation or handling. In no event shall Seller be liable to Buyer for loss of profits, loss of use, or damages of any kind based upon a claim for breach of warranty.</p>
Development Product Warranty	<p>Developmental products of Seller are warranted to be free from defects in materials and workmanship and to meet the applicable preliminary specification only at the time of receipt by Buyer and for no longer period of time in all other respects the warranties made above apply to development products. The aforementioned provisions do not extend the original warranty period of any article which has been repaired or replaced by Seller.</p>
Do not break Warranty Label	<p>If warranty label of camera is broken warranty is void. Seller makes no other warranties express or implied, and specifically, seller makes no warranty of merchantability of fitness for particular purpose.</p>
What to do in case of Malfunction	<p>Please contact your local distributor first.</p>

9 FAQ

Problem	Solution
Camera does not respond to light.	<p>Check if camera is set to "Mode 0". I.e. free running with programmed exposure ctrl. When done, check with the program "Convenient Cam" if you can read back any data from the camera, such as "Mode", "type" of CCD, exposure time settings, etc..</p> <p>If "Mode 0" works properly, check the signals of the camera in the desired operation mode like "Mode 1" or "Mode 2". In these modes, check if the ExSync signal is present. Please note that a TTL signal must be fed to the trigger connector if it is not provided by the frame grabber (LVDS type). The typical signal swing must be around 5 V. Lower levels will not be detected by the camera... If you use a TTL level signal fed to the "TB 5 connector" check the quality and swing. If these signals are not present or don't have the proper quality, the camera cannot read out any frame (Mode 1 and 2). Beware of spikes on the signal.</p>
Image is present but distorted.	<p>Check the camera configuration file of your frame grabber. Check number of "front- and back porch" pixel. Wrong numbers in configuration file can cause sync problems. Check if your frame grabber can work with the data rate of the camera.</p>
Image of a color version camera looks strange or false colors appear.	<p>If the raw image looks OK, check the camera file to see if the pixels need to be shifted by either one pixel or one line. The image depends on the algorithm used. If the algorithm is starting with the wrong pixel such effects appear.</p>
Colors rendition of a color versions not as expected – especially when using halogen light.	<p>Halogen light contains strong portions of IR radiation. Use cut-off filters at around 730 nm like "Schott KG 3" to prevent IR radiation reaching the CCD.</p>
No serial communication is possible between the camera and the PC.	<p>Use "load camera DLL" and try again.</p>

10 Glossary of Terms

Aberration	Spherical aberration occurs when light rays enter near the edge of the lens; Chromatic aberration is caused by different refractive indexes of different wavelengths of the light. (Blue is more refractive than red)
ADC	Analogue-to-Digital Converter, also known as A/D converter
Aperture	In optics, Aperture defines a hole or an opening through which light travels. In optical system the Aperture determines the cone angle of a bundle of rays that come to a focus in the image plane. The Aperture can be limited by an iris, but it is not solely reliant on the iris. The diameter of the lens has a larger influence on the capability of the optical system.
Bayer Pattern	A Bayer filter mosaic or pattern is a color filter array (CFA) deposited onto the surface of a CCD or CMOS sensor for capturing RGB color images. The filter mosaic has a defined sequence of red, green and blue pixels such that the captured image can be transported as a monochrome image to the host (using less bandwidth); where after the RGB information is recombined in a computer algorithm.
Binning	Binning combines the charge from two (or more) pixels to achieve higher dynamics while sacrificing resolution.
Bit-Depth	Bit-depth is the number of digital bits available at the output of the Analog-to-Digital Converter (ADC) indicating the distribution of the darkest to the brightest value of a single pixel.
Camera Link	Camera Link is a multiple-pair serial communication protocol standard [1] designed for computer vision applications based on the National Semiconductor interface Channel-link. It was designed for the purpose of standardizing scientific and industrial video products including cameras, cables and frame grabbers.
CCD	Charge Coupled Device. Commonly used technology used for camera sensors used to detect & quantify light, i.e. for capturing images in an electronic manner. CCDs were first introduced in the early 70ies.
CMOS	Complementary Metal–Oxide–Semiconductor. A more recently adopted technology used for camera sensors with in-pixel amplifiers used to detect & quantify light, i.e. capturing images in an electronic manner.
CPU	Central Processing Unit of a computer. Also referred to as the processor chip.
dB	Decibel (dB) is a logarithmic unit used to express the ratio between two values of a physical quantity.
Decimation	For reducing width or height of an image, decimation can be used (CMOS sensors only). Columns or rows can be ignored. Image readout time is thereby reduced.
Defect map	Identifies the location of defect pixels unique for every sensor. A factory generated defect map is delivered and implemented with each camera.
EPROM	Erasable Programmable Read Only Memory is a type of memory chip that retains its data when its power supply is switched off.
External Trigger	Erasable Programmable Read Only Memory is a type of memory chip that retains its data when its power supply is switched off.
fixed frequency	or programmed exposure time. Frames are read out continuously.
Gain	In electronics, gain is a measure of the ability of a two-port circuit (often an amplifier) to increase the power or amplitude of a signal from the input to the output port by adding energy to the signal.

Gamma	Gamma correction is a nonlinear operation used to code and decode luminance values in video or still image systems.
GenICam	Provides a generic programming interface for all kinds of cameras and devices. Regardless what interface technology is used (GigE Vision, USB3 Vision, CoaXPress, Camera Link, etc.) or which features are implemented, the application programming interface (API) will always be the same.
GigE Vision	GigE Vision is an interface standard introduced in 2006 for high-performance industrial cameras. It provides a framework for transmitting high-speed video and related control data over Gigabit Ethernet networks.
GPU	Graphics Processing Unit of a computer.
Hirose	Cable connectors commonly used for power, triggers, I/Os and strobe lights
ISO	see Gain.
Jumbo Frames	In computer networking, jumbo frames are Ethernet frames with more than 1500 bytes of payload. Conventionally, jumbo frames can carry up to 9000 bytes of payload. Some Gigabit Ethernet switches and Gigabit Ethernet network interface cards do not support jumbo frames.
Mount	Mechanical interface/connection for attaching lenses to the camera.
Multicast	Multicast (one-to-many or many-to-many distribution) is an ethernet group communication where information is addressed to a group of destination computers simultaneously. Multicast should not be confused with physical layer point-to-multipoint communication.
PWM	Pulse width modulation. Keeping voltage at the same level while limiting current flow by switching on an off at a very high frequency.
Partial Scan	A method for reading out fewer lines from the sensor, but “skipping” lines above and below the desired area. Typically applied to CCD sensors. In most CMOS image sensors an AOI (area of interest) or ROI (region of interest) can be defined by selecting the area to be read. This leads to increased frame rate.
Pixel clock	The base clock (beat) that operates the sensor chip is. It is typically also the clock with which pixels are presented at the output node of the image sensor.
RAW	A camera RAW image file contains minimally processed data from the image sensor. It is referred as raw in its meaning. SVS-VISTEK plays out RAW only.
Read-Out-Control	Read-Out control defines a delay between exposure and image readout. It allows the user to program a delay value (time) for the readout from the sensor. It is useful for preventing CPU overload when handling very large images or managing several cameras on a limited Ethernet connection.
Shading	Shading manifests itself a decreasing brightness towards the edges of the image or a brightness variation from one side of the image to the other. Shading can be caused by non-uniform illumination, non-uniform camera sensitivity, vignetting of the lens, or even dirt and dust on glass surfaces (lens).
Shading correction	An in-camera algorithm for real time correction of shading. It typically permits user configuration. By pointing at a known uniform evenly illuminated surface it allows the microprocessor in the camera to create a correction definition, subsequently applied to the image during readout.
Shutter	Shutter is a device or technique that allows light to pass for a determined period of time, exposing photographic film or a light-sensitive electronic sensor to light in order to capture a permanent image of a scene.

Strobe light	<p>A bright light source with a very short light pulse. Ideal for use with industrial cameras, e.g. for “freezing” the image capture of fast moving objects. Can often be a substitute for the electronic shutter of the image sensor. Certain industrial cameras have dedicated in-camera output drivers for precisely controlling one or more strobe lights.</p>
Tap	<p>CCD sensors can occur divided into two, four or more regions to double/quadruple the read out time.</p>
TCP/IP	<p>TCP/IP provides end-to-end connectivity specifying how data should be packetized, addressed, transmitted, routed and received at the destination.</p>
USB3 Vision	<p>The USB3 Vision interface is based on the standard USB 3.0 interface and uses USB 3.0 ports. Components from different manufacturers will easily communicate with each other.</p>
Trigger modes	<p>Cameras for industrial use usually provide a set of different trigger modes with which they can be operated.</p> <p>The most common trigger modes are: (1) Programmable shutter trigger mode. Each image is captured with a pre-defined shutter time; (2) Pulse-Width Control trigger. The image capture is initiated by the leading edge of the trigger pulse and the shutter time is governed by the width of the pulse; (3) Internal trigger or Free-Running mode. The camera captures images at the fastest possible frame rate permitted by the readout time.</p>
XML Files	<p>Extensible Markup Language (XML) is a markup language that defines a set of rules for encoding documents in a format which is both human-readable and machine-readable</p>