

# **LogiCORE IP AXI4-Stream to Video Out v1.0**

## ***Product Guide***

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## Introduction

The Xilinx LogiCORE™ IP AXI4-Stream to Video Out core is designed to interface from the AXI4-Stream interface implementing a Video Protocol to a video source (parallel video data, video syncs, and blanks). The core works in conjunction with Xilinx Video Timing Controller (VTC) core, providing a bridge between video processing cores with AXI4-Stream interfaces and a video output.

## Features

- AXI4 Stream slave interface for input
- Video (parallel video data, video syncs, and blanks) output
- Interface to Xilinx Video Timing Controller core for video timing generation
- Automatically synchronizes video timing to AXI4-Stream video
- Handles asynchronous clock boundary crossing between AXI4-Stream clock domain and video clock domain
- Selectable FIFO depth from 64 -8192 locations
- Selectable data width for 8-64 bits

LogiCORE IP Facts Table	
<b>Core Specifics</b>	
Supported Device Family <sup>(1)</sup>	Zynq 7000, Artix-7, Virtex®-7, Kintex®-7, Virtex-6, Spartan®-6
Supported User Interfaces	AXI4-Stream <sup>(2)</sup>
Resources	See <a href="#">Table 2-1</a> through <a href="#">Table 2-6</a> .
<b>Provided with Core</b>	
Documentation	Product Guide
Design Files	Verilog source code
Example Design	Not Provided
Test Bench	Not Provided
Constraints File	Not Provided
Simulation Models	Verilog source code
<b>Tested Design Tools</b>	
Design Entry Tools	ISE 14.1
Simulation <sup>(3)</sup>	Mentor Graphics ModelSim, Xilinx® ISim
Synthesis Tools	Xilinx Synthesis Technology (XST)
<b>Support</b>	
Provided by Xilinx, Inc.	

1. For a complete listing of supported devices, see the [release notes](#) for this core.
2. Video protocol as defined in the *Video IP: AXI Feature Adoption* section of [UG761 AXI Reference Guide](#).
3. For the supported versions of the tools, see the [ISE Design Suite 14: Release Notes Guide](#).

# Overview

Many Xilinx video processing cores utilize the AXI-4 Stream Interface implementing a Video Protocol (as defined in the *Video IP: AXI Feature Adoption* section of the [UG761 AXI Reference Guide](#) to transfer video between IP cores. Conversely, between systems, video is commonly transmitted with explicit blanking and sync signals for horizontal and vertical timing, and a data valid signal. DVI is an example of such a transmission mode. The AXI4-Stream to Video Out core converts AXI4-Stream Video protocol from Xilinx video processing cores that use this protocol to video output with explicit sync and timing to interface with common video systems that use timing information.

The AXI4-Stream to Video Out core input is an AXI4-Stream interface in slave mode. This interface consists of parallel video data, `tdata`, handshaking signals `tvalid` and `tready`, and two flags, `tlast` and `tuser` which serve to identify certain pixels in the video stream. The `tlast` signal designates the last valid pixel of each line, and is also known as the end of line (EOL). The `tuser` signal designates the first valid pixel of a frame, and is known as start of frame (SOF). These two flags are necessary to identify pixel locations on the AXI4 stream interface because there are no sync or blank signals. Only active pixels are carried on the bus.

The AXI4-Stream to Video Out core outputs video. For the purposes of this document, video is defined as the following signals:

- Parallel video data
- Pixel clock
- Vsync
- Hsync
- Vbank
- Hblank
- DE (data enable)

An AXI4-Stream to Video Out core with a Video Timing Controller (VTC) block diagram is shown in Figure 1-1.

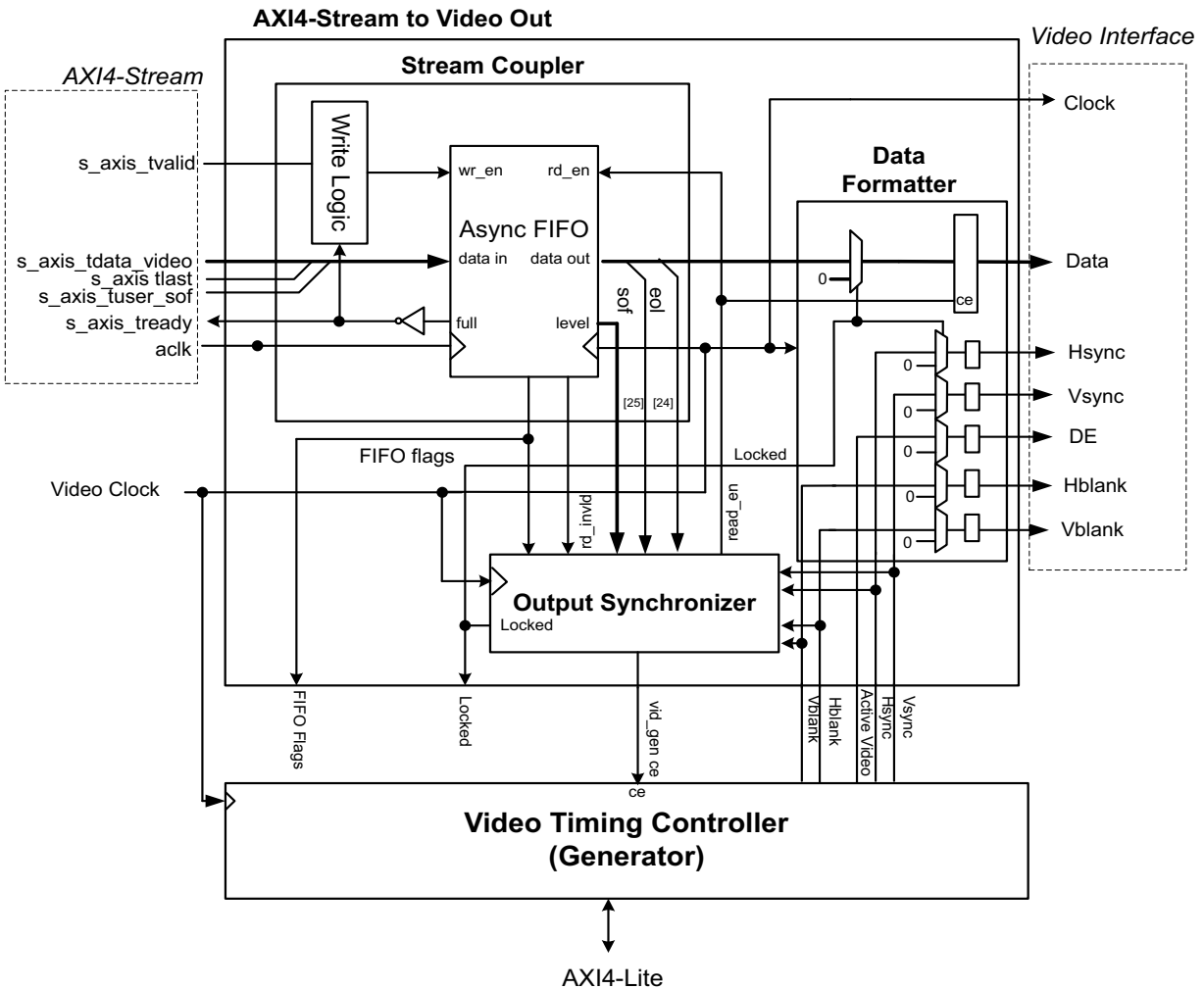


Figure 1-1: Block Diagram of AXI4-Stream to Video Out Core and Usage with the Video Timing Controller

The core is designed to be used in parallel with the generator functionality of the VTC. The VTC produces video timing signals based on video timing parameters such as the number of active pixels per line and the number of active lines via an AXI4-Lite interface. The Output Synchronizer section of the core synchronizes timing from the VTC to the video data from the AXI4-Stream Bus.

## Feature Summary

The AXI4-Stream to Video Out core converts an AXI4-Stream Slave interface that conforms with the AXI4-Stream Video protocol to a video output, consisting of parallel video data,

video syncs, blanks, and data enable. The core interfaces to the Xilinx VTC, which provides timing signals.

The core handles the asynchronous clock boundary crossing between the video clock domain and the AXI4-Stream clock domain. The data width is selectable from 8 to 64-bits, depending on the number of components required for the video format, and the number of bits per component. There is an output FIFO with selectable depth from 32 to 8192 locations.

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## Applications

- Video output providing parallel, clocked video output
  - DVI
  - HDMI
  - Other clocked, parallel video sinks

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## Licensing

The AXI4-Stream to Video Out core is provided at no cost with the Xilinx tools. Use of it is covered by the standard software license, and there are no further licensing requirements needed to use it in a design.

# Product Specification

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## Standards Compliance

The AXI4-Stream to Video Out core is compliant with the AXI4-Stream Video Protocol and AXI4-Lite interconnect standards. Refer to the *Video IP: AXI Feature Adoption* section of the [UG761 AXI Reference Guide](#) for additional information.

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## Performance

The following sections detail the performance characteristics of the AXI4-Stream to Video Out core.

### Maximum Frequencies

This section contains typical clock frequencies for the target devices. The maximum achievable clock frequency can vary. The maximum achievable clock frequency and all resource counts can be affected by other tool options, additional logic in the FPGA device, using a different version of Xilinx tools and other factors. Refer to in [Table 2-1](#) through [Table 2-6](#) for device-specific information.

### Latency

When the upstream processing block on the AXI4-Stream bus can source data at the pixel rate or faster, the typical latency through the AXI4 –Stream to Video Out core is 9 cycles of `vid_out_clk` + 3 cycles of `aclk`.

If the upstream block sources pixels at a slower rate, the FIFO will be used to even out the mismatch in the input and output rates over the course of lines and frames. This storage of pixels in the FIFO will add to the latency and will vary according to the data flow in and out of the core.



## Throughput

The average data rates of active pixels on the Video output bus matches the average rate of active pixels in on the AXI4-Stream bus. The data throughput is dictated by the video line standard and clock rate. However, the clock rates of the input need not match the output. Furthermore, since the AXI4-Stream bus does not carry blank pixels, the clock rate can be lower than the video clock rate and still have sufficient bandwidth to meet the average rate requirement. Additional FIFO depth is required in order to smooth the mismatch in instantaneous rates. Both the AXI4-Stream Clock (Fack) and the rate of the AXI4-Stream Clock (Fack) is limited by the overall Fmax.

If the sustained pixel rate available from the upstream AXI4-Stream (Fack) is equal to or greater than Fvclk, only the minimum buffer size (32 locations) is required. In this scenario, the FIFO will go empty after the EOL on each line.

If Fack is less than Fvclk, additional buffering is required. The FIFO must store enough pixels to supply pixels continuously throughout the active line. Additionally, due to phasing requirements, the horizontal active period on the output will overlap the effective blanking period of pixels coming in from the AXI4-Stream bus. This means that the output FIFO must also be large enough to provide output pixels continuously during this time.

For upstream bandwidth above the line average but below that of Fvclk, the minimum FIFO initial fill level must be:

$$\text{FIFO Initial Fill Level} = 32 + \text{Thblank}/\text{Fvclk} + (\text{Thactive} - \text{Thblank}) * \text{Fvclk}/\text{Fack}.$$

where Thblank is the duration of the horizontal blank and Thactive is the duration of the horizontal active period.

This is the level needed to keep the FIFO from running dry each line. This fill level is automatically established by the output synchronization mechanism, and is not dependent on the Hysteresis Level of the generated core.

The total FIFO depth must be slightly larger than the initial fill level to prevent overflow of the FIFO:

$$\text{FIFO depth min} = 32 + \text{FIFO initial Fill Level}$$

In every case, this is less than a full line of data, so if a line buffer is provided, it will be sufficient. However, in many cases, a full line buffer is not required.

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## Resource Utilization

The information presented in [Table 2-1](#) through [Table 2-6](#) is a guide to the resource utilization and maximum clock frequency of the AXI4-Stream to Video Out core for Virtex-7, Kintex-7, Artix-7, Zynq-7000, Virtex-6, and Spartan-6 FPGA families. This core does not use

any dedicated I/O or CLK resources. The design was tested using ISE® v14.1 tools with default tool options for characterization data.

Data width in the tables refers to the aggregate data width of all the video components into and out of the core. For example, RGB data with 8-bits per component has a data width of 24.

*Table 2-1: Spartan-6*

<b>Data Width</b>	<b>FIFO Depth</b>	<b>LUTs</b>	<b>FFs</b>	<b>RAM 16/8</b>	<b>Fmax (MHz)</b>
8	32	101	129	0/0	254
24	1024	132	196	1/1	226
64	8192	148	309	33/0	201

*Table 2-2: Virtex-7*

<b>Data Width</b>	<b>FIFO Depth</b>	<b>LUTs</b>	<b>FFs</b>	<b>RAM 36/18</b>	<b>Fmax (MHz)</b>
8	32	96	129	0/0	367
24	1024	142	196	1/0	339
64	8192	143	303	16/1	301

*Table 2-3: Virtex-6*

<b>Data Width</b>	<b>FIFO Depth</b>	<b>LUTs</b>	<b>FFs</b>	<b>RAM 36/18</b>	<b>Fmax (MHz)</b>
8	32	107	129	0/0	313
24	1024	137	196	1/0	272
64	8192	137	303	16/1	285

*Table 2-4: Kintex-7*

<b>Data Width</b>	<b>FIFO Depth</b>	<b>LUTs</b>	<b>FFs</b>	<b>RAM 36/18</b>	<b>Fmax (MHz)</b>
8	32	106	129	0/0	378
24	1024	125	196	1/0	329
64	8192	139	303	16/1	304

*Table 2-5: Artix-7*

<b>Data Width</b>	<b>FIFO Depth</b>	<b>LUTs</b>	<b>FFs</b>	<b>RAM 36/18</b>	<b>Fmax (MHz)</b>
8	32	90	129	0/0	258
24	1024	131	196	1/0	239
64	8192	141	303	16/1	226

Table 2-6: Zynq-7000

Data Width	FIFO Depth	LUTs	FFs	RAM 36/18	Fmax (MHz)
8	32	96	129	0/0	251
24	1024	131	196	1/0	238
64	8192	139	303	16/1	231

## Core Interfaces

### Port Descriptions

The AXI4-Stream to Video Out core uses industry standard control and data interfaces to connect to other system components. The following sections describe the various interfaces available with the core. Figure 2-1 illustrates an I/O diagram of the AXI4-Stream to Video Out core. Not all of the timing signals are required internally by this core, however it also passes these signals out to the Video output. Therefore all timing signals are present. The data enable and vertical sync input are required. It is recommended that the Xilinx Video Timing Controller be set to output all syncs and blanks.

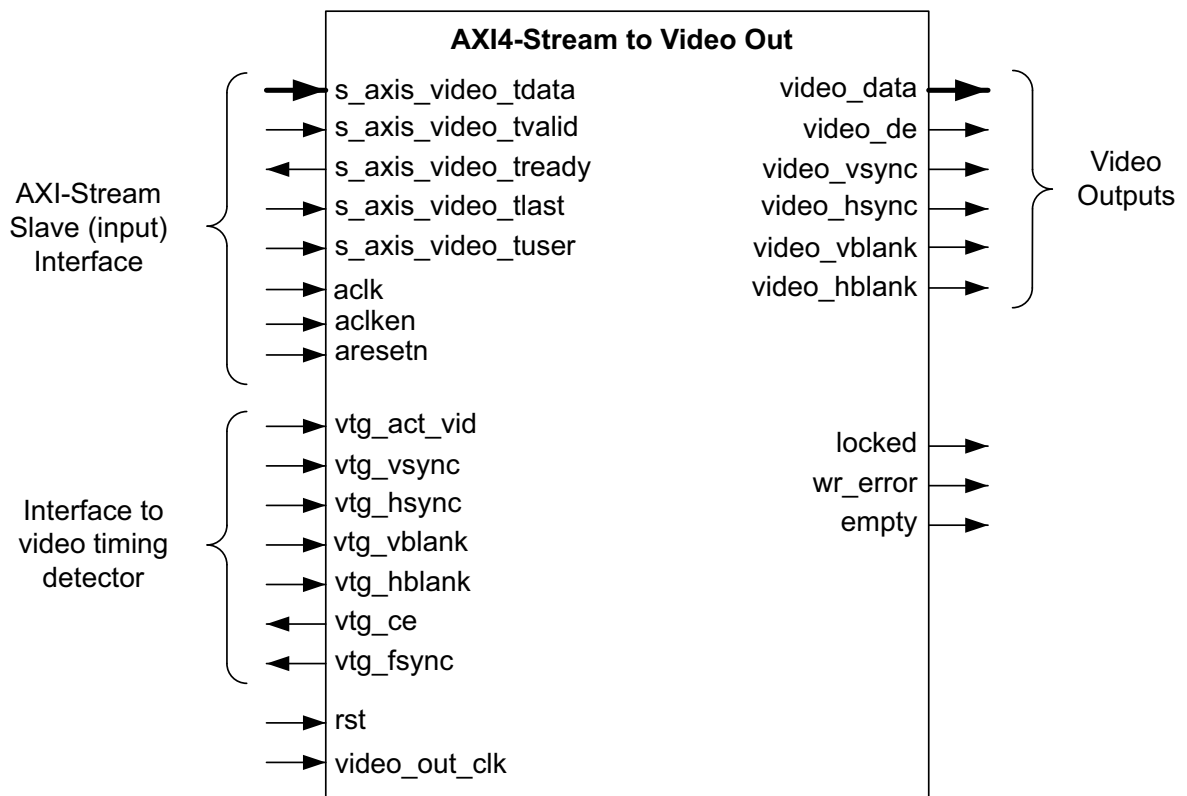


Figure 2-1: AXI4-Stream to Video Out Core Top-Level Signaling Interface

## Common Interface

Table 2-7: Port Name I/O Width Description

Signal Name	Direction	Width	Description
rst	In	1	Core reset. Active High
wr_error	Out	1	Active HIGH FIFO write error flag. 1 = FIFO write was attempted when FIFO was full.
empty	Out	1	Active HIGH FIFO empty flag. 1 = FIFO read was attempted when FIFO was empty. Due to EOL flushing, this flag will be asserted at the end of every line during normal operation.
locked	Out	1	Flag indicating whether the output timing is locked to the output video. 1= locked.

## Timing Controller Interface

Table 2-8: Port Name I/O Width Description

Signal Name	Direction	Width	Description
vtc_vsync	In	1	VTC vertical sync. Active High
vtc_hsync	In	1	VTC horizontal sync. Active High
vtc_vblank	In	1	VTC vertical blank. Active High
vtc_hblank	In	1	VTC horizontal blank. Active High
vtc_act_vid	In	1	VTC active video signal. 1 = active video, 0 = blanked video
vtc_ce	Out	1	VTC clock enable. Used to halt the timing generator for synchronization purposes.
vtc_fsync	Out	1	Currently not used. Should be left unconnected.

## Data Interface

The AXI4-Stream to Video Out core receives video via the AXI4-Stream slave interface defined in the *Video IP: AXI Feature Adoption* section of the [UG761 AXI Reference Guide](#). This video is output as parallel video data along with timing signals from a VTC.

## Video Output Interface

Table 2-9: Video Output Interface

Signal Name	Direction	Width	Description
vid_out_clk	In	1	Video clock
video_de	Out	1	Video output data enable. 1 = active video, 0 = blanked video

Table 2-9: Video Output Interface

Signal Name	Direction	Width	Description
video_vsync	Out	1	Video output vertical sync. Active HIGH
video_hsync	Out	1	Video output horizontal sync. Active HIGH
video_vblank	Out	1	Video output vertical blank. Active HIGH
video_hblank	Out	1	Video output horizontal blank. Active HIGH
video_data	Out	8-64	Parallel video output data. Active HIGH

## AXI4-Stream Signal Names and Descriptions

Table 2-10 describes the AXI4-Stream signal names and descriptions.

Table 2-10: AXI4-Stream Data Interface Signal Descriptions

Signal Name	Direction	Width	Description
s_axis_video_tdata	In	8,64	Input Video Data
s_axis_video_tvalid	In	1	Input Video Valid Signal
s_axis_video_tready	Out	1	Input Ready
s_axis_video_tuser	In	1	Input Video Start Of Frame
s_axis_video_tlast	In	1	Input Video End Of Line
ACLK	In	1	Clock
ACLKEN	In	1	Clock Enable
ARESETn	In	1	Active low synchronous

The ACLK, ACLKEN and ARESETn signals are shared between the core, the AXI4-Stream data interfaces, and AXI4-Lite control interfaces in the system.

### ACLK

The AXI4-Stream interface must be synchronous to the core clock signal ACLK. AXI4-Stream input signals are sampled on the rising edge of ACLK. AXI4-Stream output signal changes occur after the rising edge of ACLK.

### ACLKEN

The ACLKEN pin is an active-high, synchronous clock-enable input pertaining the AXI4-Stream interface. Setting ACLKEN low (de-asserted) halts the operation despite rising edges on the ACLK pin. Internal states are maintained, and output signal levels are held until ACLKEN is asserted again. When ACLKEN is de-asserted, AXI4-Stream inputs are not sampled, except ARESETn, which supersedes ACLKEN.

## ARESETn

The ARESETn pin is an active-low, synchronous reset input. ARESETn supersedes ACLKEN, and when set to 0, the core resets even if ACLKEN is de-asserted.

## Video Data

The AXI4-Stream interface specification restricts TDATA widths to integer multiples of 8 bits. Therefore, for some input data widths, data must be padded with zeros on the MSB to form a module N\*8-bit wide vector before connecting to s\_axis\_video\_tdata.

Data on the AXI-4 Stream input s\_axis\_video\_tdata is packed and padded to multiples of 8 bits as necessary. Figure 2-10 shows an example for 12-bit RGB data. Zero padding the most significant bits is only necessary for 10, 12, and 14 bit wide data. The size of the core is affected by the width of the video data and by the amount of padding required.

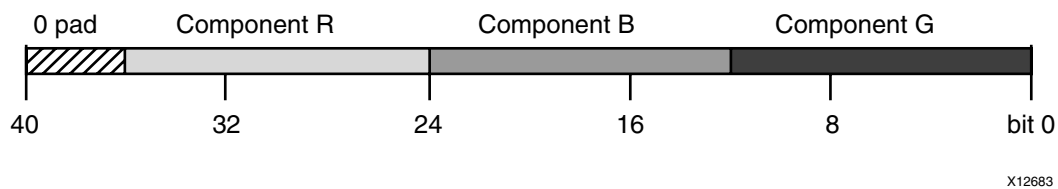


Figure 2-2: RGB Data Encoding on m\_axis\_video\_tdata

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## READY/VALID Handshake

A valid transfer occurs whenever READY, VALID, ACLKEN, and ARESETn are high at the rising edge of ACLK, as seen in Figure 2-3. During valid transfers, DATA only carries active video data. Blank periods and ancillary data packets are not transferred via the AXI4-Stream video protocol.

## Guidelines on Driving s\_axis\_video\_tvalid

Once s\_axis\_video\_tvalid is asserted, no interface signals (except the Video in to AXI-4 Stream core driving s\_axis\_video\_tready) may change value until the transaction completes (s\_axis\_video\_tready, s\_axis\_video\_tvalid ACLKEN high on the rising edge of ACLK). Once asserted, s\_axis\_video\_tvalid may only be de-asserted after a transaction has completed. Transactions may not be retracted or aborted. In any cycle following a transaction, s\_axis\_video\_tvalid can either be de-asserted or remain asserted to initiate a new transfer.

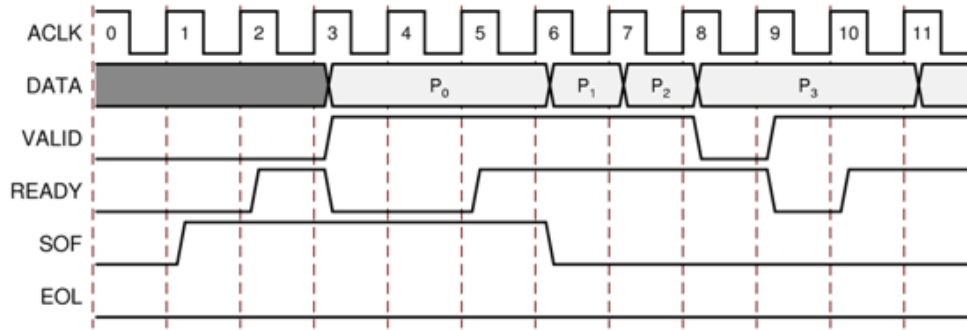


Figure 2-3: Example of READY/VALID Handshake, Start of a New Frame

### Start of Frame Signals - s\_axis\_video\_tuser

The Start-Of-Frame (SOF) signal, physically transmitted over the AXI4-Stream TUSER0 signal, marks the first pixel of a video frame. The SOF pulse is 1 valid transaction wide, and must coincide with the first pixel of the frame, as seen in Figure 2-3. SOF serves as a frame synchronization signal, which allows downstream cores to re-initialize, and detect the first pixel of a frame. The SOF signal may be asserted an arbitrary number of ACLK cycles before the first pixel value is presented on DATA, as long as a VALID is not asserted.

### End of Line Signals - s\_axis\_video\_tlast

The End-Of-Line signal, physically transmitted over the AXI4-Stream TLAST signal, marks the last pixel of a line. The EOL pulse is 1 valid transaction wide, and must coincide with the last pixel of a scan-line, as seen in Figure 2-4.

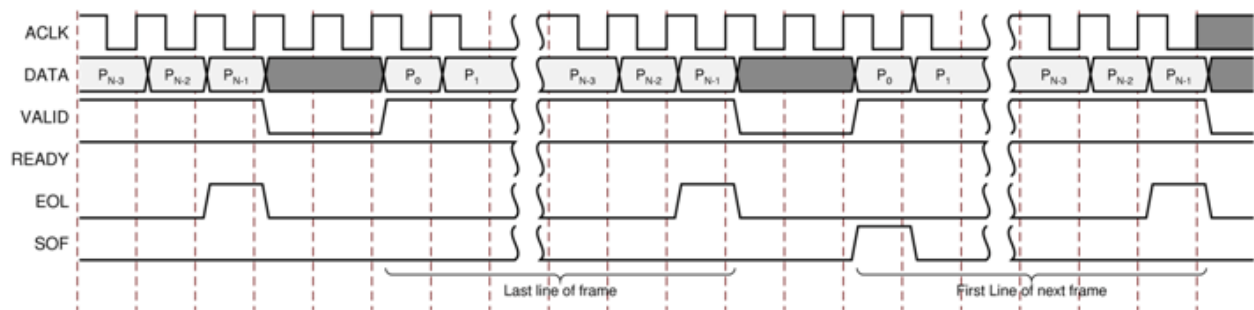


Figure 2-4: Use of EOL and SOF Signals

# Customizing and Generating the Core

This chapter includes information on using Xilinx tools to customize and generate the core.

## Graphical User Interface (GUI)

The Xilinx AXI4-Stream to Video Out core is easily configured to meet the developer's specific needs through the CORE Generator™ GUI. This section provides a quick reference to parameters that can be configured at generation time.

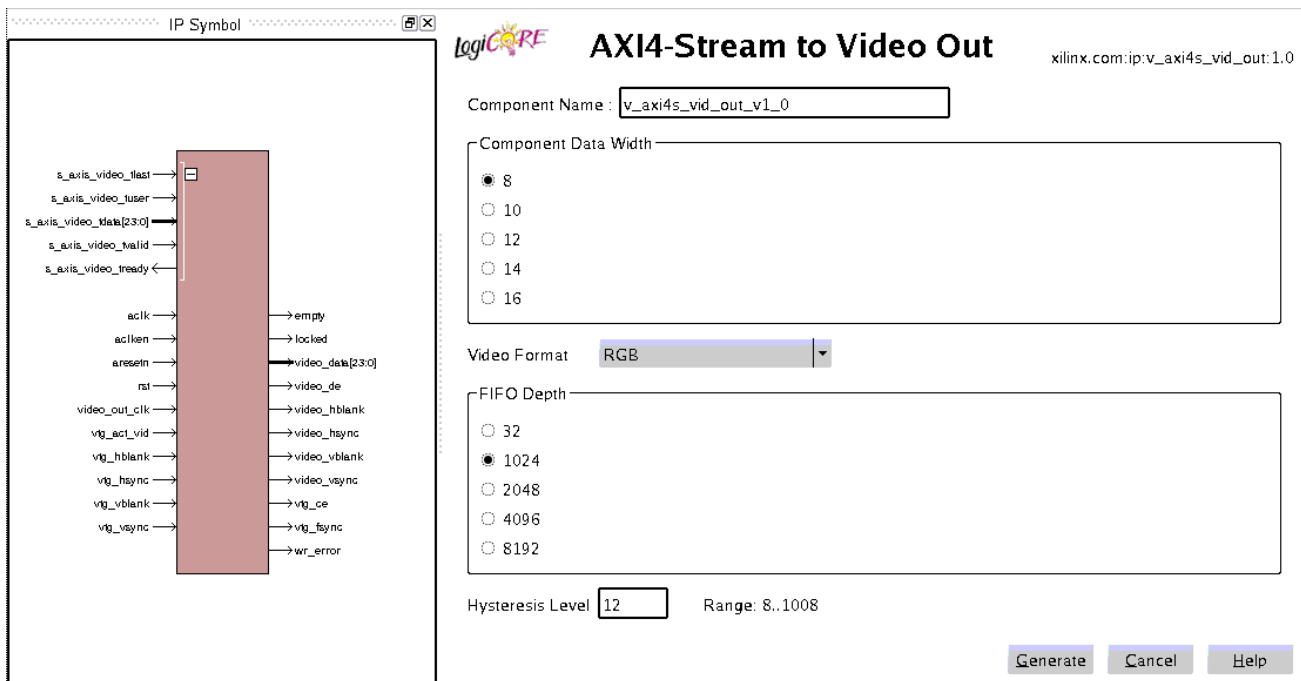


Figure 3-1: Video In to AXI-4 Stream Interpolation CORE Generator GUI

The GUI displays a representation of the IP symbol on the left side, and the parameter assignments on the right side, which are described as follows:

- **Component Name:** The component name is used as the base name of output files generated for the module. Names must begin with a letter and must be composed from characters: a to z, 0 to 9 and "\_".



- **Component Width:** Specifies the bit width of input samples. This is used in conjunction with the Video Format to determine the width of the input AXI4-Stream data interface, `s_axis_video_tdata`, and the output video bus, `vid_data`.
- **Video Format:** Specifies the video format used. The video formats are specified in the *Video IP: AXI Feature Adoption* section of the [UG761 AXI Reference Guide](#). The format selected determines the number of components used. The number of components (1-4) is multiplied by the component width to determine the width of the video data bus, `v_data`. In turn, this width is rounded up to the nearest factor of 8 to determine the width of the AXI4-Stream data bus, `m_axis_video_tdata`. For example, if the component width is 10 and the Video Format is YUV 4:2:2 (2 components), the `vid_data` will be 20 bits wide and `s_axis_video_tdata` will be 24 bits.
- **FIFO Depth:** Specifies the number of locations in the input FIFO. The options for FIFO depth are 32, 1024, 2048, 4096, and 8192.
- **Hysteresis Level:** Defines the "Cushion" level of the frame buffer. i.e. the number of locations that are considered the minimum fill level for FIFO operation to start. This number must be at least 16 less than the depth of the FIFO.

# Designing with the Core

## General Design Guidelines

The video outputs of the AXI4 Stream to Video Out core should be connected to the output video sink, for example, a DVI interface chip that accepts parallel video data and timing signals. Not all of the timing signals supplied by the Video Timing Controller core are required internally by this core, however it also passes these signals out to the Video output. Therefore all timing signals are present. The data enable and vertical sync input are required. It is recommended that the Xilinx Video Timing Controller be configured to output all syncs and blanks (horizontal sync, horizontal blank, vertical sync, vertical blank, and active video).

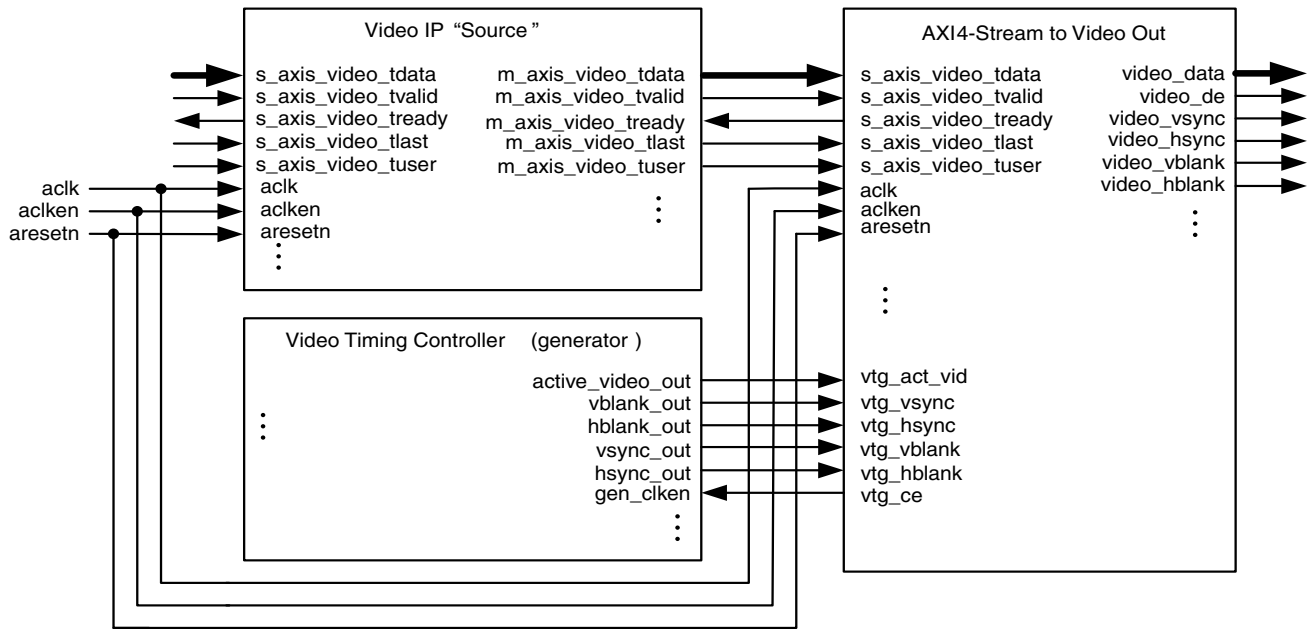


Figure 4-1: Example of ACLK Routing and AXI4-Stream Interconnect

The video data input of the core is a slave AXI-4 Stream Video Protocol interface, that connects to upstream video processing blocks as shown in Figure 4-1. The master and slave interfaces share a common clock, reset and clock enable.

As shown in figure Figure 4-1 the AXI4-Stream to Video Out core is used in conjunction with the Video Timing Controller which generates the video timing used for the video

output. The timing parameters for the Video Timing Controller must match the video line standard (active pixels per line and active lines per frame) of the video data on the AXI4-Stream interface. Otherwise, it is impossible for the output\_sync section to lock the VTC timing to the incoming video. Also, the video clock must be synchronous with the original source of the video on the AXI4-Stream bus. That is, both the AXI4-Stream video and the video timing controller must be roughly isochronous such that the frame rates are identical, with no long term drift.

## Clocking

There are two clocks used in this core.

- Video output pixel clock
- AXI4-Stream clock

The video output clock corresponds to the video line standard used on the output. It is part of the video line standard definition, and is used by both the AXI4-Stream to Video Out core and by the corresponding Video Timing Controller core that is used to generate video timing.

The AXI4-Stream clock (aclk) is part of the AXI4-Stream bus. To minimize buffering requirements, this clock should be of equal or higher frequency than the video output clock. This clock can be slower than the video clock, in which case, additional buffering is required to store pixels so that lines can be output at the burst rate of the video clock. This is discussed in the [Buffer Requirements](#) section. At a minimum, the aclk frequency must be higher than the average pixel rate.

## ACLKEN

The ACLKEN pin disables the AXI4-Stream side of the asynchronous FIFO, as seen in [Figure 4-1](#).

The ACLKEN pin facilitates:

- Multi-cycle path designs (high speed clock division without clock gating),
- Standby operation of subsystems to save on power
- Hardware controlled bring-up of system components

**Note:** When ACLKEN (clock enable) pins are used (toggled) in conjunction with a common clock source driving the master and slave sides of an AXI4-Stream interface, to prevent transaction errors the ACLKEN pins associated with the master and slave component interfaces must also be driven by the same signal ([Figure 2-2](#)).

**Note:** When two cores connected via AXI4-Stream interfaces, where only the master or the slave interface has an ACLKEN port, which is not permanently tied high, the two interfaces should be connected via the AXI4-Stream Interconnect or AXI-FIFO cores to avoid data corruption ([Figure 2-3](#)).

## Resets (ARESETn and rst)

In general, the core does not need to be reset during normal operation. The core will continuously and automatically attempt to lock the video output to the incoming AXI4-video stream until successful. The state machine in the output synchronizer block detects when the video is not locked to the AXI4-Stream. It resets the FIFO and starts an initialization sequence. Whenever it is detected that the output is not locked, the reset and initialize sequence is repeated.

There are two external resets provided: `rst`, which resets the entire core, and `aresetn`, which resets the AXI4-stream interface. Both resets cause the FIFO to be reset. The `rst` additionally causes the state machine of the `out_sync` module to be reset to a condition that is ready to attempt to lock on to the incoming AXI4-Stream. When asserted, the reset should be held for least two clock periods of the lowest frequency clock.

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## System Considerations

### Buffer Requirements

The FIFO depth is selectable via the GUI when the core is generated. The buffering requirement for the asynchronous FIFO depends mainly on the relative data rate between the upstream processor via the AXI4-Stream clock (`ac1k`) and the video output clock (`video_out_clk`) frequency, and also the line standard being used. Basically, if the upstream AXI4-Stream source cannot provide data at a sustained rate equal to or greater than the video clock rate, then additional buffering is required to store up incoming pixels ahead of when they are required such that a continuous stream of pixels can be generated at the output without emptying the FIFO prematurely. The AXI4-Stream to Video Out core will accept AXI4-Stream data as soon as it is available (i.e. it will not apply back pressure) until its FIFO is almost full.

If the sustained pixel rate available from the AXI4-Stream clock ( $F_{ac1k}$ ) is equal to or greater than Video Output pixel clock ( $F_{vclk}$ ), only the minimum buffer size (32 locations) is required. In this scenario, the FIFO will go empty after the EOL on each line.

If  $F_{ac1k}$  is less than  $F_{vclk}$ , additional buffering is required. The FIFO must store enough pixels to supply pixels continuously throughout the active line. Additionally, due to phasing requirements, the horizontal active period on the output will overlap the effective blanking period of pixels coming in from the AXI4-Stream bus. This means that the output FIFO must also be large enough to provide output pixels continuously during this time.

For upstream bandwidth above the line average but below that of `vclk`, the minimum FIFO initial fill level must be:

$$\text{FIFO Initial Fill Level} = 32 + T_{\text{hblank}}/F_{\text{vclk}} + (T_{\text{hactive}} - T_{\text{hblank}}) * F_{\text{vclk}}/F_{\text{ac1k}}$$

where  $T_{blank}$  is the duration of the horizontal blank and  $T_{active}$  is the duration of the horizontal active period.

This is the level needed to keep the FIFO from running dry each line. This fill level is automatically established by the output synchronization mechanism, and is not dependent on the Hysteresis Level of the generated core.

The total FIFO depth must be slightly larger than the initial fill level to prevent overflow of the FIFO:

$$\text{FIFO depth min} = 32 + \text{FIFO initial Fill Level}$$

In every case, this is less than a full line of data, so if a line buffer is provided, it will be sufficient. However, in many cases, a full line buffer is not required.

---

## Module Descriptions

As shown in [Figure 1-1](#), the AXI4-Stream to Video Output core works with the generator portion of the Video Timing Controller (VTC) core.

The timing outputs of the VTC connect as inputs to the AXI4-Stream to Video Output core. When locked, these timing signals are output along with video data from the FIFO as part of the video interface. These signals are also used by the Output Synchronizer, to compare to flags from the FIFO in order to guide the control action for locking the timing generator with FIFO data.

[Figure 1-1](#) shows a block diagram of the AXI4-Stream to Video Out core. There are three main blocks, the stream coupler, the data formatter, and the output synchronizer. The AXI4-Stream interface is on the left, and the video connections are on the right.

### Stream Coupler

The Stream Coupler block consists mainly of an asynchronous FIFO and write logic for the input side of the FIFO. Reading of the FIFO is controlled by the Output Synchronizer. The FIFO serves two primary purposes:

1. Clock domain crossing
2. Buffering of data between the AXI4-Stream input and the video output.

The buffering requirements are dependent on the ratio of the AXI4-Stream data rate to the video clock rate. This is described further in [System Considerations in Chapter 4](#).

## Asynchronous FIFO

The crossing of clock domains dictates that this be an asynchronous FIFO. The FIFO designed for this core has two important distinguishing features:

1. It has status flags and a fill level output in both clock domains.
2. An "invalid" (read\_error) flag is produced in parallel with output data for the useful case of reads when the FIFO is empty. It also has pointer inhibiting logic to prevent pointer crossings on underflow and overflow.

This asynchronous nature of the FIFO presents challenges for the fill level indicators and the flags. The chief risk is that pointer values could glitch when being sampled from one clock domain to another. Thus, there must be pointer synchronization across clock domains, and there must be a handshaking protocol to insure that all pointer updates are seen even when the clock rate in the two domains are radically different. Figure 4-2 is a block diagram of the asynchronous FIFO. Note the synchronizing logic and the handshaking between clock domains. The size of the FIFO is set in the GUI when the core is generated.

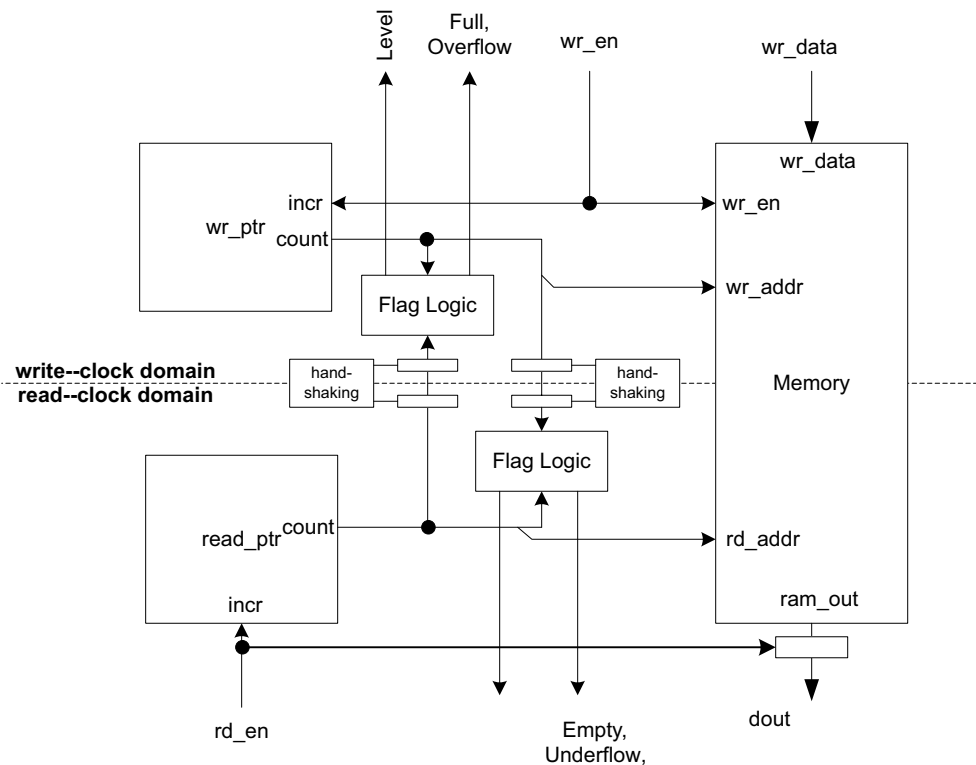


Figure 4-2: Block Diagram of Bridge Core Asynchronous FIFO

Synchronized Gray codes are commonly used in asynchronous FIFOs to eliminate the problems of synchronizing multiple counter bits changing on the same clock edge. However, instead of Gray code pointers, the FIFO for the Video In to AXI4-Stream core uses binary pointers synchronized via handshaking. The main reason is that calculating the fill

level, which is used integrally in the read logic, is simple with binary pointers but impractical with gray code pointers.

### Clock Domain Crossing of Pointers

The synchronization and handshaking for pointers is shown in detail in Figure 4-3. The first two register delays are required to resolve metastability. The third is to insure that the register has time to take the data before the handshaking is returned. Otherwise if the clock in one domain were several times faster than the other, there is a chance that the handshaking could be returned, before the pointer register is updated in the slower clock domain.

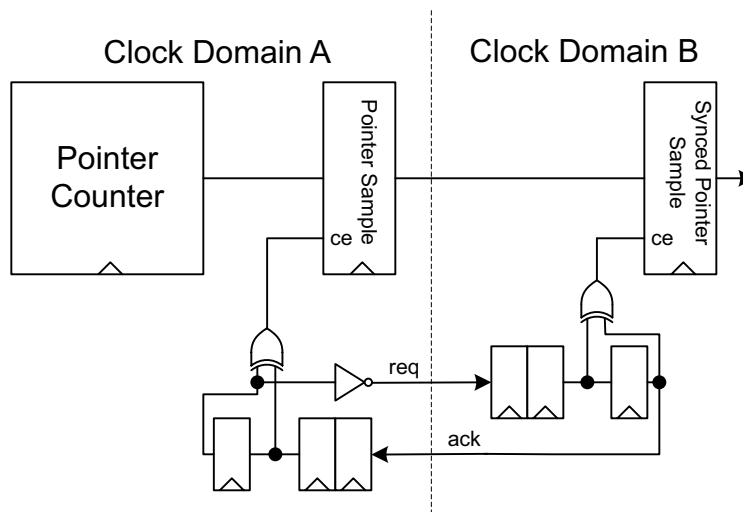


Figure 4-3: Synchronization and Handshaking for Clock Domain Crossing of Pointers

The extra delay for turning around the handshaking signal insures that data will be transferred reliably no matter what the relative clock rates. i.e. if  $F_a > 2F_b$  each "req" is still guaranteed to update the sync pointer in domain B. By the same token, if  $F_b > 2F_a$ , each ack is guaranteed to update the pointer sample in domain A. Figure 4-4 shows an example of pointer synchronization between clock domains, and the handshaking scheme shown in Figure 4-3. This handshaking scheme, utilizes two states: request and acknowledge. The "request" state is when Req and Ack are not equal, and "acknowledge" is when they are equal.

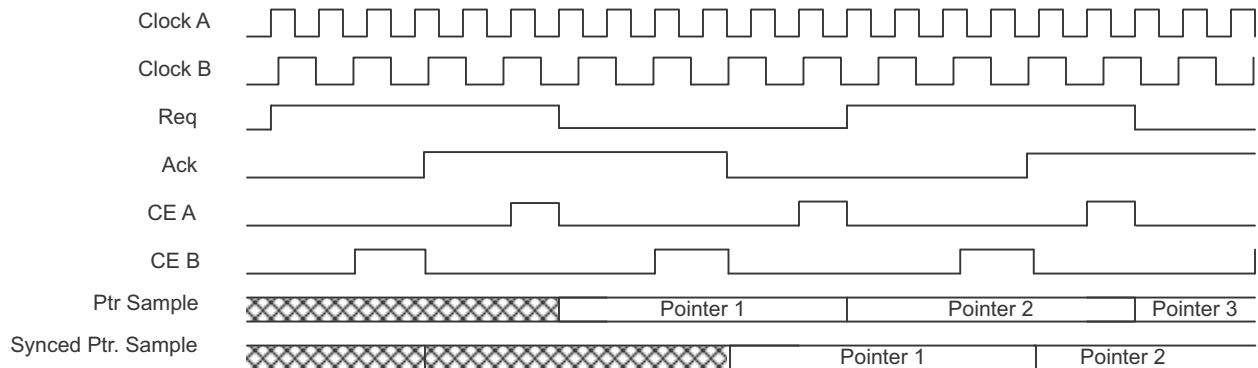


Figure 4-4: **Waveform Diagram of Handshaking and Clock Domain Crossing of Pointers**

This sample and hold method with handshaking delays the capture of the pointers by several clock edges in each domain but the pointer transfers are always reliable and glitch free. The latency of the pointers causes pessimism in the level outputs, and the flags. That is, the empty flag will persist in the read domain for several clocks after a write has occurred, etc. Also, the level output will not necessarily be monotonic. This is taken into account in the design of the bridges by providing a small “cushion” or minimum fill level in the FIFOs so that the pointer pessimism does not cause artifacts.

### Underflow Prevention

Besides synchronizing flags, it is not enough to signal an empty condition, because “reads” of the FIFO will not stop on empty. Additional read operations will be performed in order to get the EOF to the output of the FIFO. This will happen routinely, and the FIFO must not lose any data. That is, underflow is not allowed. When new data is eventually written to the FIFO, reading must pick up with the first new valid pixel. To do this, the read pointer is inhibited when the FIFO is empty.

The empty flag asserts coincident with the last available location being clocked into the output register. The read pointer, however is not advanced to match the write pointer but remains pointing at the last valid pixel that was read. Subsequent reads, when empty is asserted, will cause the read\_error flag to be asserted, flagging the pixel from the FIFO as invalid. The data output, however will not change.

Thus, when a read occurs to an empty FIFO, the invalid flag (read\_error) is set, and the read pointer does not increment. In this way, the EOL can be advanced through the pipe by a series of reads on the empty FIFO. With each read, an invalid pixel backfills the advancing EOL but the downstream logic can distinguish these from valid pixels.

### Pointer Format

It is important to provide an accurate level, and to distinguish between full and empty conditions when the read and write pointers are equal. This is done by having extra “revolution” bits on the pointers in addition to the address bits as shown in Figure 4-5.





the video output interface. The locked signal from the output synchronizer is used to enable the video interface. Before lock is achieved, the video outputs are all forced low.

## Output Synchronizer

A major task for the AXI4-Stream to Video Out core is to synchronize the asynchronous and irregularly timed video data from AXI4 Stream interface with the periodic and repeatable timing signals from the VTC. In the slave mode supported by the core, the timing of the data in the pipeline on the AXI-Stream interface cannot be controlled. Therefore, the synchronization is done mainly by controlling the phase of the VTC. This function is performed by the Output Synchronizer block in [Figure 1-1](#). Also, the data from the AXI4-Stream interface goes into a FIFO to be able to smooth out small and short-term latency variations that occur during the course of a frame. The phase of the VTC must have some additional lag, such that the FIFO will have a sufficient fill level to cushion the short-term variations.

Since the video input source may be disconnected or change line standards, the Video Output Bridge must constantly compare the timing of incoming video data relative to the timing of the VTC. This makes it possible to detect timing mismatches so that it can re-synchronize after any type of interruption. Thus, it must be self monitoring and self synchronizing. [Figure 4-10](#) shows a block diagram of the output synchronizer.

### Algorithm

The operation of the self synchronizing circuit can be broadly defined in two steps: initialization and run. In the run mode, alignment must be continually checked and if there is a discrepancy, a new initialization is required, as shown in [Figure 4-6](#).

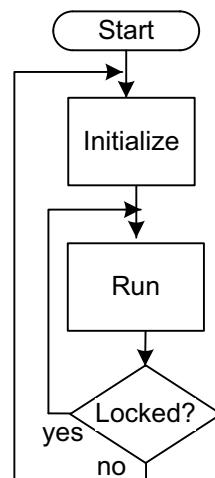
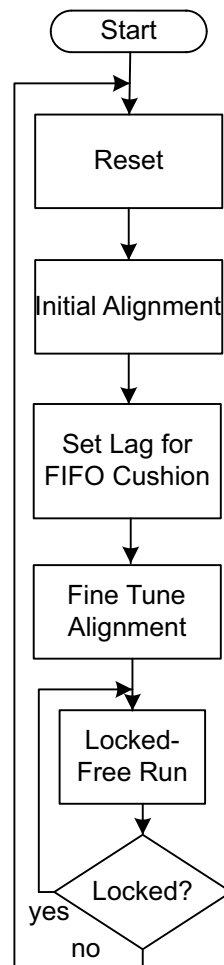


Figure 4-6: Basic Self Synchronizer Flow Chart

The initialization phase does an alignment of the VTC to the AXI4-Stream data, provides for some cushion in the FIFO, and precisely aligns the video data from the FIFO to the VTC

generated video output signals. [Figure 4-7](#) shows the initialization steps.



**Figure 4-7: Self Synchronizer Flow Chart Showing Initialization Steps**

The initial alignment of VTC generated video output signals to the FIFO is done by letting the VTC free run until it reaches the point of the first valid pixel of the first line of the frame (SOF). At this point, the VTC is paused using the clock enable of the VTC. The FIFO is read as fast as possible, keeping it essentially empty, and the start of field (SOF) flag is monitored. When VTC SOF is asserted, the FIFO data and the VTC generated video output signals are roughly aligned. This is the initial alignment.

At this juncture, the FIFO is paused for some additional period, nominally about 16 clocks, such that when the FIFO output data and VTC generated video output signals are aligned, the FIFO has some pixels stored to cushion any short term variations in the input data rate.

With a rough alignment, and a cushion set for the FIFO, The last step is to fine tune the FIFO output/VTC generated video output signals alignment such that the end of line (EOL) flags read from the FIFO precisely match the last clock of Data Enable from the VTC before the horizontal blanking period. The fine tuning process is shown in more detail in [Figure 4-8](#).

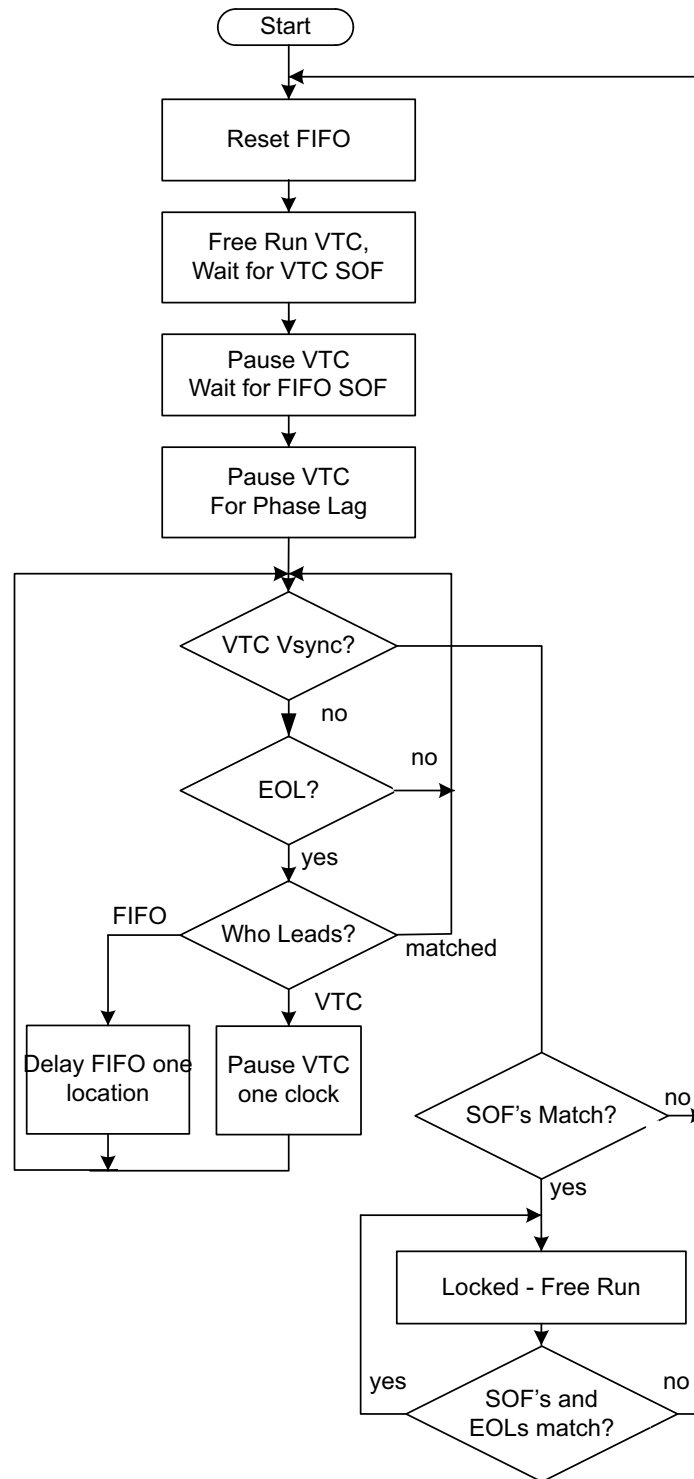


Figure 4-8: Self Synchronizer Flow Chart Showing Fine Tuning Process

During the first frame time after rough alignment, the EOLs from the FIFO and from the VTC (or rather the EOL signal derived from Data Enable) are compared every line. If the VTC is leading, it is paused by one clock. If the FIFO is leading, the reading of the FIFO is delayed by one location. In this manner, the EOLs will be aligned after several lines, typically a dozen

or two. Typically, the FIFO will be leading because the VTC has an additional pause after rough alignment, but due to startup idiosyncrasies, this is not guaranteed. Delaying the FIFO read has the effect of building up a cushion in the FIFO. Even though the FIFO delay is exercised most often, the VTC delay must be included to assure reliable synchronization in every situation.

At the end of the frame, the EOL's are aligned via the fine tuning process, and there is a cushion of pixels in the FIFO. However, since the FIFO must empty completely at the end of each line in order to flush the EOL through to the video output, This cushion will be used up at the end of each line. Nevertheless, the phase lag of the VTC generated video output signals insures that the cushion is built up at the start of the next line such that it can smooth out variations during the active line.

When the Vsync from the VTC becomes active, the EOLs from the FIFO and the VTC are aligned, and if everything is stable, the SOF's will also be aligned. If the SOF's are aligned, then the locked mode is entered. In this mode, the VTC free runs, and the FIFO is read as dictated by the VTC. The Video output is enabled such that pixel data, and timing signals are output from the bridge. This is the run state, that can continue indefinitely.

The EOL's and SOF's are continuously compared while the output is locked. If they ever do not match, the system is considered unlocked and a new initialization cycle is initiated. In the case of a disconnected or unstable input to the system, initialization cycles will be repeated until the system is stable.

Figure 4-9 shows the flow charts in previous figures and how the stages correspond in the various levels of detail.

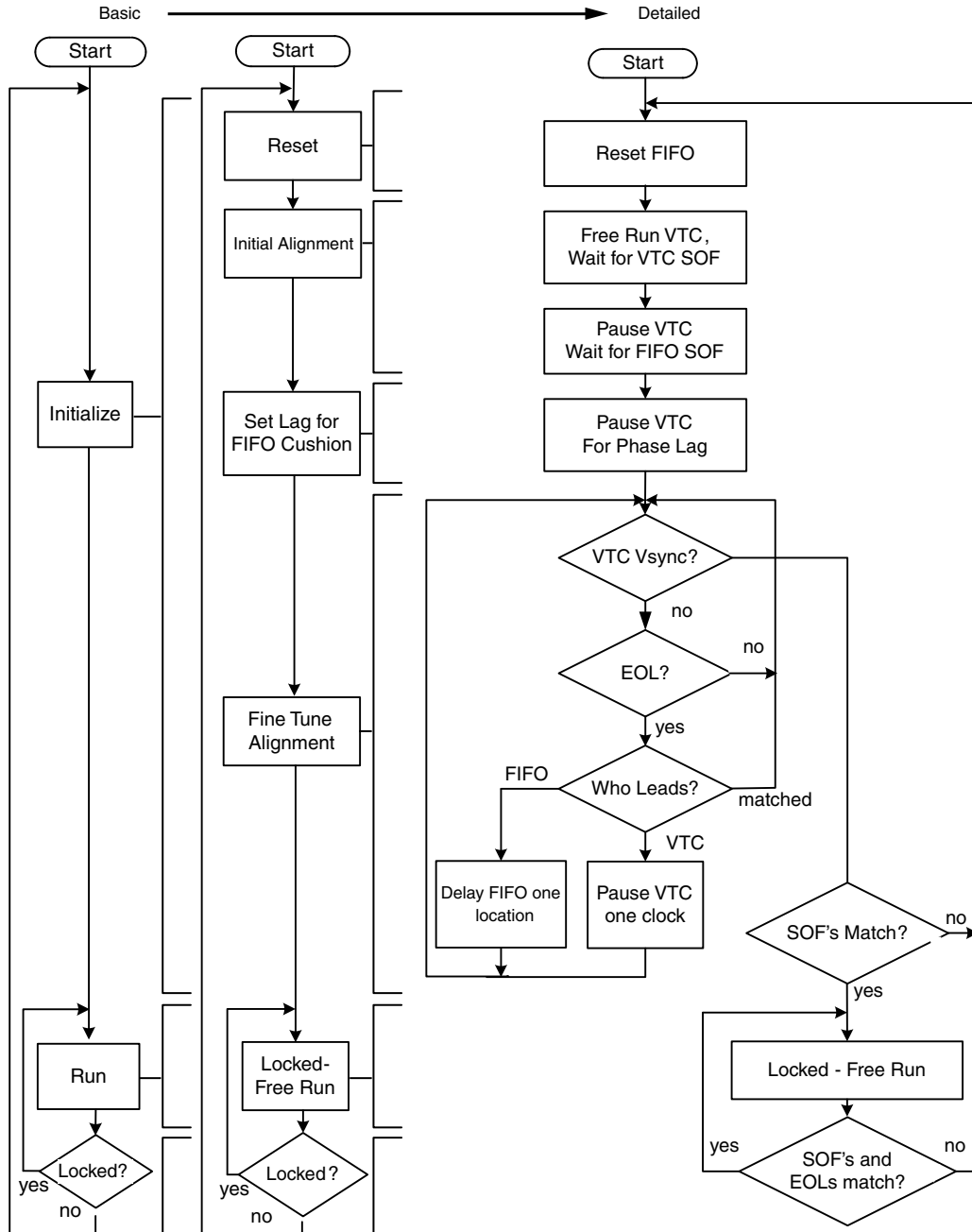


Figure 4-9: Flow Charts from Basic to Detailed Showing Equivalencies

### Implementation

The output synchronizer is shown in Figure 4-10. This is essentially a state machine that implements the algorithm described in the previous section. The control outputs are all registered, and reflect the current state. That is, the control outputs are pre-decoded, rather than being decoded based on the current state.

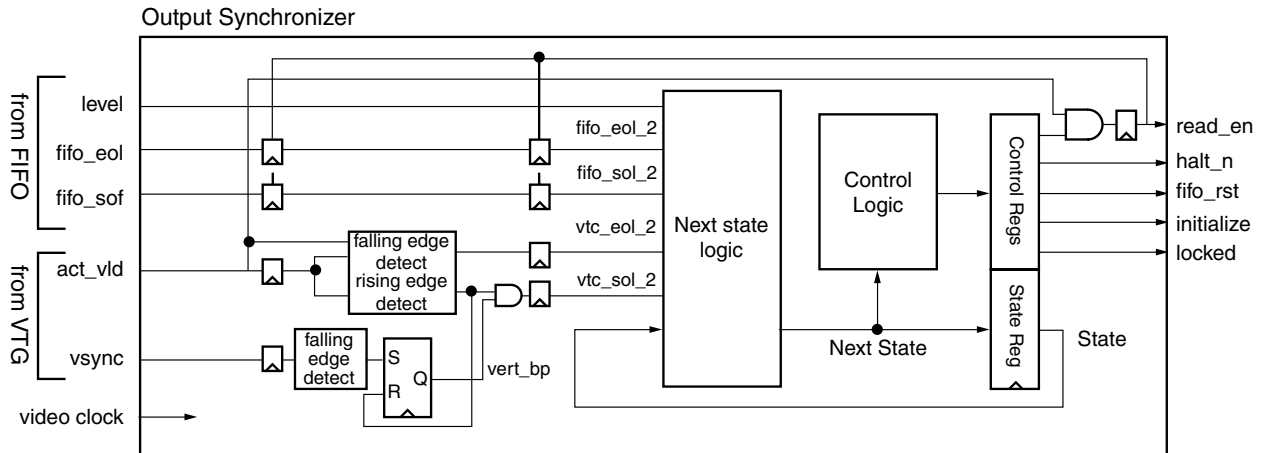


Figure 4-10: Output Synchronizer Block Diagram

Besides the state machine, there is logic to create virtual EOL and SOF flags from the VTC generated video output signals. These flags are created based on edges of the act\_vld (a.k.a. data enable or DE) from the VTC. The vsync input is used to distinguish the SOF. Also there is additional logic to create the FIFO read\_en signal based on the act\_vid from the VTC as well as control bits from the state machine. The read\_en output has a register after the state machine to insure that all outputs of the module are registered.

Figure 4-11 is a state diagram of the state machine of the output synchronizer. It follows the initialize-run algorithm described earlier in this document. Initialization consists of a coarse alignment, setting additional lag, and fine tuning. When the EOL's are aligned, and matching SOF's occur, the state machine goes to the "EOL's Matched" state. If matching SOF's occur a second time, the "Locked" state is entered, which concludes initialization. It will remain in this state as long the system is stable.

The initialization process is done over three frame times. The first is waiting for the FIFO SOF. The second is for the fine tuning to align EOL's. The third is basically a double check that the EOL's and SOF's are aligned. If an SOF mismatch occurs during fine tuning, it means that fine tuning has failed to align within the frame time. In this case, the initialization process is re-started. Also, in the "EOL's Matched" or "Locked" states, EOL and SOF matching is continuously checked. If there is any mismatch, it means the output is unlocked, and the initialization is re-started.

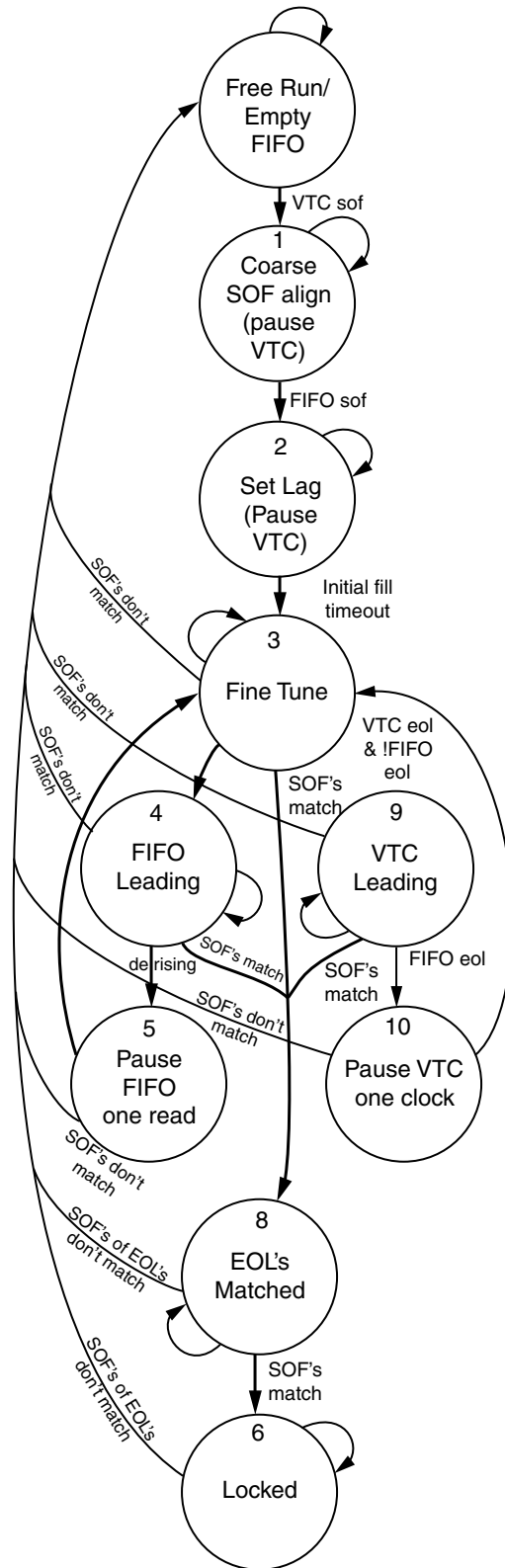


Figure 4-11: Output Synchronizer State Diagram



# Constraining the Core

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## Required Constraints

The only constraints required are clock frequency constraints for the video clock, `video_clk_out`, and the AXI4-Stream clock, `aclk`. Paths between the two clock domains should be constrained as false paths, which should be ignored during timing analysis.

For example, here is some UCF code that could be used to constrain the video clock and the AXI4-Stream Clock for 150MHz operation:

```
NET vid_out_clk TNM_NET = vid_out_clk;
TIMESPEC TS_vid_out_clk = PERIOD vid_out_clk 150 MHz HIGH 50%;
NET aclk TNM_NET = aclk;
TIMESPEC TS_aclk = PERIOD aclk 150 MHz HIGH 50%;

TIMESPEC TS_vid_out_clk_to_aclk = FROM vid_out_clk TO aclk TIG;
TIMESPEC TS_aclk_to_vid_out_clk = FROM aclk TO vid_out_clk TIG;
```

---

## Device, Package, and Speed Grade Selections

There are no device, package, or speed grade requirements for this core. For a complete listing of supported devices, see the [release notes](#) for this core.

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## Clock Frequencies

The pixel clock frequency is the required frequency for this core. See [Maximum Frequencies in Chapter 2](#).

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## Clock Management

There are two clock domains for this core. The clock crossing boundary is handled by the FIFO, and a handshaking system for passing pointers between domains.

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## Clock Placement

There are no specific Clock placement requirements for this core.

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## Banking

There are no specific Banking rules for this core.

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## Transceiver Placement

There are no Transceiver Placement requirements for this core.

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## I/O Standard and Placement

There are no specific I/O standards and placement requirements for this core.

## Detailed Example Design

No example design is available at the time for the AXI4-Stream to Video Out v1.0 core.

For a comprehensive listing of Video and Imaging application notes, white papers, reference designs and related IP cores, see the Video and Imaging Resources page at:

[http://www.xilinx.com/esp/video/refdes\\_listing.htm#ref\\_des](http://www.xilinx.com/esp/video/refdes_listing.htm#ref_des).

# Additional Resources

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## Xilinx Resources

For support resources such as Answers, Documentation, Downloads, and Forums, see the Xilinx Support website at:

<http://www.xilinx.com/support>.

For a glossary of technical terms used in Xilinx documentation, see:

[http://www.xilinx.com/support/documentation/sw\\_manuals/glossary.pdf](http://www.xilinx.com/support/documentation/sw_manuals/glossary.pdf).

For a comprehensive listing of Video and Imaging application notes, white papers, reference designs and related IP cores, see the Video and Imaging Resources page at:

[http://www.xilinx.com/esp/video/refdes\\_listing.htm#ref\\_des](http://www.xilinx.com/esp/video/refdes_listing.htm#ref_des).

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## Solution Centers

See the [Xilinx Solution Centers](#) for support on devices, software tools, and intellectual property at all stages of the design cycle. Topics include design assistance, advisories, and troubleshooting tips.

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## References

These documents provide supplemental material useful with this user guide:

1. [UG761 AXI Reference Guide](#)

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## Technical Support

Xilinx provides technical support at [www.xilinx.com/support](http://www.xilinx.com/support) for this LogiCORE™ IP product when used as described in the product documentation. Xilinx cannot guarantee timing, functionality, or support of product if implemented in devices that are not defined in the documentation, if customized beyond that allowed in the product documentation, or if changes are made to any section of the design labeled DO NOT MODIFY.

See the IP Release Notes Guide ([XTP025](#)) for more information on this core. For each core, there is a master Answer Record that contains the Release Notes and Known Issues list for the core being used. The following information is listed for each version of the core:

- New Features
- Resolved Issues
- Known Issues

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## Ordering Information

The AXI4-Stream to Video Out v1.0 core is provided under the [Xilinx Core License Agreement](#) and can be generated using the Xilinx® CORE Generator™ system. The CORE Generator system is shipped with Xilinx ISE® Design Suite software.

Contact your local Xilinx [sales representative](#) for pricing and availability of additional Xilinx LogiCORE IP modules and software. Information about additional Xilinx LogiCORE IP modules is available on the Xilinx [IP Center](#).

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## Revision History

The following table shows the revision history for this document.

Date	Version	Revision
4/24/2012	1.0	Initial Xilinx release of core.

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