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Embedded-BCI: assessment of parallelizing computations on an embedded system

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Abstract: Using Brain-Computer Interfaces (BCI) as an assistive technology aims at providing an innovative solution adapted to subjects’ disabilities. BCI either provide a new interface for controlling solution mobility (e.g. wheelchair) or monitoring the state of user during his/her journey. This would be possible by implementing these interfaces on Embedded Systems (ES). However, because of the BCI sophisticated data processing and the ES limited computation performances, the computation time for a real-time use of the BCI on an ES is a limitation. Hence in this work, we investigate and evaluate the parallelization and acceleration performances, on a Raspberry Pi 2 model B (RPi) board, of an STFT-based algorithm for estimating cognitive workload from an Electroencephalographic (EEG) signal. This is done based on multi-core CPU and GPU architectures of the used RPi. Results show that the parallelized implementation using the CPU runs up to \( \times 4 \) faster than a simple implementation. Compared to CPU of intel-CORE i3 processor, the GPU of the RPi revealed large difference in computation time.

Keywords: BCI, embedded system, parallelization, CPU, GPU, multicore.

I. INTRODUCTION

Nowadays, embedded systems become the highlights of the artificial intelligence (AI) progress. These electronic and computer systems are designed to perform specific tasks while ensuring a high autonomy. This autonomy lies in their capacities to manage their available resources for interacting with all other systems comprising their environment. Although the use of these systems, in recent years, was limited to areas of military, currently the deployment of such systems is widely applied in many other fields, especially transport. Beyond this, ES integrate more and more the human everyday life by seeking to design new assistance tools for disabled people or in situations of extreme dependence. A crucial aspect is to take into account the specificities of each individual and propose technical solutions adapted to their residual motor capacities [1]. In this aspect which is sought to minimize decision errors, the development process is particularly harsh and hence involving more and more formal techniques.

Mobility represents a basic need for people with motor deficiencies to integrate and participate in the social everyday life [2]. In this context, the wheelchair is the most commonly used assistive device to allow both internal and outside mobility. In often cases this device is controlled manually with a joystick. In the case where no residual motor ability is available, paradigms based on non-muscular flows can be used (e.g. eye movements, galvanic skin response and heart rate variation). However, regarding the variability of disabled users, the use of brain signals may represent the reliable control mean. In the context of assistive mobility, Brain-Computer Interfaces (BCIs) provide systems of direct control through non-muscular channels based on brain signals [3],[4],[5]. In this realm, Rebsamen in [6] introduces a control strategy for wheelchair driving based on the P300 Event-Related Potential (ERP) component. Through a GUI, the BCI-based wheelchair system proposes to the user to select his/her decisions to move the wheelchair in a typical building. The paradigm used in this strategy exploits the generation of a positive deflection, P300, in the brain signal. This deflection is measured in the central brain area 300 milliseconds after the reception of a stimulus. This paradigm was introduced for the first time by Farwell and Donchine in their P300 Speller [7]. In the same idea of developing technical solutions to assist mobility and increase motor capacities of disabled people, Tonin in [8] presents a BCI-based approach for controlling a telepresence robot by users with disabilities. Based on their spontaneous brain activity, users drove a telepresence robot from their clinic more than 100 Km away. In order to facilitate the navigation, this approach combines concepts of motor imagery and shared control. The developed system makes use of imagination of movements (e.g. imagining the movement of hands) and an obstacle detector for safety and helping users to keep full control on the robot driving. Results from this approach show that the incorporation of shared control reduces users’ mental efforts.

A part from using BCI for controlling robotic devices [9],[10], [11], recent works were focused on assessing and evaluating mental efforts and workload while using mobility devices. In [12] authors developed an EEG-based approach in order to assess and monitor changes in drivers’ cognitive states while using a virtual reality
methodology for parallelization of the STFT algorithm. Experimental results are described and discussed in sections 4. Finally, conclusions are drawn in the last section.

II. Fourier transform algorithm

Fourier transform is a widely used method for studying non-stationary signals as it gives the time-frequency distribution for many signals:

\[ S(f) = \int_{-\infty}^{+\infty} s(t) e^{-j2\pi ft} dt \]  

by approaching the integral by a sum of rectangular areas of time \( T_e \) and by limiting the integration time to the interval \[ 0, (N - 1) * T_e \] we obtain:

\[ S(f) \approx T_e \sum_{n=0}^{N-1} s(nT_e) e^{-j2\pi fnT_e} \]  

which gives for frequency values \( f_k = k \frac{f_e}{N} \):

\[ S(f_k) \approx T_e \sum_{n=0}^{N-1} s(nT_e) e^{-j2\pi nk\frac{f_e}{N}} \approx T_e \sum_{n=0}^{N-1} s(nT_e) e^{-j2\pi nk} \]  

It is not a sophisticated approximation of \( S(f) \) but is used in practice, as Discrete Fourier Transform (DFT), since there is an effective computing algorithm known as Fast Fourier Transform (FFT) \[ 18 \]. The computation of DFT requires \( N^2 \) complex operations while using the FFT needs only \( N \log_2 N \).

III. Methods and Materials

A. Experimental setups

The first experimental protocol involves controlling an exoskeleton arm using a touchless interface with 5 IR-sensors which allow the displacements in different spatial positions. The touchless interface is complemented by an SSVEP-based BCI. The experimentations rely on the ESTA robotic exoskeleton \[ 19 \]. The EEG data acquisition system uses the g.Mobilab+ device using an acquisition frequency of 256 Hz. The acquisition device is based on 8 channels placed according to the 10-20 international system. All electrodes refer to the right or left earlobe and the ground is placed on Fz as depicted in Figure 1. For SSVEP stimulations, a microcontroller is set up to flash stimuli light emitting diodes (LED) at frequencies 13 Hz, 17 Hz and 21 Hz.

The second experimental protocol consists in measuring the brain activity during the use of an ITS. Equipped with a control tool, the user navigates on the ITS. The BCI-based ITS adapts and presents the learning content to the user depending on his/her mental state and effort. EEG data are measured continuously basing on the g.Mobilab+
acquisition device with 8 channels (Oz, O1, O2, POz, P03, P04, Pz, Iz) and using a sampling rate of 256 Hz. The EEG data are filtered using a pass-band filter for 1-30 Hz.

On another hand, our study exploit a model 2 B RPi board with 1 GB of RAM. The system on chip RAM (Broadcom BCM2836) of the used RRi board contains both a CPU and GPU with independent performances to each other. We decided to use this RPi board model given (Broadcom BCM2836) of the used RRi board contains both a CPU and GPU with independent performances to each other. We decided to use this RPi board model given the multicore architecture that it incorporates.

**B. CPU implementation**

Our parallelization approach on the CPU of the RPi is straight-forward. The implementation makes use of the multi-cores of the RPi. Thanks to the multi-threading architecture incorporated in the used RPi, The 8 EEG channels are distributed among $N_{th}$ threads. On another hand, the implementation takes advantage of the OpenMP library in order to automatically distribute the execution of the STFT code on the used threads. Thus, each thread executes the code separately and calculates its own STFT. An overview of this process is presented in Figure 2.

**C. GPU implementation**

To our knowledge, there is no library or programming language, like CUDA or OpenCL, intended particularly for the parallelization on the GPU of RPi. Works from literature, and which exploited the RPi GPU, used optimized assembler codes. The RPi board has 12 cores inside its GPU, each known as QPU (for Quad Processing Unit). The STFT algorithm implementation could be optimized leveraging these QPUs. A QPU is a 16 Single Instruction Multiple Data (SIMD) processor which allows disposal of vectors of 16 values. Therefore an execution using vectors of 16 values can be done in parallel. On another hand, as the STFT computation uses complex numbers, this implementation requires only two registers to store 16 real number and 16 imaginary number. We denote by Step the computing time unit in which a QPU consumes 16 points. This implies that a QPU performs two steps (one for reals and another for imaginaries) when consuming the 16 points. Thus computing the STFT on 128 points requires $N_{QPU} = 128/16 = 8$ QPUs. The computing time unit in which the 8 QPU consume the 128 points in parallel is denoted by Pass. Thus for computing the STFT on 256 points, 8 QPUs are required using two passes. At the end of each pass, each QPU accesses the Vertex Pipeline Memory (VPM) of the RPi memory in order to write its outcomes.

**IV. RESULTS AND DISCUSSION**

Here we present results with particular attention on computation time. CPU implementation revealed reliable performances. The STFT algorithm was computed using signal windows with various lengths. We considered window lengths of 1s, 2s and 4s. Using EEG data of our experiments, these windows lengths respectively correspond to points numbers of 256, 512 and 1024. Figure 4 shows the gain in the computation time (per seconds) for these different window lengths while using $N_{th}$ threads. There are 3 different parts on the chart. For 1 to 4 threads, the gain in calculation time is very close from the theoretical gain which reflects excellent parallelization. All threads are processed by the processor cores. The system performs as a quad processor. Between 5 and 7 threads, the curve does not follow the theoretical curve and the gain in computation time decreases.
Threads management takes too much time and slows the program. This is due to the fact that the number of threads is less than and not proportional to the number of cores. Beyond 8 threads the gain increases and remains the same even when using 12 threads. On another hand, results show that the gain in computation time increases when increasing the number of points on which the STFT is computed. This reflects that the parallelization is effective when working with window lengths larger than 4s.

Comparing performances of the RPi GPU to those of the CPU of intel-CORE i3 processor revealed the huge gain in computation time offered by the RPi GPU when computing the STFT on larger time-windows.

However the RPi GPU implementation offers promising optimization performances, its use in the design of innovative embedded solutions remains limited. This limitation is due to absence of libraries or programming languages, such as CUDA or OpenCL, which are designed specifically for parallelization on the RPi GPU. Therefore, at present, the development of ES that leverages the GPU of the RPi imposes very high skills in low-level programming using assembler. However, through findings presented in this work, we demonstrate that the parallelism on the CPU of the RPi using the OpenMP library is a robust and efficient alternative solution for accelerating real-time processing of data from time-windows of lengths between 1 and 2 seconds.

CONCLUSION

In this work we studied and assessed performances of parallelization and acceleration of computation on the RPi board for a reliable use of BCI applications. Our investigation consisted on parallelizing a STFT-based algorithm for estimating the brain workload. Our study focused on the STFT parallelizing since it is the most time-consuming part of the brain workload estimation process from a multi-channel EEG signal. Based on the multi-threading and multi-cores architectures included in the RPi, the optimized CPU implementation runs up to \( \times 4 \) faster. On another hand, based on assembler implementation, we evaluated computation performances of parallelizing the STFT algorithm on the RPi GPU. Compared to CPU of intel-CORE i3 processor the GPU of the RPi revealed large difference in computation time. The whole results are motivating to design future RPi-based mobile systems which take advantage from BCIs innovative aspect (e.g. autonomous mobile robots).

REFERENCES


