A Recursive Digital Filter Implementation for Noisy and Blurred Images

This paper presents the design and the implementation of an optimized Canny-Deriche edge detector. After a brief reminder of the filter’s equations, we define different techniques to speed up the sampling rate of the IIR filter. In particular, improving the throughput rate of the IIR filter, we present a look-ahead with decomposition technique. This method leads us to design a first chip, which performs at a sampling rate of over 20 MHz with a silicon area of 60 mm². Using a local register retiming method, we have designed a second circuit, which is able to process a pixel in 30 ns with a silicon area of 30 mm². These two approaches are compared. This work leads us to an ASIC which was designed in a CMOS 1 μm technology and successfully tested.

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Introduction

A part of low level image processing consists of the detection (by filtering) of sharp level variations of luminance in the image to obtain the edge segments, extremities and angles. To select the geometrical information related to the structure of the objects present in an image, a key step consists of extracting the edges of the considered objects. Several accurate numerical algorithms have been proposed in this field: Roberts [1], Prewitt [2], Canny [3], and Deriche [4] have already been implemented in software or with dedicated hardwares for several applications [1,5,6].

One of the main differences between these algorithms is the calculation complexity of differential operators between neighbor pixels: from $2 \times 2$ to more than $9 \times 9$ per kernel. The choice of an edge detection algorithm depends mainly on the signal to noise ratio (robustness), the localization, and the quality of detection and the implementation efficiency. One problem is the necessary CPU time required to perform the edge extraction.

We present here a very high speed edge detector chip using the optimized Canny-Deriche IIR filter in a single chip.

This paper is organized as follows. The following section is devoted to the edge model and the optimized Canny-Deriche filter. Then different digital filter integration examples are shown and different techniques are defined to accelerate calculations in filtering. The calculation is...
detailed by using a look-ahead with decomposition technique well adapted to the acceleration of recursive filters, and this technique is applied to the optimized Canny-Deriche filter [7].

In the penultimate section the integration part of the filter obtained by look-ahead calculation in an ASIC is shown, and in the last section the direct implementation of the filter without look-ahead technique is shown, but with a local retiming of internal registers contained in the recursive part of the filter.

The Filter

The edge model presented here is the best approximation for a wide variety of edges seen in real-time image processing [7]. Even if the edge at the input of a camera is a step, it is transformed at the output in an edge which we assume to follow this model (exponential edge model):

\[
c(x) = \begin{cases} 
\frac{1 - e^{-sx}}{2} & \text{for } x \geq 0 \\
\frac{e^{sx}}{2} & \text{for } x < 0
\end{cases}
\]

with \( s > 0 \)

\[\text{Figure 1. Exponential edge model with } s = 0.5.\]

Chosen criteria for this algorithm are the following:

(i) signal/noise ratio: where the noise is considered white, additional, gaussian and centered in zero.

(ii) localization: the average gap between edge detected with noise position and its real position.

(iii) quality of the detection (spurious response): with noise, the signal detected can present several maxima, and thus parasitic responses must be as far as possible from the real response.

These three criteria are maximized using a mathematical approach.

The optimal blurred edge detector impulse response is thus given by (optimal edge detector impulse response) [7]:

\[
f^-(x) = A\left( k e^{\alpha x} \sin(wx) + e^{\alpha x} \cos(wx) - e^{\alpha x} \right) \text{ with } x \leq 0
\]

\[
f^+(x) = A\left( k e^{-\alpha x} \sin(wx) - e^{-\alpha x} \cos(wx) + e^{-\alpha x} \right) \text{ with } x > 0
\]

This leads to a recursive realization with two stable third recursive filters moving in opposite directions. It can be extended to the 2D case by knowing that the slope of a surface in any direction can be determined exactly from its slope in two directions:

\[
y^+(i) = a_1 x(i-1) + a_2 x(i-2) - a_3 y^-(i-1) + a_4 y^+(i-2)
\]

\[
y^-(i) = a_1 x(i-1) + a_2 x(i+2) + a_3 y^-(i-1) + a_4 y^+(i-2)
\]

with:

\[
a_1 = A\left( k e^{-\alpha x} \sin(\omega x) + e^{\alpha x} \cos(\omega x) - e^{-\alpha x} \cos(\omega x) - e^{\alpha x} \sin(\omega x) \right)
\]

\[
a_2 = A\left( k e^{-(\alpha + s)x} \sin(\omega x) + e^{-(\alpha + s)x} \cos(\omega x) - e^{\alpha x} \sin(\omega x) - e^{\alpha x} \cos(\omega x) \right)
\]

\[
a_3 = 2 e^{-\alpha x} \cos(\omega x) + e^{-s x}
\]

\[
a_4 = e^{-2\alpha x} + 2 e^{-(\alpha + s)x} \cos(\omega x)
\]

\[
a_5 = e^{-(2\alpha + s)x}
\]

We have shown [7] that for a good choice of the parameters \( m \) and \( w \), and in the case of blurred and noisy images, our operator allows a notable increase of the signal to noise ratio in comparison with the Deriche filter (for example with a signal/noise ratio equal to 2, we increase the performance by 20%).

The recursive filter implementation allows us to avoid the truncation of the filter impulse response, and the use of this filter in the case of multiscale application is easier because the number of operations per pixel is independent of the scale parameters.

Filter’s Implementations

We describe, in the following sections, the filter’s implementations in an ASIC.
Direct implementation of the optimized Canny–Deriche filter

A solution to achieve real-time image processing consists of integrating the filter in a specific dedicated processor (ASIC).

The Z transform of the recursive filter given by equations (2) are the following:

\[
TZ^+ = \frac{Y^+(z)}{X(z)} = \frac{a_1 z^{-1} + a_2 z^{-2}}{1 - a_3 z^{-1} + a_4 z^{-2} - a_5 z^{-3}}
\]

\[
TZ^- = \frac{Y^-(z)}{X(z)} = -\frac{a_1 z + a_2 z^2}{1 - a_3 z + a_4 z^2 - a_5 z^3}
\]

The corresponding architecture is given in Figure 2.

The integration of such an architecture creates some problems. Observe that the critical path is composed by one multiplier and four adders and constitutes a complex combinational chain. Moreover, the number of glitches increases when signals through each adder.

The integration of this filter with the help of the CAD tool OPUS (Cadence Design Framework II) in a CMOS 1 µm technology has shown its limitations. The frequency of processing is in the order of 25 MHz (for a silicon area 5 mm²). If our main goal is the integration of an edge detector operator in real time for images larger than 512 × 512 pixels, this architecture will not work correctly.

For fast real-time throughput applications, the various methods that allow accelerated calculations become more important.

Filter implementation with calculus acceleration

Digital filtering occupies an important place in the field of the digital signal and image processing. To improve the performances of these filters for real-time applications, the traditional approach consists of increasing the hardware component speed or to program a dedicated processor such as DSP (Digital Signal Processor). The parallel system implementation in dedicated circuits (ASIC), allows higher frequencies to be reached. However, the class of applications of such circuits remains limited.

In the following subsection a solution is given that accelerates the calculations of the filter \( f(x) \).

Sampling period definition

A digital filter is characterized by its minimal sampling period imposed by its implementation (Figure 3):

\[
T_s = \frac{1}{L \ \text{MAX} \left[ \frac{D_l}{M_l} \right]} \quad 1 \in S_i
\]

The sampling period of an IIR filter is limited by its recursive part. It is given by:

\[
T_m = \frac{1}{L} \ \text{MAX} \left[ \frac{D_l}{M_l} \right] \quad 1 \in S_i
\]

The iteration period of the graph above-mentioned is:

\[
T_m = \left( T_o + T_m \right) / 8
\]

Scattered look-ahead with power-of-two-decomposition technique

Given the recursive part of an \( N \)th order filter with \( k \) pipeline stages in its feedback loop,
\[ H(z) = \frac{1}{1 - \sum_{i=1}^{N} q_i(k)z^{-2k}} \]  

(6)

The original transfer function corresponds to \( k = 1 \), where \( q(1) = a \). The equivalent filter with 2k pipeline stages can be obtained by multiplying the numerator and the denominator by:

\[ \left( 1 - \sum_{i=1}^{N} (-1)^i q_i(k)z^{-ik} \right) \]

(7)

The pipelined filter is described by:

\[ H(z) = \frac{1 - \sum_{i=0}^{N} (-1)^i q_i(k)z^{-2ik}}{1 - \sum_{i=1}^{N} q_i(2k)z^{-2ik}} \]

(8)

where the sequence \( q_i(2k) \) is derived in terms of the sequences \( q_i(k) \) (depending on the \( N \)th order filter being even or odd) by relationships given in annex.

The application of this transformation a second time gives a pipelined filter four times, (then eight times, and so on). From the original function, it is necessary to apply \( \log_2(M) \) transformations to have \( M \) pipeline levels. Each transformation increases the speed by a factor of 2 and brings \( N \) supplementary multipliers to the filter structure.

In general, the transfer function of an \( M \) level pipeline is given by:

\[ H(z) = \left( \sum_{i=0}^{N} b_{z^{-i}} \right)^{\log_2(M)-1} \prod_{k=0}^{M-1} \left[ 1 - \sum_{i=1}^{N} (-1)^i q_i(2^k)z^{-2^ik} \right] \]

(9)

This transfer function can be implemented with \( (2N + N\log_2(M) + 1) \) multiplications.

Application to the \( f(x) \) filter

The described acceleration method mentioned above is valid for any order of the filter used whose Z-transform is:

\[ TZ^+ = \frac{Y^+(z)}{X(z)} = \frac{a_1z^{-1} + a_2z^{-2}}{1 - a_3z^{-1} + a_4z^{-2} - a_5z^{-3}} \]

\[ TZ^- = \frac{Y^-(z)}{X(z)} = -\frac{a_1z + a_2z^2}{1 - a_3z + a_4z^2 - a_5z^3} \]

(10)

with \( X(z) = TZ(x) \).

The transfer function of this filter \( TZ^+ \) \((TZ^-)\) is transformed by four pipeline levels (limited by the capacity of integration in an ASIC design). The filter resulting from the transformation is a 12th order filter whose transfer function \( H(z) \) is given by Eqn 11.

This transfer function can be seen as a product of a four transfer functions. These transfer functions are implemented in a cascade form, as described in Figure 4.

**Figure 4.** \( H(z) \) cascade implementation.

\[ H(z) = \frac{1}{1 - \left( a_1z^{-1} + a_2z^{-2} \right) + 2(-a_4 + 2a_3a_5)z^{-4} + a_5^2z^{-6}} \]

(11)

with:

\[ H_1(z) = a_1z^{-1} + a_2z^{-2} \]

\[ H_2(z) = 1 + a_3z^{-1} + a_4z^{-2} + a_5z^{-3} \]

\[ H_3(z) = 1 + \left( a_3^2 - 2a_4 \right)z^{-2} - \left( a_4^2 + 2a_3a_5 \right)z^{-4} + a_5^2z^{-6} \]

\[ H_4(z) = \frac{1}{1 - \left( a_3^2 - 2a_4 \right)^2 + 2(-a_4^2 + 2a_3a_5)z^{-4} + a_5^2z^{-6}} \]

(12)
The corresponding graph filter is the following:

![Graph Filter](image)

**Figure 5.** $H_1(z)$ and $H_2(z)$ cascade implementation.

Global register retiming

Supplementary registers obtained from the look-ahead calculation have an interest only if they are suitably exploited. Retiming [8,9], is a technique which allows delays to be moved in a data flow graph and exploited better. By using this principle, registers of the $H(z)$ filter feedback-loop are retimed as shown in Figure 7(a). In Figure 7(b), $e(n)$ is the output of the non-recursive part of the look ahead filter.

The registers are moved inside each multiplier to obtain a pipeline level. This operation also allows a pipeline structure for adders between them. The non-recursive part can use these multipliers without introducing modification to the transfer function, but will introduce a timing latency of the output $y(n)$.

![Register Retiming](image)

**Figure 7(a).** $H(z)$ feedback loop.

After showing the different techniques to accelerate recursive filters, the look-ahead acceleration is a method well adapted in view of filter integration in an ASIC implementation.

Data coding

The use of fixed arithmetic takes into account the coefficient and internal data coding. To limit the bit coding an empirical approach is chosen. In [10], we show that the bit coding is highly dependent on the ‘s’ parameter. In this way, for $s > 1$, a 12 bit coding for coefficients and internal data is a good tradeoff between filter performances (signal to noise ratio and localization) and silicon area. For $s < 1$, 16 bit coding is necessary.

In Figures 10, 11 and 12 we show the results obtained for this image (it is a circle drowned in a Gaussian noise with a signal to noise ratio of 17 dB), for $s = 2$ and with a 12 bit data coding and with real calculus (on 64 bits).
ASIC Implementation of the Look-ahead Filter

In this section the architecture and the realization of dedicated circuit (ASIC) for a ramp edge detection is presented. The look-ahead calculations are obtained with the method developed in the previous section. The design is made such that four identical circuits are used to obtain the horizontal and the vertical gradient. We describe from an initial bloc diagram how we have been able to reduce the internal memory and to synchronize processings of left to right and right to left for lines, top to bottom and bottom to top for columns.

X+ are the results obtained by the filtering in sweeping lines from left to right, X− in sweeping them right to left.

Y+ are the results obtained from the filtering in sweeping columns top to bottom, Y− in sweeping columns bottom to top. These results are calculated in parallel with the help of four identical circuits. They process the same image in parallel and synchronous manner. The edge extraction operator is given in Figure 11.

The general idea (simplified) of the working of such a circuit is:

(i) loading coefficients.
(ii) loading an image line (column) into a $512 \times 8$ bits of RAM.
(iii) processing the line (column) following $X^+$ and $X^-$ (there $Y^+$ and $Y^-$). The filter is managed by a special control unit.
(iv) results of the processing of each filter are loaded in an output RAM ($512 \times 12$ bits).
(v) $X^+[i]$ and $X^-[i]$ addition (there $Y^+[i]$ and $Y^-[i]$) is done in a very rapid manner compared to the iteration frequency of the filter. This process is started as soon as the two necessary terms for the addition are available.

One RAM architecture

The objective is realized as a single circuit, with the two choice modes of running as $X^+$ or $X^-$. In order to develop an architecture based on muxes (Figure 11) four identical circuits are necessary to obtain the vertical and horizontal gradient.
If “c” is equal to zero, the filter realizes the X+ mode the
corresponding video (8 bits). Data is filtered, then loaded by the
LIFO.

If “c” is equal to one the input video is then directed to
the LIFO, then filtered so as to obtain the processing fol-
lowing X^2.

ASIC blocks

This subsection is dedicated to the functions of each of the
ASIC blocks.

Figure 12 shows the main functional blocks that form the
heart of the circuit as well as the different signals of
input/output and command signals.

The different blocks are: the filter, the control unit, coeffi-
cients registers, the input muxes (MUX1 and MUX2) and
output (MUX3), the LIFO memory, and the address
counter.

All the filter coefficients are on 12 bits and are repre-
sented in two’s complement notation. Coefficients are
loaded from the video data bus.

As the bus of data is on a byte, to load 12 bits two clock
cycles are necessary (loading the first 8 bits in parallel man-
ner, and on the clock edge following loading the last four
bits). The pipelined filter (Eqn 11) has 11 coefficients, and
thus programming requires 22 clock cycles. The control
unit manages the coefficients.

We have seen (Eqn 11) that the filter implementation is a
12th order recursive filter. Its equation contains 11 coeffi-
cients. Each coefficient ends at one of the two inputs of the
associate multiplier. The filter has 11 multipliers. Three of
them are in the recursive part and eight in the non-recursive
part. The structure of these multipliers is based on the
Baugh-Wooley algorithm.

This multiplier architecture was chosen because of its
ability to be pipelined [11,12]. For the purpose of reducing
times of partial products additions, Wallace [13] and Dadda
[14] have proposed techniques to manage the different
adders undertaking the partial product addition.

The Baugh-Wooley [12] multiplier allows the generation
of partial products for mixed products (two’s complement
(C2), no signed, no signed X C2) in a very regular structure.

The main blocks of the filter are: memories element;
multipliers; control blocks for the initialization; and adders.

ASIC features

The circuit has been realized with the CAD tool Cadence,
using the ES2 standard cell library in a CMOS 1.2 μm
technology. The edge operator features are: frequency
(post-layout), 20 MHZ (the multipliers until 50 MHZ); it
processes 512 × 512 pixels images; area: 60 mm²; pixels
coding, 8 bits; all the internal arithmetic on 12 bits.

The results presented here confirm the complexity of realiz-
ing a recursive filter (processing a pixel to a frequency greater
than 10 MHz). The gradient \((G_x = X^+ + X^-)\) can, in parallel, only be obtained by the use of two circuits of this type.

Thus we propose another alternative to improve the area/speed trade-off. This method consists of implementing the filter directly without look-ahead calculation, but moving the registers in the recursive part of the filter [5].

**Improvement of the Direct Filter Implementation**

This section proposes a new approach based on an optimized clocked circuit by relocating registers in order to reduce combinational rippling. Unlike pipelining, direct retiming does not increase circuit latency. As shown in Figure 13, only the recursive part remains. Note that the two architectures use the same functional elements connected in the same manner, except for the locations of registers.

The frequency of this architecture is given by the time through one multiplier and one adder. With this method three adders are eliminated in the critical path, allowing a speed increase of about 20% for the same area.

The choice for the final idea of the dedicated processor has focused on this architecture.

**Architecture**

Due to the necessary memory space for the calculation of the edge operator, an implementation of the architecture, described in Figure 13, in a single programmable component (FPGA) is not suitable. The structural implementation of the ASIC has been done using a cell-based approach in a CMOS 1 µm technology, with the CAD tool OPUS (Cadence Design Framework II). The proposed architecture is presented in Figure 14.

The different blocks are: the causal filter, the anti-causal filter, the latches for loading coefficients, and one block to change the sign of coefficients \(a_1\) and \(a_2\) (anti-causal filter). The circuit is controlled by the following signals: charge_coef, reset_coef, reset_filter, line_synchro, scan1 and scan2 (test of filters), clock. The output of filters are given by \(Y^+\) and \(Y^-\). The gradient operation is \((G_x)\), calculated on the exterior of the processor.
Filters

This circuit integrates a causal and an anti-causal filters. Each of these filters is composed of five $12 \times 12$ bit multipliers, 12-bit four adders and six 12-bit registers (Figure 4). Only the signs of the coefficients $a_1$ and $a_2$ are opposite between the causal filter and anti-causal, which justifies the necessity of inserting a supplementary logic to change the sign of these coefficients (bloc «coeff-sign» on Figure 14.

The cell-based approach seems sufficient for the realization in ASIC. However, it is necessary to determine the multiplier/adder which allows the best speed/area trade-off. The multiplier thus generated has suitable performances (less than 20 ns for multiplication $12 \times 12$ bits, for a silicon area lower than 1 mm$^2$). The choice of the adder is focused on an architecture of the type “carry-select”, offering the best trade-off between speed and area (two addition words of 12 bits in 5 ns and a silicon area lower than 0.1 mm$^2$). In a cell-based approach the multiplication and addition operation is achievable in less than 25 ns.

Coefficients

All five coefficients are in a two’s complement notation, and are serially loaded in 10 clock cycles into the latch by the video bus (8 bits). Once the coefficients are loaded, they are available at the input of the corresponding multiplier. The coefficients can be initialized by setting the reset signal to zero.

Results

Prototypes realized with this approach, in a CMOS 1 $\mu$m technology, have been tested successfully. Indeed, the obtained dedicated processor (Figure 15) is able to process a pixel in 30 ns, with variable size images ($64 \times 64 - 1024 \times 1024$ pixels). The complexity of the circuit is about 72 000 transistors for a silicon area of 29 mm$^2$ ($5.6 \times 5.3$ mm$^2$).

Note that we have not integrated the LIFOS in order to economize the silicon area.

Note also that the sensitive improvement of the speed of functioning of the circuit, and the idea of using two identical circuits, the vertical and horizontal gradient, are calculated in parallel.

Comparison of the different methods

We have proposed different solutions for the integration of the third order recursive Canny-Deriche filter. In previous sections we have described the direct implementation of this filter, developed an adequate method to the acceleration of this type of filter, and in the previous section we have seen how a simple modification of the filter architecture leads to a sensitive increase of performances. Table 1 compares performances of these different implementations. To realize an objective comparison we have integrated a CMOS 1 $\mu$m technology for all of these solutions.

According to the aimed application, this study brings different integration solutions. In all cases, it is conceivable to process images of size larger than $512 \times 512$ pixel images.

Table 1. Comparison between the different methods of the optimized Canny-Deriche filter implementations (Technology CMOS 1 $\mu$m ES2)

<table>
<thead>
<tr>
<th>Implementation</th>
<th>Estimated performances</th>
<th>Real performances</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>Area (mm$^2$)</td>
<td>F (MHz)</td>
</tr>
<tr>
<td>Direct</td>
<td>5.2</td>
<td>25</td>
</tr>
<tr>
<td>Global retiming</td>
<td>15.3</td>
<td>71</td>
</tr>
<tr>
<td>Local retiming</td>
<td>5.3</td>
<td>40</td>
</tr>
</tbody>
</table>

Estimated: Pre-layout results take into account an estimation of interconnect capacitances.

Real: Post-layout results are obtained after the place and route phase and the extraction of capacitances.

Figure 15. Chip picture. Real time edge detection operator (optimized Canny–Deriche algorithm) with a clock rate of 33 MHz for a silicon area of 29 mm$^2$ (72 000 transistors), internal precision 12 bits.
The solution of the pipelined filter with look-ahead technique (global retiming) allows data flow in the order of 800 Megabits/s (66.5 MHz by pixel), three times more than a direct filter implementation, but with a silicon area cost increase of three times that of the original.

The local retiming method proposed represents a good area/speed trade-off. Indeed, the cost in area is minimal (area identical with the direct implementation), with a data flow in the order of 400 Megabits/s (37.5 MHz by pixel) that allows us to process images of size $1024 \times 1024$ pixels in real time.

Conclusion

The digital recursive filter acceleration is a necessary step for the implementation of algorithms in real time.

This algorithm-architecture-silicon adequation work for a third order recursive filter has allowed us to review the different recursive filter acceleration techniques.

We have thus demonstrated two techniques of filter integration. Firstly, the scattered look-ahead technique, with power-of-two decomposition technique calculation, was demonstrated on the first dedicated processor. Secondly, the more direct method allowed us to improve appreciably the area/speed compromise, which is an important factor during the design of the circuit.

This study has been based on a high data flow dedicated processor. The satisfactory results obtained have allowed us to develop an image processing board around this processor.

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References


Appendix

Calculation of $q_i(k)$

The recursive part of an $N$th order filter with $k$ pipeline latches in its feedback loop is described by:

$$H(Z) = \frac{1}{1 - \sum_{i=1}^{N} q_i(k)Z^{-ik}}$$

The original transfer function corresponds to $k = 1$ and $q_i(1) = a_i$. We obtain an equivalent 2$^k$ pipeline level by multiplying the numerator and denominator by:

$$\left(1 - \sum_{i=1}^{N} (-1)^i q_i(k)Z^{-ik}\right)$$

where

$$H(Z) = \frac{1 - \sum_{i=0}^{N} (-1)^i q_i(k)Z^{-ik}}{1 - \sum_{i=1}^{N} q_i(2k)Z^{-2ik}}$$
With the relationship between \( q_i(2k) \) and
\[
q_i(k) : \quad q_i(2k) = q_i^2(k) + 2q_2(k) \\
q_N(2k) = (-1)^{N+1}q_N^2(k)
\]

For an \( N \)th-order odd filter:
\[
q_i(2k) = \begin{cases} 
2q_{2i}(k) + (-1)^{i+1}q_i^2(k) + 2 \sum_{j=1}^{i-1} (-1)^{j+1}q_j(k)q_{2i-j}(k), & i = 2, \ldots, \frac{N}{2} \\
(-1)^{i+1}q_i^2(k) + 2 \sum_{j=i+1}^{N} (-1)^{j+1}q_j(k)q_{2i-j}(k), & i = \frac{N}{2} + 1, \ldots, N-1.
\end{cases}
\]

For an \( N \)th-order even filter:
\[
q_i(2k) = \begin{cases} 
2q_{2i}(k) + (-1)^{i+1}q_i^2(k) + 2 \sum_{j=1}^{i-1} (-1)^{j+1}q_j(k)q_{2i-j}(k), & i = 2, \ldots, \frac{N-1}{2} \\
(-1)^{i+1}q_i^2(k) + 2 \sum_{j=i+1}^{N} (-1)^{j+1}q_j(k)q_{2i-j}(k), & i = \frac{N+1}{2}, \ldots, N-1.
\end{cases}
\]