# Computational 3D Microscope

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**Computational 3D Microscope**

**YING OU**

This **Masters Project Paper** fulfills the Master of Engineering degree requirement.

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# ABSTRACT

This project report covers the development of a computational 3D microscope, NoScope. Using tomographic and light field algorithms, we present a method to reconstruct 3D volumes of microscopic samples taken with a lensless sensor. Business and intellectual property strategies for commercializing NoScope are detailed in the first three sections. The remaining sections highlight the project's technical accomplishments and methods.

# Capstone Report
# Project NoScope


Ying Ou

A paper submitted in partial fulfillment of the
University of California, Berkeley
requirements of the degree of
*Master of Engineering*
in
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# Part I

# Problem Statement

# 1 Project Introduction

As technology has advanced with the emergence of digital computing and signal processing, computers that used to take up entire rooms now fit in a backpack, and doctors and nurses have diagnosis equipment built into their cellphones. However, the optical microscope, a piece of equipment crucial for any medical or experimental lab, has remained unchanged for nearly three hundred years. Modern commercial microscopes rely on fragile lenses and precise alignments, and without additional equipment have no means of sharing the acquired images. Heavy and bulky, they are living fossils in a portable world and would benefit greatly from a technological overhaul.

Many fatal diseases, such as malaria, are endemic in tropical areas around the world. In order to better cure people with such diseases, a faster and more affordable detection and diagnosis method is greatly needed in those region. Traditional microscopes had reached their ceiling of being portable due to its fragile nature, and thus cannot be used as a means to diagnose diseases in the field. A more portable device is needed for doctors and nurses working in those area. With a faster diagnose method, millions of lives will be saved every year.

Imagine a world in which the advantages of microscopy are readily available to every individual with a need due to a low price and viability in a wide range of environments. Furthermore, the microscopic images may easily be made digital. Has a boy in a small African village contracted malaria? How can a doctor in a distant area assess over the Internet a patient's health whose disease requires microscopy? These questions find an answer in a robust, inexpensive, and yet powerful digital microscope. Additionally, people everywhere would be free to explore an exciting and useful unseen world.

How can we achieve our vision then? The clue lies in the advent of digitization and higher computational power; we believe these two factors should be the driving force in future of microscopy. Unlike traditional optics, constrained by the limits of the physical world, computational microscopy can ride the tide of improving electronics, compensating for lack of expensive optics with more complex, but more cheaply achievable computations. In particular, the availability of memory and modern processing speed on common consumer devices opens up access to image-processing algorithms that were previously privy to only the world of laboratory work.

As such, our team wishes to leverage the broader trend of digitization to develop a robust, cheap, portable diagnostic tool that can produce digital images of traditional medical samples. With its advanced computational imaging processing technologies, the NoScope manages to create high-resolution digital images without optical lenses. Abandoning the expensive and fragile lenses, NoScope successfully eliminates the high cost and special handle requirement associated with lenses. In addition, since samples are imaged by USB cameras, the digital files can be shared among individuals easily.

# Part II

# Capstone Strategy

# Contents

# 1 Introduction

By the end of April 2015, the goal of Team NoScope is to produce a minimum viable product of a prototype microscope that creates three-dimensional images of microscopic samples. We plan on accomplishing this through a series of computational algorithms combining principles of limited angle tomography (Kak et al., 1988) and light field imaging (Levoy et al., 1996). Using these imaging techniques, our hardware will create a three-dimensional image from a series of two-dimensional ones. The goal of this paper is to give the reader a brief introduction to our product, then explain its necessity in the market through its key value propositions, and finally elucidate our strategy for entering the congested microscopy market.

## 1.1 Our Product

The end goal of project NoScope is a fully functioning, robust microscope prototype that can be taken to market as a minimum viable product. The main factors driving our hardware development are portability, durability, and low cost. In order to limit cost, our team has developed a lensless system that bypasses the need for expensive and fragile lenses, which builds upon the LED array illumination technique in Waller Lab (Tian et al., 2014). We have also incorporated a simple microcontroller on the device, allowing the intensive computations to easily be performed by an attached computer. This significantly reduces the number and complexity of parts, when compared to a traditional microscope.

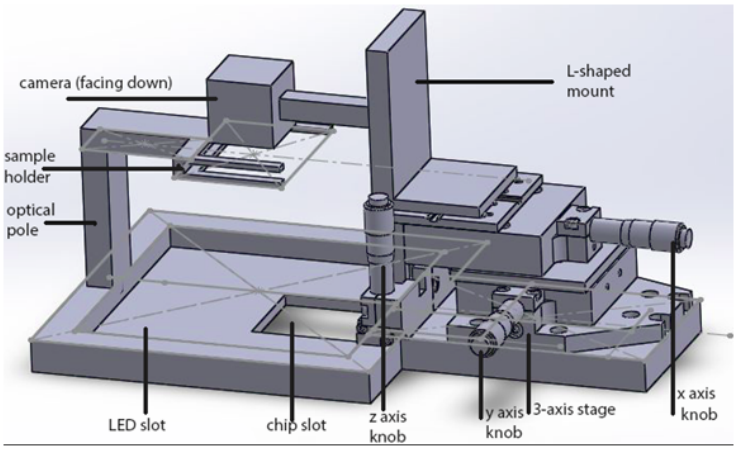


Figure 2.1: Isometric view (CAD) of NoScope.

The current iteration of NoScope consists of a 32x32 matrix of LED's, a camera sensor, and a microcontroller that synchronously triggers specific LED's with camera exposures. During prototyping a custom designed, 3D printed case will house the components. By connecting to a laptop and running software we are developing in parallel with the hardware, the end user will be able place samples on a standard microscope slide and acquire high-resolution 3D images. The inclusion of light field algorithms allows the image to be refocused in post-processing so that various depths of the image can be analyzed by the end user.

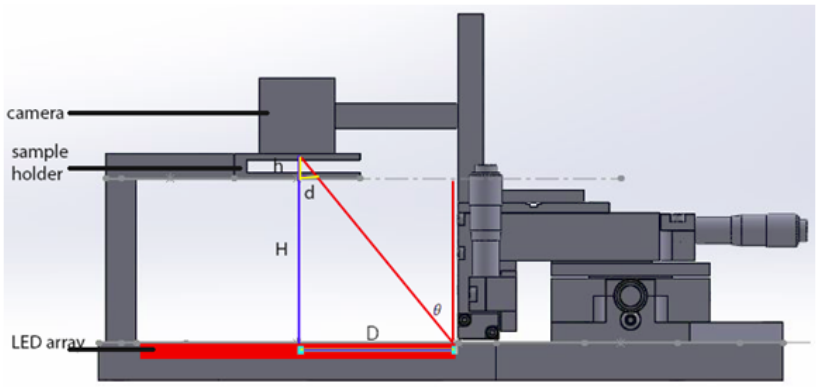


Figure 2.2: Side view hardware schematics of NoScope. Notice the distance of the sample holder to the camera.

Note that figure 2.2 shows the sample placed extremely close (approximately 2mm) away from the camera sensor. This configuration hints at the fundamental working principle of NoScope: casting a shadow of the sample on the sensor. By illuminating a translucent sample, we project an image of the sample on the sensor. Since modern sensors have extremely small pixel pitches (distance between pixel), we are effectively able to view images of its shadow at microscopic scale, thus acting as a microscope. For example, our sensor has a pitch of 5.3$\mu$m.

In addition, we are able to generate different 'views' of the sample by illuminating different LEDs. Since each of the LEDs are placed at a different angle incident to the sample, lighting different LED, and taking separate exposures is analogous to viewing an object at different angles. This also forms the basis for digital refocusing.

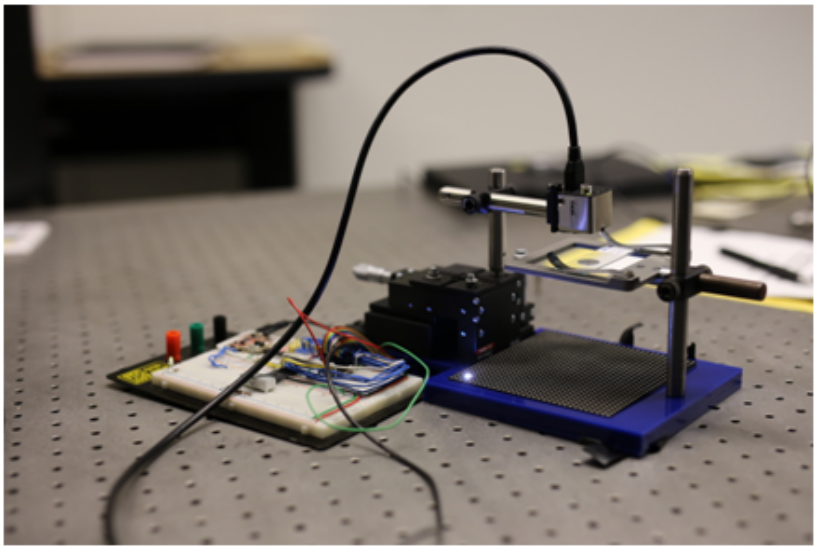

Figure 2.3: First iteration of NoScope. The breadboard is a temporary module and not an actual part of the prototype.

For the current iteration of NoScope, we were able to achieve a resolution of about 32 lp/mm, as well as resolve 3D structures of various microscopic specimens using light field methods. More details can be found in the technical contribution section.

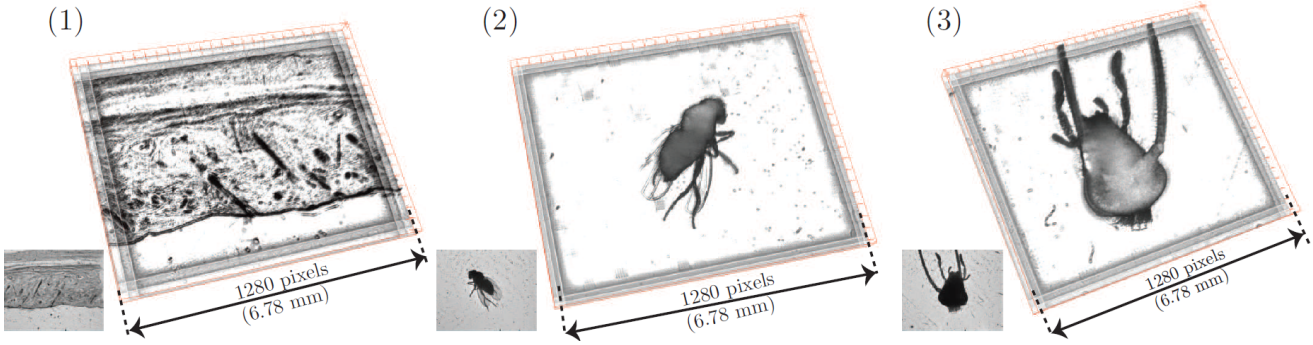


Figure 2.4: Examples of 3D samples from Light field algorithm. No thresholding/post-processing applied. Taken from light field technical contribution report (Lee, 2015).

While the current resolution we can achieve with NoScope is still slightly low, the resolving power of a lensless microscope can be improved by using a sensor with smaller pixel pitch, and better algorithms to account for wave effects. We envision future iterations of NoScope to be used for diagnosing diseases as well as for academic use in teaching environments. In addition, our product can also potentially replace pricey optical microscopes as an inexpensive alternative.

# 2 Need for Product

Commercialization of NoScope requires the identification of the customers and a full understanding of their needs. In order to find our potential customers, this section will first examine the broader trends in the microscopy industry, and identify a niche for NoScope. Then it narrows down to a specific primary stakeholder and discusses their potential needs, and how these can be fulfilled by NoScope. It further shows that this potential need has not been fulfilled by other products, by analysing the difference between NoScope and our close competitors. Accurate identification of the customer's needs helps companies to shape strategies and have a better positioning. Therefore, this section lays a concrete foundation for our marketing strategy to be discussed in the subsequent section.

## 2.1 Motivating Trends

As an intrusive new entry, NoScope expects to assist the technology revolution in microscopy and to fulfill needs for underrepresented customers. This section identifies the motivating trends for our microscope in the general industry and our primary market.

Microscopy is a fast growing industry. The market revenue is expected to double in five years from 3.84 billion in 2014 (IndustryARC 2013, p.11). The growing market along with the unique features of NoScope could lead to future investment in NoScope. In addition, this industry is also experiencing a technological shift. The traditional optical microscopes are gradually losing favors due to the limited resolution (IndustryARC 2013, p.13). NoScope might be able to help optical microscopes to regain popularity. The core technology of NoScope is the 4D light field imaging, which is designed to increase the resolution of the sample images without optical lenses. Once this technology has proven to be applicable, it will be possible for NoScope to lead other optical microscope companies to further increase the resolution of optical microscopes.

Despite the industry's maturity, current microscopy still cannot fulfill all its customers' needs. Aside from the expensive cutting-edge equipment being produced by leading companies in this field, there is a significant need for a low-cost product. One particular example is the use of microscopy in malaria diagnosis. According to World Health Organization (WHO), the funding for malaria control and elimination has reached US 2.7 billion by the end of 2013, a threefold increase since 2005, and this

growth of funding has been greatest in Africa Region (WHO 2014, p.12). However, this funding falls far below the 5.1 billion that is required to achieve global targets for malaria control and elimination (WHO 2014, p.12). Replacing expensive microscopes with NoScope can potentially save thousands of dollars for medical facilities, which allows more funding to be channeled into prevention and treatment of malaria.

## 2.2 Satisfying Stakeholders in Medical Diagnosis

Moving further along the argument of a potential niche in malaria diagnosis, we have thus identified our primary stakeholders as doctors, or medical technicians in malaria-endemic areas. By the end of 2015, there will be about 1 million community health workers in sub-Saharan Africa, estimated by researchers in Columbia University (Singh et al., 2013). However, doctors and nurses alone are not enough to solve the problem. According to WHO, there were about 207 million cases of malaria in 2012 and an estimated 627,000 deaths (WHO 2014b). In order to contribute to the fight against tropical diseases in under-developed regions, we plan to provide these health workers inexpensive and portable microscopes with strong disease diagnosis ability.

The biggest challenge for us is maintaining a low price point. Governments of developing countries cannot afford sufficient expensive medical equipment to satisfy diagnostic needs. On the other hand, doctors from nonprofit organizations mainly rely on donations from external parties, and also have limited budgets. Therefore, expensive microscopes–which are in the range of thousand dollars–are not suitable for our primary customers.

Our key value proposition is thus to make our hardware highly affordable by using a lensless design. Microscopy lenses are particularly expensive, comprising the majority of a typical microscope's price. Naturally, by avoiding lenses altogether, we can significantly reduce our selling price. This allows our customers to have more money to invest in disease treatment rather than diagnosis.

Our second value proposition is portability and robustness. It is no coincidence that many of the malaria-endemic areas, such as North India, and Africa, are also less economically developed. Consequently, these regions may lack proper transport infrastructures. The conventional microscope lens is a piece of equipment that not only is heavy, but also fragile. As such, these lenses often come with their own protective suitcases. These logistical factors further compound the difficulty of getting

the microscope to the field. By removing the lens entirely, we address the issue of accessibility of microscopic diagnostic services by transforming the microscope into a light, electronic device.

In addition to being lensless, NoScope boasts a unique feature of 3D imaging. The ability to view samples in 3 dimensions can help increase the accuracy of disease diagnosis. Most disease diagnosis relies on morphological discrimination of unhealthy cells based on pathological features (Tadrous, 2011). A 3D image allows doctors to view the sample from different angles, and observe features that might otherwise be hidden in 2D projections or slices. This leads to higher accuracy identification of cell types or parasites. Incidentally, as the following section will show, the 3D imaging feature also distinguishes us from the rest of our competition, making NoScope the most suitable product for disease diagnosis.

## 2.3 Differentiation: NoScope vs Competitors

In the process of selecting our closest competitors, we have considered the similarity of their technology to ours, as this is a good indication of how directly they compete against NoScope. Building on this, we have further subdivided our competitors coming from the industry and academia. On the commercial side, this section will cover our potential rivals from Lytro, Cellscope, and Pelican. In academia, we will examine the field-portable tomographic microscope by Ozcan Research Group in UCLA.

In comparing our product with those of the competition, we keep in mind the key criteria of cost, portability, and computational imaging capabilities–particularly any 3D capabilities. Although the products of these competitors may hold some advantages over our product in certain areas, NoScope still holds its weight in the market of lightweight, inexpensive imaging systems for disease diagnosis.

### Competition in the Industry

In this subsection, we evaluate three industry competitors: Lytro, Cellscope, and Pelican Imaging.

#### Lytro

We start our industrial competitor analysis from the computational imaging system developed by Lytro. This system is marketed toward everyday users who want to capture depth-related details in their life photos and have more post-processing options available to them to modify these photos. The system boasts a small form factor that makes it convenient to be carried around without hassle. The

light sensor array requires lenses to properly focus the light for capturing light-field information. This light-field technology enables Lytro to vary parameters such as depth-of-field as well as numerical aperture in post-processing (Lytro, 2015), which is a large factor in the appeal of computational imaging systems. However, the method of computational imaging at work in their product does not allow for high-resolution 3D images due to the poor range of angles available to a camera in a macroscopic scene. Most importantly, Lytro does not focus on disease diagnosis and is incapable of microscopy, and thus fills a different need in the imaging market compared with our target customers.

**Cellscope**

Cellscope offers strictly an optical assembly to accompany a user's smartphone to allow for convenient microscopy while taking advantage of computing power and hardware already in the user's possession. Their product consists of a mount for a smart phone, mirrors and lenses, and a mount for the specimen to be viewed. In concert with a smart phone, this assembly accomplishes the key points of being lightweight and affordable while allowing for taking microscopic images. (Cellscope, 2015) Despite these advantages, Cellscope does not offer computational imaging, and thus has no capability of creating 3D images, which renders it less useful in garnering detailed information about samples, such as malaria parasites.

**Pelican Imaging**

Pelican Imaging has developed–but has yet to sell or contract out use of–a computational imaging sensor capable of replacing the camera in future smart phone models. The capabilities of a smartphone with this type of integration exhibit much similarity with those of Lytro cameras, particularly post-processing to alter many key characteristics of photos. Hence, we find that Pelican's sensor module matches up against our product in much the same way as Lytro does. However, there is potential for a future product combining Pelican's sensor module as Cellscope to fill the same market need as our product. Such a combination would combine the advantage of 3D imaging with portability and microscopy (Anderson, 2015). However, the optical components present in Cellscope's product may put the price point higher than our product. This combination would also rely on the user to already have a smartphone with Pelican's sensor.

Although this competition in still theoretical at this point, it indicates that there is movement toward filling this niche in the market that we are targeting, and thus informs us to move quickly in developing

our product to gain hold of the market.

### Competition in Academia

#### Field-portable Tomographic Microscope - UCLA

Looking at our academic competitor, Ozcan Research Group in UCLA has a design that bears many similarities to our proposed design. Namely, their microscope employs an LED array, as well as a lensless design, both of which are also key features in our device.

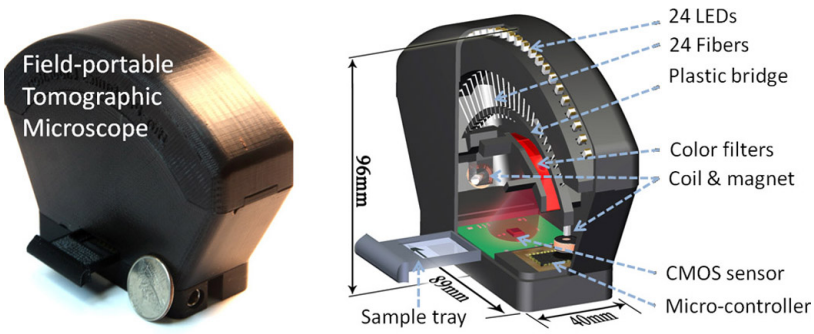


Figure 2.5: The schematics of Ozcan Research Group's tomographic microscope.
[Image Source: `http://www.spie.org/x84293.xml`]

Their image processing technique also resembles ours on the surface. Using multiple angles of illumination, their device takes images of the same specimen at different angles. In addition, in order to extend the angles of illumination beyond one axis, the coil and magnet in the device can electrically actuate the optic fibers to light the sample differently, giving the device an additional axis of data to work with. Following which, the on-board chip on the microscope processes these images into a 3D hologram using the technique of dual-axis tomography (Isikman et al., 2011).

A closer examination reveals several differences between the two devices. In terms of image processing, we are currently tackling the problem using two approaches: 4D light field, as well as 3D tomography. For the more comparable tomography technique, our device differs by virtue of the number of LED axis we have. By employing a full 2D matrix of LEDs, as opposed to just two axes in their device (additional axis by driving coils), our design endows us with multiple axes of data to work with. Consequently, we expect to be able to achieve a higher theoretical fidelity when it comes to reconstructing the 3D structure.

Aside from the algorithm used, we expect our device to be far lower cost than UCLA's microscope, owing to the simplicity of our design. The first reason is that the domed-shaped housing for the LED, which has to be custom made, is much more expensive than a flat piece of LED array we are planning to use, which can be bought off-the-shelf.

Additionally, UCLA's microscope achieves their second axis of illumination by actuating magnetic coils on the device (Isikman et al., 2011). This undeniably adds complexity, and hence cost, to the device. In contrast, as mentioned in the analysis of our tomography algorithm, the nature of our 2D LED array already allows us to have multiple axes of illumination. Taken together, we expect our device to be simpler in design, but still capable of achieving the same, if not better, resolving capability.

From our analysis of competitors above, we find our product provides a service not yet filled by others. Although Lytro, Pelican Imaging, Cellscope and Ozcan's Research group have somewhat similar products, our end goal will serve a need separate from all of them by providing a portable, low-cost microscope capable of 3D imaging focusing on disease diagnosis.

Since we accurately identified the specific need of our stakeholder, we are better able to differentiate ourselves from our competition. As such, we have laid the foundation of a specific need we hope our product will eventually be able to satisfy. The following section will thus use that niche as an anchor to expand on the broader strategy of entering the market.

# 3 Entering the Market

Successful entrance into our target microscopy market necessitates an overall understanding of the forces and trends permeating this market. In this analysis, we aim to garner insight regarding those technological and business aspects that impact our strategy to enter the market, which include profitability under competitive forces, and the pricing of our product.

## 3.1 Competitive Forces Analysis

We first seek to gain a thorough understanding of the factors affecting profitability in this market. In evaluating these factors, we apply Michael Porter's well-known framework of the "Five Forces" model to gauge competitive forces. We further consider positioning ourselves according to Clay Christensen's "disruptive innovation" model in order to help combat each of these forces.

As this technology has not yet been commercialized in the application of microscopy, considerable opportunity exists in the market for our product. However, we find the current industry environment hostile to new entrants such as ourselves, and we must overcome strong barriers to entry in order to gain a foothold in the market. Substitutes for our chosen application of malaria diagnosis–medical diagnosis and Rapid Diagnostic Test RDT–pose a threat of luring customers away from our product. Finally, we consider what power buyers and supplier might have over our profitability in this market.

#### Established Rivals

A small number of large companies command most of the power and profit in the microscopy industry; indeed, more than 90% of revenue in the $5,682 million industry of 2013 went to a limited number of key players (McWilliams, 2013, p. 135). Looking at industry reports, we find that these key players largely consist of glass manufacturers (Uba, 2015, p. 14). The clout of this cluster of glass manufacturers presents a considerable barrier to entry due to the limited number of suppliers. However, since a large advantage of the technology we employ is the lack of optical components such as lenses, we expect to be minimally affected by the clout of this cluster of glass manufacturers. This allows us to circumvent the strong barriers to entry set up by the larger players of the industry.

Established microscope companies have more resources and better reputation than we would upon

entering the market. How then can we penetrate the market to become profitable while minimizing retaliation from incumbents? The answer lies in Clayton Christensen's "disruptive innovation" model. By taking advantage of the un-catered needs of markets with lower gross margins, we can reach a customer base with a smaller budget and thus enter the market (Christensen, 2015, p. 1). The lensless nature of our system brings our costs low enough to be highly competitive, and undercut the cost of microscopes with similar specifications, as we discuss in the next section on pricing. Large microscope companies will run the risk of degrading their profits in order to compete on a similar price point.

Furthermore, our technology presents its own barrier to mimicry. After searching through commercially available options, we found that computational imaging has not yet been commercialized for any microscope, so companies would be forced to conduct R&D in the field of our technology in order to take advantage of the value that saves product cost. Lastly, even if competitors increase the R&D effort for a comparable product, they run the risk of self-competition. The customer bases between our initial customers and a typical microscope producer are not mutually exclusive; these competitors would compete with their own products for the same customers if they chose to mimic our technology.

**Buyers and Suppliers**

The buyers of microscopes come from various industries. The life science industry is the largest player on the buyer side with 26% of the market, followed by the semiconductor industry, education, and the nanotechnology industry, with market share as shown in Table 1 below (McWilliams, 2013, p. 7).

Table 2.1: Global microscopes market share by major application, 2012 (McWilliams, 2013, p.7).

| **Industry** | **Proportion of Market** |
|---|---|
| Life science | 26% |
| Semiconductors | 24% |
| Education | 12% |
| Nanotechnology | 7% |

From Table 1, we can clearly see that the life science industry is the biggest player in the buyer's side, but it does not dominate the market. The semiconductor industry and material science industry both have similar market shares as the life science industry on the buyer side. Furthermore, if we look into

the life science industry, microscopy has been the de facto tool of cell and tissue analysis from 1800 (Rosen, 2005), and it is extremely hard for the industry to find substitutes for the microscope and change its 200 year-old habit. Therefore, we can safely conclude that the buyer power of microscopy industry is relatively weak.

If we look at the components of a microscope, its most expensive and fragile parts are the lenses. Looking at the major supplier microscopes, the optical instrument industry, we find an interesting phenomenon–the major players in the microscopy industry, such as Nikon and Carl Zeiss Ag (McWilliams, 2013, p. 135), also have business in optical instrument manufacturing industry (Oliver, 2015; Uba, 2015). This shows that the suppliers of large microscope companies are themselves; these companies most likely found it profitable to perform backwards integration by bringing manufacturing in-house. The supplier power is thus weak for the large companies in the industry. However, this also means small companies and OEMs in the industry need to buy lens from their major competitors. The supplier power for small companies in the industry is quite high. In order to mitigate the strong supplier power from those big players, we designed our product to be lensless. The electrical components of our product, a LED array and a CCD camera, are easily replaceable. Therefore, we can conclude that the supplier power for our product is also relatively weak.

**Threat of Substitutes**

Next, we consider the power of substitutes for diagnosis of malaria by evaluating the two major substitutes: clinical diagnosis and Rapid Diagnostic Test (RDT). We show that microscopy remains the de-facto gold standard for diagnosing malaria, and hence, the threat of substitution is weak.

*Plasmodium* is the malaria-causing parasite. Conventional diagnosis of malaria works by staining a patient's blood smears using a mixture of acidic eosin and methyl blue, known as Giemsa's solution. (Fleischer et al., 2004, p. 2). This solution stains the *Plasmodium* infecting red blood cells, allowing technicians to detect their presence under a microscope.

Unfortunately, the microscope has its limitations; financial and technical obstacles combined preclude microscopy from being more widely used. Current microscopes are inherently bulky and expensive. Furthermore, the typical optical microscope requires a trained technician to operate, increasing the difficulty of getting a good microscopy test in poor rural regions.

In spite of that, medical experts widely consider Giemsa microscopy to be the most reliable method for diagnosis (Murphy et al., 2013, p. 2). This is due to its low per-use cost, at approximately USD $0.12 0.40 per smear (Wongsrichanalai et al., 2007, p. 6), and its ability to quantify accurately, the severity and variant of *Plasmodium* in the blood sample. This is also the reason why we have targeted malaria diagnosis as our initial market; our simpler lensless microscope can increase the accessibility and affordability of good microscopy service in this much needed market.

**Clinical Assessment**

We now consider the most basic form of diagnosis: clinical assessment by a doctor. The process of clinical diagnosis starts with recording a patient's travel history. More specifically, this considers any high-risk endemic area in a one-year window prior to diagnosis, such as Africa, North Korea, or North India. However, this has the flaw of assuming an accurate travel history. In addition, the highly variable incubation period across *Plasmodium* variants means that, in some cases, even a one year period is not enough to cover all bases. For example, the vivax variant of *Plasmodium* found in North India and Korea will only start attacking the body 12-18 months after the mosquito bite (Griffith et al., 2007).

Moreover, even after establishing the travel history, recognizing malaria infection based purely on symptoms is not straightforward. Early symptoms of malaria bear many similarities to other common diseases, such as fever, chills, headache, and malaise. Inevitably, this complication hampers the early diagnosis of malaria, especially when it is at its most treatable stage. Unfortunately, it is only in the later stages in which the most telling, but fatal, symptoms surface. These includes coma, anaemia, hypoglycaemia, and more (WHO, 2010, p. 4).

Ultimately, diagnosis itself cannot provide confirmation of malaria infection. This implies that most clinical diagnosis will invariably fall back on microscopy as a final step. Naturally, it seems reasonable to deduce that pure clinical diagnosis is a weak substitute for giemsa microscopy.

**Rapid Diagnostic Test**

The next best alternative is known as Rapid Diagnostic Test (RDT). RDTs are dipsticks which indicates the presence of antigens (proteins) secreted by *Plasmodium* in the blood. A patient uses a RDT by pricking a small amount of blood on a test strip containing antibodies targeting specific *Plasmodium* antigens. Depending on the result, the blood colors the test strip in a specific manner, allowing

a quick diagnosis.


Figure 2.6: Example of a Rapid Diagnostic Test, BinaxNOW from Alere. Source: `https://ensur.invmed.com/ensur/broker/ensurbroker.aspx?code=12000304&cs=26232437`

The advantage of using RDT is that it is fast and easy to use. Unlike a microscope, the small RDT test kit can be brought out to the field, and be used by an untrained person by reading off the strip. It also does not require an electricity source. Most importantly, the RDT can give an indication within 5-20 minutes, making it suitable for screening a larger number of people. This also accounts for its recent popularity. These tests are increasing in popularity and use in recent years, with 319 million units of reported sales in 2013, up from 46 million in 2008 (WHO, 2014, p. 22).

Despite its popularity, RDTs remain far from being a microscopy replacement. The first issue is that RDTs are only sensitive towards one variant of *Plasmodium*, the falciparum. For other variants, the RDT becomes less sensitive, especially when parasite density is low (Wongsrichanalai, 2007). This opens up the danger of false negatives. Second, the RDT is unable to distinguish between variants of *Plasmodium*, which is essential for effective treatment. Third, RDTs cannot quantify the concentration of the parasite in the blood, which indicates the severity of infection.

The limitations of RDT put it, at best, a complementary product, rather than a substitute, for microscopy. It is currently well-suited for giving quick diagnosis in areas where microscopes or technicians are unavailable.

Having considered the available substitutes, we believe NoScope attacks a sweet spot in the space of diagnosis by offering diagnostic reliability, accuracy, ease of use (no optical focusing), and affordability. By carefully segmenting an application of microscopy that has no viable substitutes, we have positioned our lensless microscope in a strategically strong position. As such, a vital specification of our microscope is to be able to resolve the *Plasmodium* variants, as well as doing it affordably, in order to

place ourselves in an advantageous position in the malaria diagnosis market.

Upon examining the competitive forces in our chosen market, we expect to encounter strong barriers to entry. We can circumvent profit loss by taking advantage of the lensless nature of our system. This lack of optical components also contributes to our highly competitive price point, which fuels our use of the disruptive innovation model of entering a market. Large companies ultimately would not provide strong retaliation due to factors of price point, R&D costs, and self-competition. We find buyer power weak due to the large demand for microscope and the unique value of NoScope. Supplier power does not dampen profitability considerably due to the interchangeability of suppliers that our system design affords us. Our affordable and powerful design is highly competitive against the available substitutes. Altogether, we expect these competitive forces to weigh little against our potential profitability.

## 3.2 Competitive Pricing in a Saturated Market

While the previous section covered the broader business strategy, this section will cover our specific competitive pricing tactics for NoScope. Too low of a price will hurt profits and will not allow us to expand quickly. Too high of a price, however, would put us in direct competition with large microscope producers whose brand recognition and R&D power we cannot match.

### The Top-down Approach

To determine the optimum price, we used a top down approach and analyzed Nikon's annual shareholder report. As one of the leading microscope producers, Nikon's 2013 net sales for optical instruments was 41.9 million dollars (Nikon, 2013). At an average cost of $530 per microscope, calculated using `http://amscope.com`'s inventory, this comes to 79,056 units sold per year. Our team wants NoScope to have a 5 year first-generation life cycle with one year of R&D Preceding. Being a smaller startup, our expected sales per year were determined as a fraction of Nikon's annual sales, with expected sales approximately doubling each year as the company grew.

The Bill of Materials for NoScope was calculated using reputable vendors such as DigiKey. This in combination with employee costs was used to calculate annual sunk costs (Figure 2.3). Using this data, we determined that in order to turn a profit on NoScope after three years we would need a product cost of $120.60. Calculating a 50% buffer for unexpected costs leads to a final price tag of $189.99 per unit. This is well below the average traditional microscope cost allowing us to compete with

established rivals price-wise, while still remaining competitive in the event of new market entrants.


Figure 2.7: Accumulated costs vs. units sold for product lifecycle

As mentioned above, we estimate NoScope's Generation 1 Life cycle to last five years. Using the Stages in the Product Life Cycle (Figure 2.4), this would account for our introduction and growth period. While firmware updates will still be pushed through the end of the product's lifecycle, during the last two years, all hardware development will be shifted towards creating a second generation of NoScope.

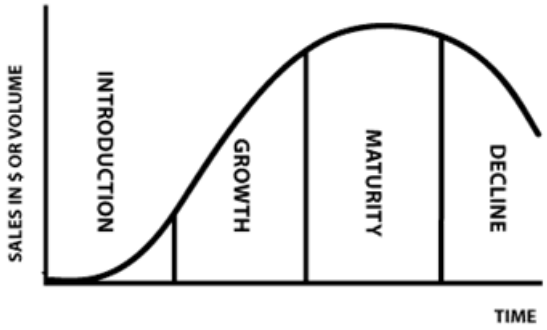


Figure 2.8: Product Life Cycle illustration Source: `https://serrvartisans.files.wordpress.com/2012/03/productlifecycle.gif`

The second generation will be slightly more economical, yet offer more features, such as automatic disease diagnosis and cloud storage services. At this point we will heavily push marketing and brand recognition, having built a stable user base with the first generation model. When NoScope extends from Growth to Maturity, our team will branch off into two distinct consumer products: a medical grade microscope for doctors and other professionals, and a consumer model suitable for schools and

affordable enough to be bought in bulk.

Further on, our company will form an R&D team to research future expansions and applications for our technology. When NoScope enters into the Decline portion of the life cycle, all efforts will be put towards commercializing R&D's prototypes. This may involve changing markets entirely (targeting maker/hobbyist fields instead of medical professionals) and will depend entirely on current market trends. We estimate the total time period from Introduction to Decline to be 10 years, following current market trends as well as the computational "Moore's Law" stating how computing power doubles approximately every 18 months, causing our product to become obsolete if we do not modify it.

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# A Return of Investment Calculations

Costs Calculation

| | Year 1 | Year 2 | Year 3 | Year 4 | Year 5 | Year 6 |
|---|---|---|---|---|---|---|
| 41900000 | 0 | 0 | 7876 | 23628 | 55132 | 118139 | 236278 |
| Annual Sales: | 0 | 0 | 0.1 | 0.3 | 0.7 | 1.5 | 3 |

| Part # | Units per Part | Cost Per Part | Annual Cost | |
|---|---|---|---|---|
| ATtiny2313 | 1 | 0.745 | $5,867.58 | |
| HC595 Shift Reg | 1 | 0.1108 | $872.65 | |
| LED Matrix | 1 | 50 | $393,796.99 | |
| CMOS Camera | 1 | 2.02 | $15,909.40 | |
| Camera Module | 1 | 20 | $157,518.80 | |
| Housing | 1 | 10 | $78,759.40 | **$652,724.82** |

| Part # | Units per Part | Cost Per Part | Annual Cost | |
|---|---|---|---|---|
| ATtiny2313 | 1 | 0.745 | $17,602.73 | |
| HC595 Shift Reg | 1 | | $0.00 | |
| LED Matrix | 1 | 50 | $1,181,390.98 | |
| CMOS Camera | 1 | 2.02 | $47,728.20 | |
| Camera Module | 1 | 20 | $472,556.39 | |
| Housing | 1 | 10 | $236,278.20 | **$1,955,556.48** |

| Part # | Units per Part | Cost Per Part | Annual Cost | |
|---|---|---|---|---|
| ATtiny2313 | 1 | 0.745 | $41,073.03 | |
| HC595 Shift Reg | 1 | | $0.00 | |
| LED Matrix | 1 | 50 | $2,756,578.95 | |
| CMOS Camera | 1 | 2.02 | $111,365.79 | |
| Camera Module | 1 | 20 | $1,102,631.58 | |
| Housing | 1 | 8 | $441,052.63 | **$4,452,701.97** |

| Part # | Units per Part | Cost Per Part | Annual Cost | |
|---|---|---|---|---|
| ATtiny2313 | 1 | 0.745 | $88,013.63 | |
| HC595 Shift Reg | 1 | | $0.00 | |
| LED Matrix | 1 | 20 | $2,362,781.95 | |
| CMOS Camera | 1 | 2.02 | $238,640.98 | |
| Camera Module | 1 | 15 | $1,772,086.47 | |
| Housing | 1 | 8 | $945,112.78 | **$5,406,635.81** |

Page 1

Costs Calculation

| Part # | Units per Part | Cost Per Part | Annual Cost | |
|---|---|---|---|---|
| ATtiny2313 | 1 | 0.745 | $176,027.26 | |
| HC595 Shift Reg | 1 | | $0.00 | |
| LED Matrix | 1 | 20 | $4,725,563.91 | |
| CMOS Camera | 1 | 2.02 | $477,281.95 | |
| Camera Module | 1 | 15 | $3,544,172.93 | |
| Housing | 1 | 8 | $1,890,225.56 | **$10,813,271.62** |

| Employee Costs | Engineers | Executives | Support Staff | Support Payroll |
|---|---|---|---|---|
| Year 1 | 5 | 0 | 0 | $500,000.00 |
| Year 2 | 3 | 2 | 2 | $700,000.00 |
| Year 3 | 6 | 2 | 3 | $1,050,000.00 |
| Year 4 | 6 | 2 | 5 | $1,150,000.00 |
| Year 5 | 8 | 2 | 7 | $1,450,000.00 |
| Year 6 | 13 | 2 | 10 | $2,100,000.00 |

Page 2

ROI

| | | | | | | |
|---|---|---|---|---|---|---|
| ROI Period (yrs) | 3 | | | | | |
| Year | 1 | 2 | 3 | 4 | 5 | 6 |
| Total Costs: | $500,000.00 | $1,352,724.82 | $3,005,556.48 | $5,602,701.97 | $6,856,635.81 | $12,913,271.62 |
| Product Cost: | **$120.75** | | | | | |
| Product Cost (x1.5) | **$181.12** | | | | | |

# Part III

# IP Strategy

# 1 Introduction

This portion of the report is not meant to be an exhaustive analysis on all possible forms of intellectual property protections. Instead, this is meant to be an extension on our business strategy in the previous section, and a brief outlook on the most pressing IP concerns that may aid or hamper us in NoScope's competitiveness in the microscopy arena.

The most unique and potentially patentable portion of our project is the hardware. Four main pieces comprise our system: the LED array and its controlling system, a sample holder, a camera sensor, and a moving stage to mount the sensor. In particular, it is the specific combination of these components that succinctly captures the three critical value propositions of our project: 3D imaging, lack of lenses, and super-resolution. Light from different, single LEDs will cast shifted images of a specimen directly on our CCD camera sensor, giving us the angular information we need to perform 3D reconstruction of the specimen. In addition, the moving stage allows us to translate the camera sensor in microscopic scales - this creates multiple shifted versions of a single image, allowing us to combine these images using super-resolution techniques to a higher resolution than our physical pixel would allow.

The reasons to focus on hardware patenting over image processing algorithms stem from concerns of practicality. First, most of the algorithms we use are based on already published work, precluding any sort of claim on them. Second, many of our competitors have successfully patented their hardware, and this sets a strong precedence for us to consider following the same route. Moreover, one of our close academic competitors from UCLA, which we have analyzed in the business strategy paper, has successfully patented a utility patent with USTPO.

However, the fact that the UCLA Ozcan group has filed a patent using a technology very similar to ours is also a cause of concern. In the next section, we will examine in detail, their group's patent, and demonstrate that our hardware does not infringe their claim. Finally, after establishing the viability of obtaining a patent, we will explain why team NoScope believes that, although obtaining a patent is crucial for getting the product to market, it will do little to maintain our competitive edge in the long-term.

# 2 Examining our Competitor's Patent

The name of the patent is "Lens-free wide-field super-resolution imaging device". Its schematic representation of the invention is shown in figure 1 below. In the abstract of the patent, the group describes their design as an imaging system with "an image sensor and a sample holder disposed adjacent to the image sensor" (Ozcan et al, 2014), which bears similarity to our design. Their design also includes "an illumination source configured to scan in two or three dimensions relative to sensor array" (Ozcan et al, 2014), which is also similar to our system. They included LEDs as one type of their illumination sources. In addition, they mentioned in the patent "the system includes least one processor configured to reconstruct an image of sample", similar to NoScope.

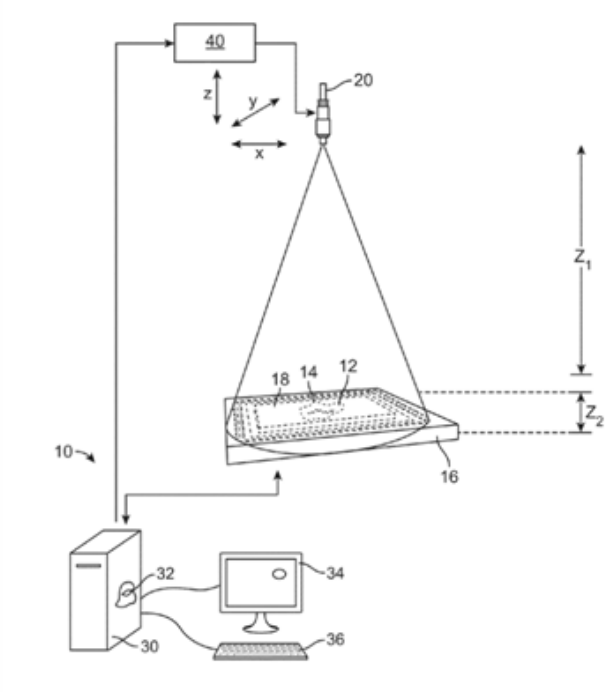


Figure 3.1: Schematic representation of invention of patent filed by Ozcan Research Group (Ozcan 2014, p3)

## 2.1 Their Five Claims

Although Ozcan's patent has many similarities to our own, there is no possibility of a successful lawsuit on their part due to key distinctions between their patent's claims and our product. Ozcan's patent has 29 claims (Ozcan et al, 2014), which serve to distinguish whether infringement has occurred. Of these 29 claims, there are five main ones with the rest being smaller elaborations to the "big five"

claims, e.g., different light sources or minor changes to the setup. The major claims are diagrammed below.

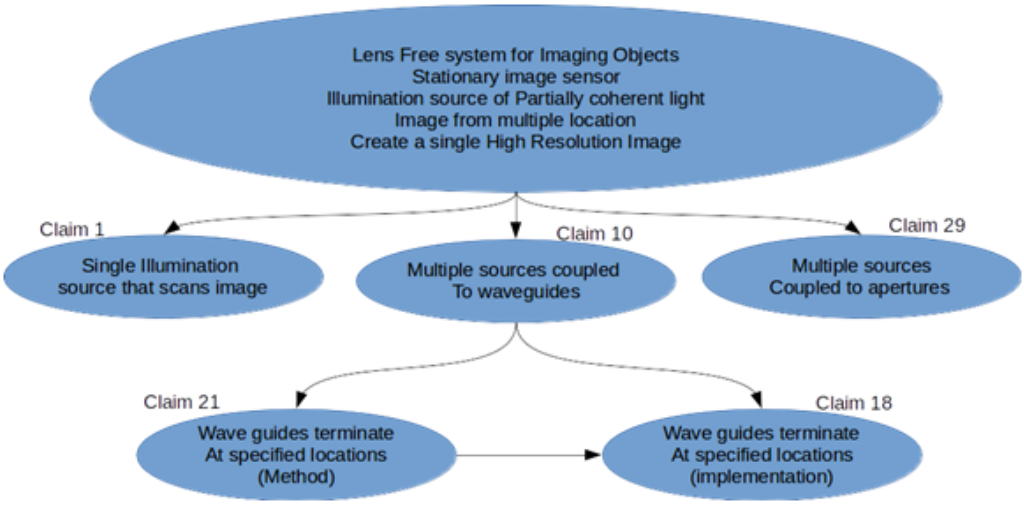


Figure 3.2: Summary of 5 major claims of Ozcan's lens-free microscope.(Ozcan 2014). Arrows connecting claims imply that the claim has all the features of it's parent claim, and additionally it's own sub-features.

To analyze whether our group would be in violation of these claims, each major claim was analyzed using the concept of "Doctrine of Equivalents", articulated in a classic Warner vs. Hilton law case as a test for whether a product violated the claims of a patent (Warner/Hilton, 1997). The Doctrine acts as a three point test. If a product "performs substantially the same function in substantially the same way to obtain the same result," (Warner/Hilton, 1997) it is in violation of the patent's claim. Fortunately for our group, while parts of Ozcan's claims perform substantially the same function in substantially the same way, none of them obtain the same result. Ozcan's patent exclusively covers the creation of a single high-resolution, or "super-resolution" image from a series of lower resolution images. Our group creates a 3D image of the object being imaged, and does not currently make any claims for super-resolution imaging, as we are limited by the resolution of our imaging device. This notable difference would make us exempt from any infringement claims Ozcan's group could make regarding their patent.

# 3 Competitive Advantage of a Patent

In our previous section, we examined one of our closest academic competitors, Ozcan Group of UCLA, and determined that it is indeed possible for us to file a similar hardware patent that would not infringe on any of their claims. In this section, we will examine the competitive advantages a patent confers in getting our product to market, and finally, make an overall recommendation on devising our intellectual property strategy.

## 3.1 Differentiation - Hallmark of Innovation

A key advantage of filing for a patent is that it acts as a key differentiating point for our product, especially in a technologically driven industry like microscopy. According to BCC, which performed a filtered search for on USPTO, a large company such as Olympus holds approximately 58 utility patents on optical microscopy (McWilliams 2013: 38). In pitting against ourselves against these large rivals in microscopy, a patent is almost a necessity in signifying technological innovation in our product.

In addition, patents are also vital for the process of raising capital if we were to begin as a startup company. For a startup with focus on selling a hardware device, a patent is not only a direct indication of innovation, it is also the assurance that we hold the legal right to produce and manufacture the product. Conversely, a lack of patent raises doubts from potential angels or venture capitalists looking to invest into NoScope. Obtaining a patent would be an unavoidable requirement if we wish to start a company around our lensless microscope.

## 3.2 Looking beyond the patent

However, beyond the practical purpose of securing funding and differentiating ourselves from our competitors, a patent will provide negligible long-term competitive advantage in the microscopy market. The first reason is that microscopy is by nature an international market. Filing for patent protection in multiple countries is both time-consuming and expensive. In traditional optical microscopes, the U.S. only accounts for 34% of the overall market (McWilliams 2013: 125). Moreover, as detailed in our strategy section, we are targeting malaria-endemic areas, which includes a considerable number of countries such as North India, and regions in Africa. Unfortunately, IP laws are only applicable in the country in which the patent is filed. Our lensless design will not be protected in our primary geographical market, and the financial resources required for multiple patent filings is prohibitive for

a new entrant like us.

Moreover, unlike what conventional wisdom would suggest, a patent in the microscopy market is unlikely to prevent competitors from producing similar, yet non-infringing designs. For imaging in microscopy, multiple ways of achieving the same function exist, many of which are based on well-established academic work, such as super-resolution. A clear example would be how we ourselves have circumvented UCLA's patent claims with a different illumination device, as well as using a moving sensor stage, in order to achieve similar functions of pixel super-resolution. Thus, it does seem reasonable to deduce that there will likely be potential competitors producing altered designs that can directly compete with NoScope.

Taking into consideration the above drawbacks, our group thus believes that obtaining a patent is a necessary step in order to bring the product to market. While it is necessary for raising capital in the early stages, a patent will not help us establish a monopoly in the malaria niche we segmented. This brings us back to our final point we made in our business strategy paper: a long term sustainable advantage in the microscopy market requires constant innovation, and a continually improving product.

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# Part IV

# Individual Technical Contribution

# Contents

# 1 Overview

The NoScope team is intended to prototype a lens-less diagnostic tool that could create 3D images. Unlike traditional optical microscopes, the NoScope contains no optical lenses. Rather, it achieves magnification and 3D display through post sampling image processing based on limited angle tomography (Kak et al., 1988) and light field imaging (Levoy et al., 1996).

Team NoScope has been divided into two sub-groups, in charge of computational imaging algorithms and hardware system design. Ryan and I are responsible for the hardware design. In the fall semester, we cooperated on the general system setup and the modeling of the LED array. The procedures and results for LED modeling will be covered in this paper. In the spring semester, we have worked separately to speed up the prototyping process. My responsibilities include selecting crucial hardware components, prototype manufacturing, and taking samples for algorithm verification.

My individual work ties closely to the main goal of the overall project. As mentioned in the Intellectual Property Strategy (Cui et al., 2015), the hardware system is potentially most patentable portion of the project. The system captures the critical value of our product. It has been revised based on feedbacks from the algorithm development team, in order to enable the functionalities designed by the imaging algorithms. The hardware system also restricts the capability of the NoScope. The camera and the 3-axis stage determines the image resolution, as will be discussed in detail in a later section. Thus, it is important to select suitable hardware that fit the over all design of the NoScope.

This paper first examines precedent lens-less imaging systems, and then contrasts their capabilities with the NoScope. In the next section, it presents the process of component selection, and the procedures of modeling LED radiation pattern. In the last section, the LED radiation pattern, the final prototype, the method of prototype manufacturing, and general procedures for using the NoScope are presented.

# 2 Knowledge Domains

As mentioned in the intellectual property strategy section, the hardware design is the most unique and potentially most patentable portion. Therefore, in previous sections, differences between the NoScope and its competitors have been examined extensively (Cui et al., 2015). Apart from the market or legal point of view as presented before, this section intends to offer an academic background for this comparison. It starts with the general motivation for lens-less microscopy, followed by designs of previous systems. Then it points out the significant difference between the NoScope and precedent systems, and how does this special design makes the NoScope a more advanced product.

In the last few years, several lens-less digital computational microscopes have been introduced to the biomedical community. To begin with, the lens-less imaging device is part of the effort for speeding up the process of handling microscopy samples. Integrating the compact microscope into a lab-on-a-chip platform, lens-less device has eliminated the time consuming lens-alignment process required by most optical systems (Oheim, 2007). Second, lens-less microscope can achieve a higher resolution combined with high field-of-view (FOV), which is impossible for traditional microscope with optical lenses (Xu, et al. 2001). Although they provide high resolutions associated with high magnification, optical lenses also narrow down the depth of focus. Therefore, lens-less imaging device, whose resolution is independent of optical lenses, can achieves higher FOV without sacrificing its resolution (Isikman, et al. 2011).

Hence, there is an ongoing research on lens-less device in the past few years. Early digital in-line holography devices used point sources generated by a single laser and a pinhole. They used magnified diffraction patterns to digitally reconstruct testing objects (Xu, et al. 2001). However, the number of fringes captured by cameras limited the resolution, so images at oblique illumination angles can only be achieved by rotating the camera along with the illumination (Isikman et al. 2011). In order to make the device more compact, the Ozcan Research Group at UCLA has proposed an alternative design, field-portable tomographic microscope, which shifts the light source 50 degrees around the sample (Isikman, et al. 2011). This provides a unit fringe magnification, and makes the in-line holography possible for illumination angles larger than 40 degrees without shifting the receiving camera (Isikman, et al. 2011).

The NoScope further improves the functionality of the field portable tomographic microscope by using a different light source. The NoScope uses a 32 by 32, flat LED array, instead of a rotated light source along two axes. The flat LED array provides more than two LED axes, giving the NoScope advantages for combating the limited angle artifacts for the tomography method. However, the images are distorted by the flat LED array, since the LED light is no longer perpendicular to the camera. This undesired distortion is been corrected using a translation algorithm, mentioned in Cui's technical report (Cui, 2015).

# 3 Methods and Materials

## 3.1 Hardware Component Selection

The LED array, the camera, and the 3-axis stage are components that directly determine the capability of the NoScope. Hence, it is important to first determine the criteria for the system design, and then select the most suitable components with appropriate specifications.

The LED array provides a multi-angle illumination light source, which provides angular information that enables 3D reconstruction. More angular information leads to more accurate result for both tomography and light field methods. As for flat LED array, the incident angle can be increased by increase the distance between the corner and the center LED, which results in an increased size of the LED array. On the other hand, smaller LED array is more desirable, since it can result in a more compact device. Therefore, it is important to select a LED light array that is large enough to provide enough angular information. Thus, the 32 by 32 RGB LED Matrix by adafruit is chosen. It contains 1024 LEDs on a 32 by 32 grid, 4 mm apart from each other (Adafruit, 2015).

The camera determines the quality of the samples. The pixel size of the CCD (charge-coupled device) camera limits the highest resolution of the images. However, as the pixel size becoming close to the visible light wavelength, additional algorithm is needed to increase the resolution by compensating the diffraction effect (Tian, 2014). Since the current computation algorithm does not contain the correction for diffraction pattern, it is sufficient to select a relatively larger pixel size, so the diffraction will not affect the quality of the images. Additionally, the distance between sample and CCD sensor also limits the selection of camera. Due to the lens-less nature of the NoScope, it requires an extremely short sample to camera distance to achieve a sharp image. Based on consideration mentioned above, DCC3240C, a high sensitivity USB 3.0 CMOS camera is used for the NoScope. The pixel size of the camera is 5.3$\mu$m, and the sensor area is 6.78mm by 5.43 mm (Thorlabs, 2015). By removing the cover glass of the camera, sample slides can come within 1mm from the camera sensor, which provide enough freedom for adjusting the sample distance.

The 3-axis stage is used to precisely adjust the location of the camera for alignment, and translate the camera in microscopic scale for super-resolution. The resolution of the stage should be about the

same as the pixel size of the camera, so the camera can still capture the entire sample after shifting. For the same reason, a graduated stage is more desirable, since the stage will not accidentally shift the camera too much. In addition, knowing how much the stage shifted helps to reset the stage back to its original location, so it is much easier to align the camera after measurements.

## 3.2 LED Modeling

Both tomography and light field algorithm is build on an assumption of a constant light intensity (Hardiman, 2015; Lee, 2015). However, light intensity received from a single LED changes when observed from different angles, forming a radiation pattern. When the observer directly faces the LED, the received light intensity is the maximum. As observer turning away from the light source, the received light intensity decreases. When the observer is 90 degree from the light path, the received light intensity is zero. Since the CCD camera sensor is much smaller than the LED array, intensity variation caused by different illumination angle should be accounted. In addition, the radiation pattern is also important for prototype design, as will be shown in a later section. It determines the lowest light intensity received by the camera as well as the amount of angular information provided by the systems. Both will further affect the accuracy of the final 3D images.

Hence, the light intensity of a single LED is measured using OPT101, ADS1115, and Arduino Uno microprocessor. OPT101 is an integrated combination of a monolithic photodiode and trans-impedance amplifier. It can receive radiant power ranges from 300nm to 1000nm, including the visible light spectrum, and produce output voltage proportional to received radiant power (Texas Instrument, 2003). The output signal will then be sampled by ADS1115, a 4-channel ADC (analog to digital convertor) breakout board. This board samples the input voltage at 860 sample per second, and provides a 16 times gain (Adafruit, 2015b). It also includes an I2C interface, which allows data transfer between the board and the microprocessor, Arduino Uno. The microprocessor will finally pass the data to a computer through serial ports.

A rotation stage, URS75BPP, is also attached to the LED array, allowing measurements from different angles. URS75BPP is a high precision rotation stage, which provides 360 degrees continuous motion. However, due to the malfunction URS75BPP's step motor, the rotation stage is used with a manual drives, with one-degree rotation precision.

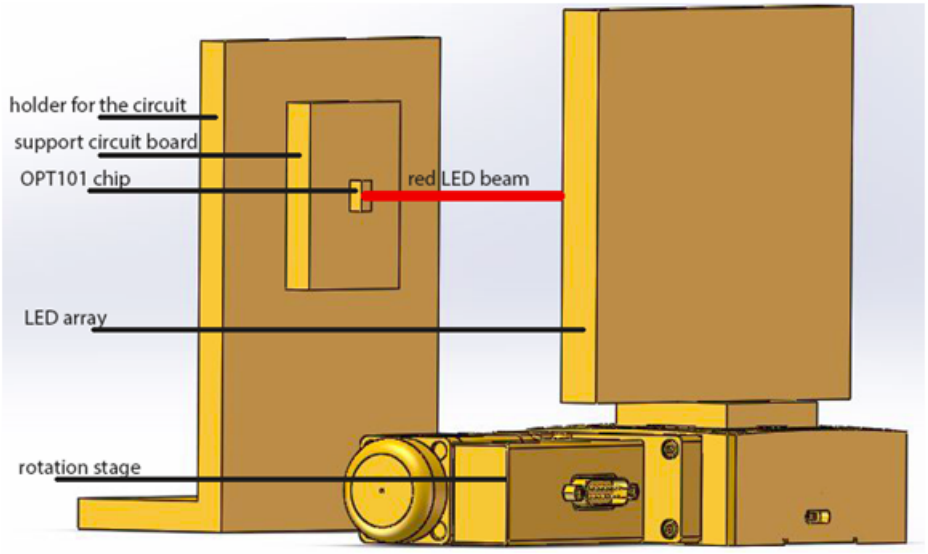


Figure 4.1: System used for LED radiation modeling.

Figure 4.1 illustrates the measurement setup. The LED array is placed on the rotational stage, with the center LED aligned with the OPT101 chip. The OPT 101 chip is driven by an Arduino Uno microcontroller, which displays the detected light intensity on a computer (not showing in the Figure). With absolutely no additional light source, the intensity of the LED is measured for every 5 degrees, from 0 to 90 degree.

Each single LED location contains three LED diodes, providing monochromatic red, green, and blue. Since in the final prototype, all three diodes are turned on simultaneously creating a white light, the light intensity of the white light is calculated by adding up the intensity of all the other lights. Matlab is then used to process the intensity data and fitting it to a monopole model.

# 4 Results and Discussion

## 4.1 LED Modeling

The result of LED calibration is shown in the polar plot, in Figure 4.2. The measured data (the doted blue line) displays an expected oval shape, roughly matches the simulation data for a monopole illumination paten. However, at lower angle, the measured intensity is slightly less than the simulation, meanwhile at higher angle, the measurements has a higher intensity than the simulation. This difference might due to the structure of the LED array. All the LED lights are mounted in a flat 32 X 32 grid, but the light beams are not strictly perpendicular to the grid. Rather, it has been diffracted by the edge of the grid, which reduced the light intensity at lower angle relative to higher angles.

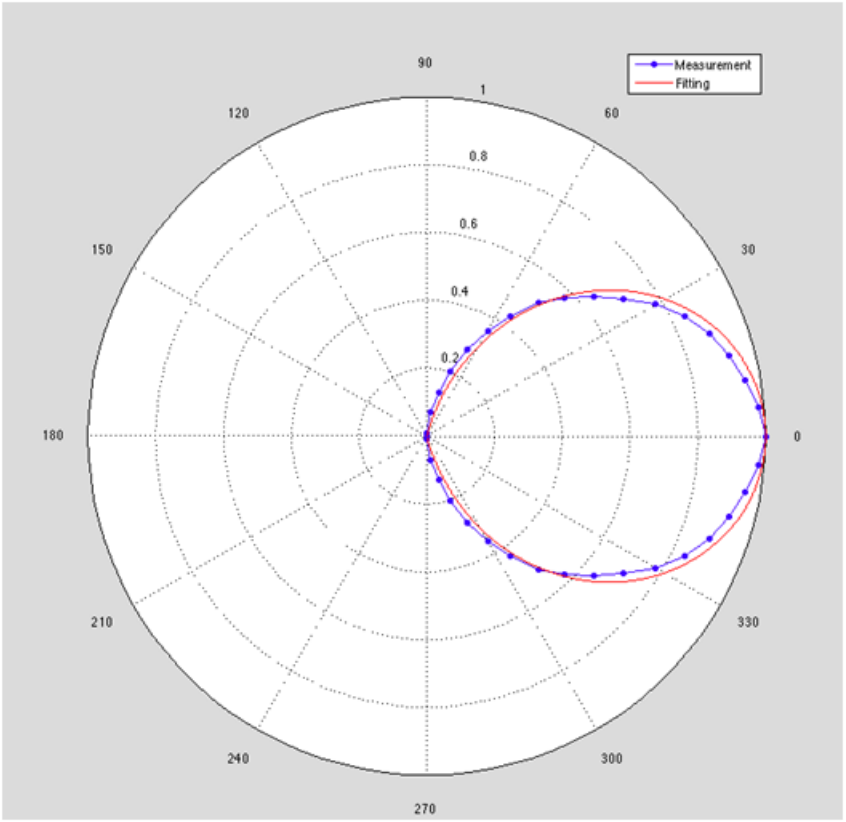


Figure 4.2: Polar plot of LED intensity measured and modeled.

However the overall intensity inaccuracy is only 0.32% of the maximum intensity measured at 0 degree,

and thus can be ignored. The function for the fitted model is

$$I = I_0 \cos(1.2\theta) \tag{1}$$

where $\theta$ is the illumination angle, and $I_0$ is the largest intensity measured at 0 degree. This result can be used later to determine the distance between the LED array and the CCD camera sensor.

## 4.2 Final Prototype

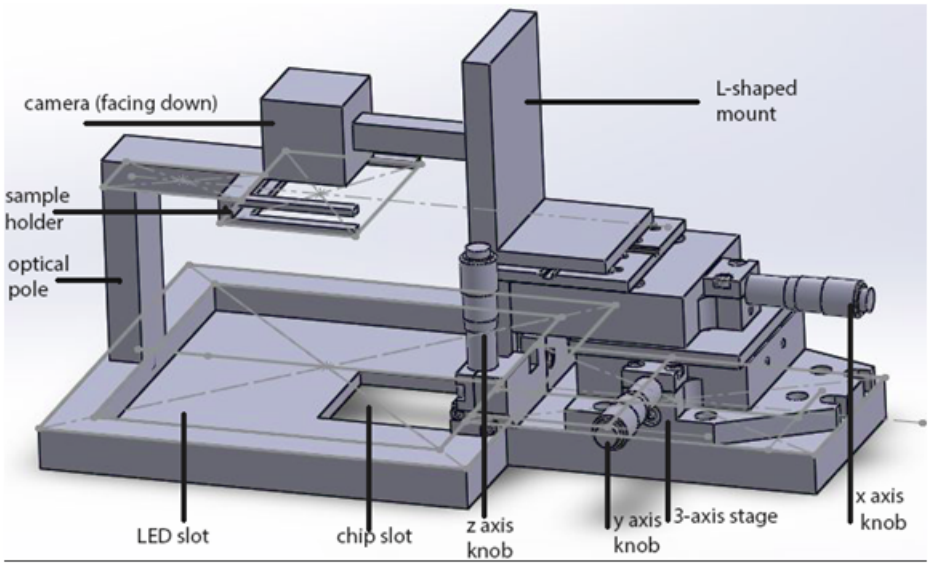


Figure 4.3: Isometric view of the cad model for the hardware system.

Figure 4.3 is an isometric view of the final prototype. The camera attaches to the 3-axis stage through a pole and a L-shaped mount. Below the camera is a sample holder, attached to an adjustable optical pole. A LED array can be placed in the frame facing toward the camera, and a trench is cut on the frame to place the cable and the control chip of the LED array. The centers of the LED array, the sample slides, and the camera sensor are aligned. Next to the LED frame is a platform to attach the 3-axis stage.

Apart from the physical dimension of the elements, there is one more limitation for the prototype design: the distance between LED array and the camera. As the distance decreasing, the illumination angle of the LED increases, so the light intensity camera received decreases, based on the model

shown in the previous section. However, larger illumination angle results in more angular information, which increase the accuracy for tomography method. Therefore, the largest illumination angle shall be determinate based on the two factors mentioned, and the distance between the camera and the LED array can be calculated based on this angle. It is initially set to 50 degree, the same as the largest illumination angel of the field portable tomographic microscope constructed by the UCLA group (Isikman et al. 2011). Based on the model presented in the previous section, the intensity for this illumination angle is:

$$I = I_0 \cos(1.2\theta) = 0.5 I_0 \tag{2}$$

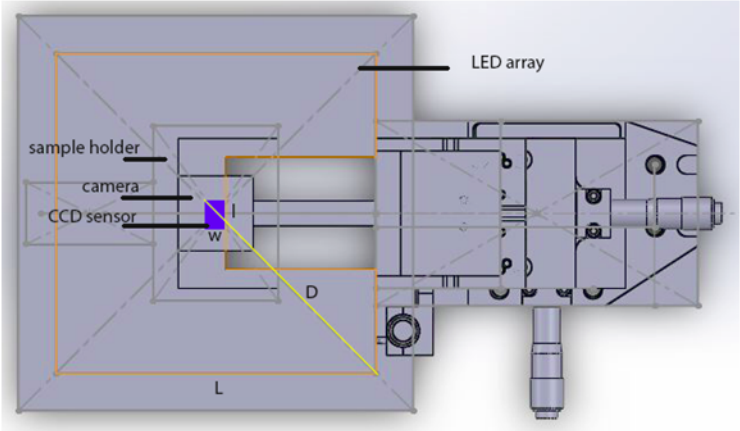


Figure 4.4: Top view of the hardware system.

As highlighted with an yellow line in figure 4.4, the longest distance between the camera sensor and LED light, $D$, is:

$$D = \sqrt{(\frac{L+w}{2})^2 + (\frac{L+l}{2})^2} = 9.48cm \tag{3}$$

where L is the length of the LED array, l and w is the length and width of the camera sensor. From figure 4.5, the distance between the camera and the LED array, H, can be calculated using trigonometry:

$$H = D \times \tan(90 - \theta) = 7.96cm \tag{4}$$

For a 1mm sample, the distance between camera and sample holder, h, is:

$$h = d \times \frac{H}{D} = 2mm \tag{5}$$

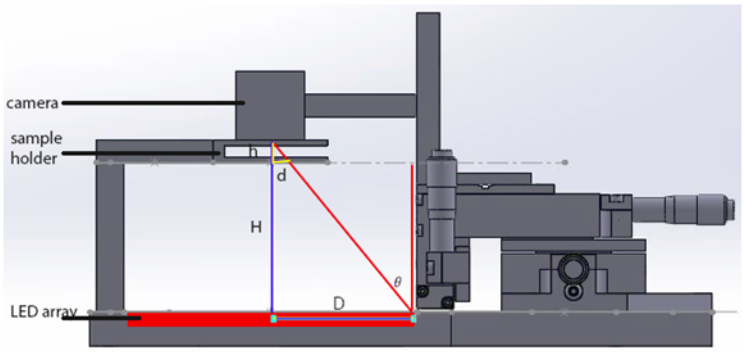


Figure 4.5: The side view of the hardware system.

However, for other samples, the distance H and h can be adjusted by accommodating the adjustable optical pole and the z-axis of the 3-axis stage.

## 4.3 Prototype Manufacturing

In order to construct a portable sampling device, a baseboard is built to anchor the sample holder and 3-axis stage. It is manufactured using equipment in CITRIS Invention Lab. The initial approach for housing was to use the Afinia H-Series FDM printers, the so-called 3D printer. However, given the large dimension of the baseboard, this method is infeasible for the following three reasons. First, the building area is 0.255m long and 0.205 m wide, which is too small to manufacture a baseboard holding a 0.128m LED array together with a 0.13m 3-axis stage. Second, contraction of the polyactic acid plastic, the printing material, could cause the baseboard to warp, and prevent the set up from aligning. Third, 3D printing is also time consuming. Therefore, VLS3.50 Laser Cutter is used instead. The laser cutter can process material 0.61m by 0.305m, and produce the baseboard in less than five minutes.

The baseboard now consists five layers of $1/8^{th}$ inch thick acrylic board with slightly different design to fit optical bolts and nuts. The design is shown in Figure 4.6 and 4.7. The top two layers of the baseboard contain 5 holes to attach the adjustable optical pole and the 3-axis stage using optical bolts.

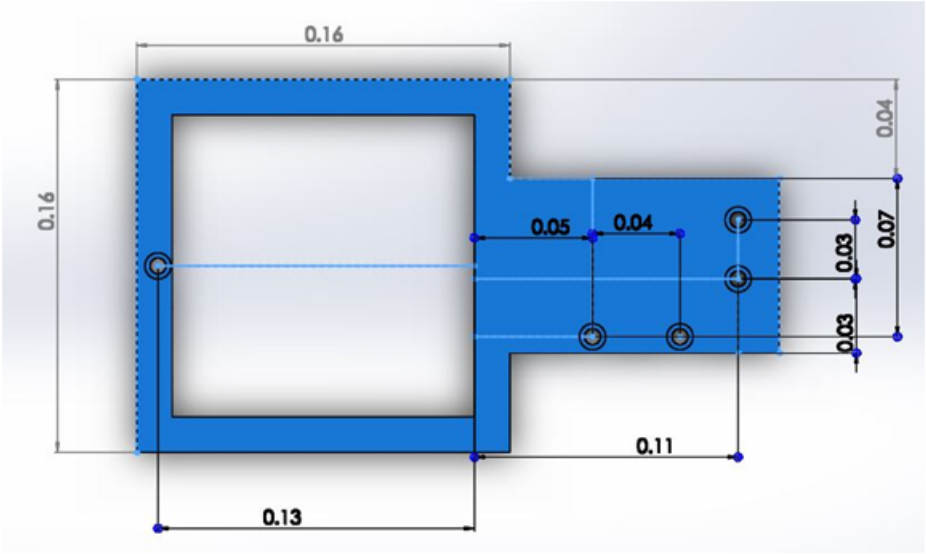


Figure 4.6: Top view of the first two layer of the baseboard.

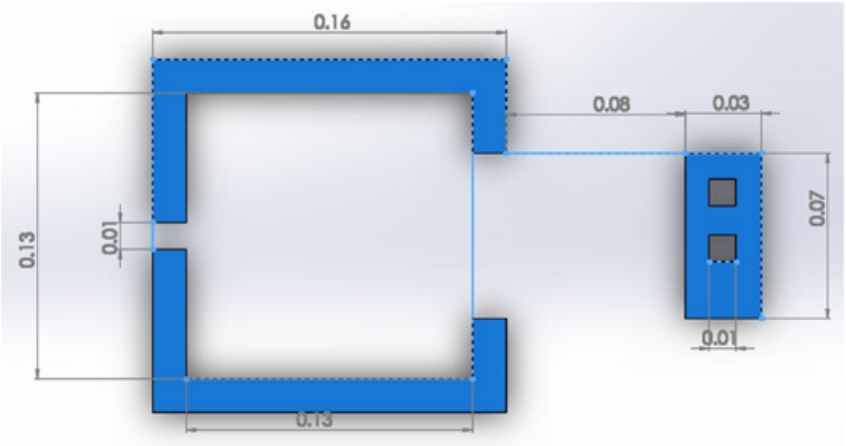


Figure 4.7: Top view of the middle two layer of the baseboard

The next two layers, as shown in Figure 4.7 contain three square-shaped holes to fit the nuts. It also contains a cut to fit the printed circuit board (PCB) used to drive the LED array. The final device is shown below in Figure 4.8.

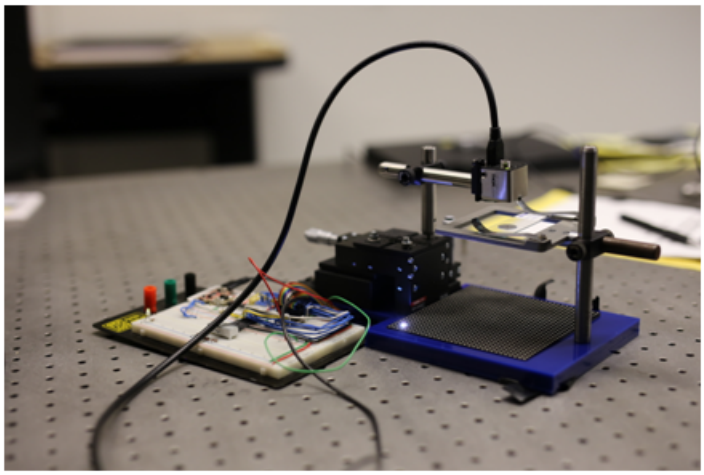

Figure 4.8: The portable NoScope with breadboard aside.

## 4.4 Procedure for using NoScope

This section provides procedures for acquiring sample images using the final prototype of the NoScope. The images are then further manipulated using the computational imaging algorithm to construct high-resolution 3D images. The section includes two main parts: system alignment and image acquisition. This section provides detailed descriptions and the purposes of these steps.

Before taking any picture, the center of the LED array, the sample, and the camera should be aligned, to offer a reference for the computational algorithms. Since the camera is shifted to achieve super-resolution in later steps, the center of the camera and the LED array need to be aligned first. Turn on the center LED, and place the sample at the center of the slide holder, and adjust its position until it presents at the center of the camera. Then adjust the z-axis of the 3-axis stage, so the sample image looks sharp on the camera. Last, turn on the farthest LED located at the corner of the LED array to verify that the camera will capture the entire sample for all images.

After alignment, turn on the LED lights in the array successively, and the camera will take a sequence of images accordingly. After the system finish taking this first set of images, the camera is translated in microscopic scales, by turning the x and y-axis knobs of the 3-axis stage. Another set of slightly shifted images is then taken. Last, repeating the previous steps, and taking images with translation in different directions and distances. Now the samples are ready to be processed on computers.

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# Part V

# Concluding Reflections

# 1 Concluding Reflections

Our team has accomplished most of the tasks proposed in the initial project plan. Up to now, we have assembled a lens-less microscope that is capable to display samples in 3 dimensional images. A minor adjustment we made on our original proposal is the form of our product. Instead of a stand-alone device, which has the ability to process and display the processed data, NoScope now becomes a data-sampling device that relies on a computer to construct the 3D images. This is because the proper functionality of the light field and tomography method requires extensive processing power and memory. Therefore, in order to make NoScope self-contained, it is necessary to refine the algorithms and customize the electrical system, which is very time consuming and impracticable for five engineers to finish in less than a year.

This adjustment leads to the first project management insight I gained from working with NoScope: teams are always overly optimistic with their progresses, and tend to set bigger goals. Unfortunately, unforeseen obstacles can always results in delays of the project progress, and teams need to constantly adjust their schedules reflecting these delays. At the beginning of this semester, our camera was broken, and prevented us from testing our light field algorithms using real experimenting data. Therefore, our software team moved on to develop new algorithms while waiting for the new camera. The hardware team also shifted the housing design to an earlier date.

For future improvements, I would not recommend researchers stick to our schedule and developing the stand-alone device right away. Few more modifications of NoScope might result in an even more robust and reliable device. From the perspective of the physical prototype design, a more customized 3-axes shifting stage might helps to further reduce the size of the entire device. Better cameras with smaller pixel sizes might results in a better resolution. The flatten LED array can also be modified to provide higher angular information to improve the tomography results. For the software development, researchers might need to actively compensate diffraction effect to achieve a better resolution. Also, refinement of the current algorithm is needed to produce a faster and less computationally intensive program.