
PyRealSense Documentation

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Cross-platform `ctypes`/`Cython` wrapper to the `librealsense` library.

Prerequisites

- install `librealsense` and run the examples.
- install the dependencies: `pyrealsense` uses `pycparser` for extracting necessary enums and structures definitions from the `librealsense` API, `Cython` for wrapping the inlined functions in the `librealsense` API, and `Numpy` for generic data shuffling.
- Windows specifics: set environment variable `PYRS_INCLUDES` to the `rs.h` directory location and environment variable `PYRS_LIBS` to the `librealsense` binary location. You might also need to have `stdint.h` available in your path.

Installation

from `PyPI` - (OBS: not always the latest):

```
pip install pyrealsense
```

from source:

```
python setup.py install
```

Online Usage

```
## setup logging
import logging
logging.basicConfig(level = logging.INFO)

## import the package
import pyrealsense as pyrs

## start the service - also available as context manager
serv = pyrs.Service()

## create a device from device id and streams of interest
cam = serv.Device(device_id = 0, streams = [pyrs.stream.ColorStream(fps = 60)])

## retrieve 60 frames of data
for _ in range(60):
    cam.wait_for_frames()
    print(cam.color)

## stop camera and service
cam.stop()
serv.stop()
```

The server for Realsense devices is started with `pyrs.Service()` which will printout the number of devices available. It can also be started as a context with `with pyrs.Service():`.

Different devices can be created from the service `Device` factory. They are created as their own class defined by device id, name, serial, firmware as well as enabled streams and camera presets. The default behaviour create a device with `id = 0` and setup the color, depth, pointcloud, color_aligned_depth, depth_aligned_color and infrared streams.

The available streams are either native or synthetic, and each one will create a property that exposes the current content of the frame buffer in the form of `device.<stream_name>`, where `<stream_name>` is color, depth, points, cad, dac or infrared. To get access to new data, `Device.wait_for_frames` has to be called once per frame.

Offline Usage

```
## with connected device cam
from pyrealsense import offline
offline.save_depth_intrinsics(cam)
```

```
## previous device cam now offline
from pyrealsense import offline
offline.load_depth_intrinsics('610205001689') # camera serial number
d = np.linspace(0, 1000, 480*640, dtype=np.uint16)
pc = offline.deproject_depth(d)
```

The module `offline` can store the `rs_intrinsics` and `depth_scale` of a device to disk by default in the user's home directory in the file `.pyrealsense`. This can later be loaded and used to deproject depth data into pointcloud, which is useful to store raw video file and save some disk memory.

Examples

There are 3 examples using different visualisation technologies: - still color with [matplotlib](#) - color and depth stream with [opencv](#) - pointcloud stream with [VTK](#)

Caveats

To this point, this wrapper is tested with:

- `librealsense v1.12.1`
- Ubuntu 16.04 LTS, Mac OS X 10.12.2 w/ SR300 camera
- Mac OS X 10.12.3 w/ R200 camera

The offline module only supports a single camera.

Build Status

Ubuntu Trusty, python 2 and 3:

Possible Pull Requests

- improvements to the documentation
- more functionality from `rs.h`
- boiler plate code (Qt example?)
- support for several cameras in offline module
- continuous integration for Windows and MacOS

Make sure to push to the `dev` branch.

pyrealsense package

On import, you get access to the `Service` class which handles device creation.

pyrealsense.core module

`pyrealsense.core.Device` (*service*, *device_id*=0, *streams*=None, *depth_control_preset*=None, *ivcam_preset*=None)

Camera device, which subclass `DeviceBase` and create properties for each input streams to expose their data. It should be instantiated through `Service.Device()`.

Parameters

- **service** (*Service*) – any running service.
- **device_id** (*int*) – the device id as hinted by the output from `start()`.
- **streams** (list of `pyrealsense.stream.Stream`) – if None, all streams will be enabled with their default parameters (e.g `640x480@30FPS`)
- **depth_control_preset** (*int*) – optional preset to be applied.
- **ivcam_preset** (*int*) – optional preset to be applied with input value from `pyrealsense.constants.rs_ivcam_preset`.

Returns A subclass of `DeviceBase` which class name includes the device serial number.

class `pyrealsense.core.DeviceBase` (*dev*, *device_id*, *name*, *serial*, *version*, *streams*)

Bases: object

Camera device base class which is called via the `Device()` factory. It exposes the main functions from `librealsense`.

apply_ivcam_preset (*preset*)

Provide access to several recommend sets of option presets for ivcam.

Parameters `preset` (*int*) – preset from (`pyrealsense.constants.rs_ivcam_preset`)

deproject_pixel_to_point (*pixel, depth*)

Deproject a 2d pixel to its 3d point coordinate by calling rsutil's `rs_deproject_pixel_to_point` under the hood.

Parameters

- **pixel** (*np.array*) – (x,y) coordinate of the point
- **depth** (*float*) – depth at that pixel

Returns (x,y,z) coordinate of the point

Return type point (np.array)

get_available_options ()

Returns available options as a list of (DeviceOptionRange, value).

get_device_extrinsics (*from_stream, to_stream*)

Retrieve extrinsic transformation between the viewpoints of two different streams.

Parameters

- **from_stream** (`pyrealsense.constants.rs_stream`) – from stream.
- **to_stream** (`pyrealsense.constants.rs_stream`) – to stream.

Returns extrinsics parameters as a structure

Return type (`pyrealsense.extstruct.rs_extrinsics`)

get_device_modes ()

Returns a generator that yields all possible streaming modes as StreamMode.

get_device_option (*option*)

Get device option.

Parameters **option** (*int*) – taken from `pyrealsense.constants.rs_option`.

Returns option value.

Return type (double)

get_device_option_description (*option*)

Get the device option description.

Parameters **option** (*int*) – taken from `pyrealsense.constants.rs_option`.

Returns option value.

Return type (str)

get_device_option_range_ex (*option*)

Get device option range.

Parameters **option** (*int*) – taken from `pyrealsense.constants.rs_option`.

Returns option range.

Return type (DeviceOptionRange)

get_device_options (*options*)

Get device options.

Parameters **option** (list of int) – taken from `pyrealsense.constants.rs_option`.

Returns options values.

Return type (iter of double)

get_frame_number (*stream*)

Retrieve the frame number for specific stream.

Parameters **stream** (*int*) – value from `pyrealsense.constants.rs_stream`.

Returns frame number.

Return type (double)

get_frame_timestamp (*stream*)

Retrieve the time at which the latest frame on a specific stream was captured.

Parameters **stream** (*int*) – stream id

Returns timestamp

Return type (long)

is_streaming ()

Indicates if device is streaming.

Returns return value of `lrs.rs_is_device_streaming`.

Return type (bool)

poll_for_frame ()

Check if new frames are available, without blocking.

Returns 1 if new frames are available, 0 if no new frames have arrived

Return type int

Raises `utils.RealsenseError` – in case librealsense reports a problem.

project_point_to_pixel (*point*)

Project a 3d point to its 2d pixel coordinate by calling `rsutil's rs_project_point_to_pixel` under the hood.

Parameters **point** (*np.array*) – (x,y,z) coordinate of the point

Returns (x,y) coordinate of the pixel

Return type pixel (*np.array*)

reset_device_options_to_default (*options*)

Reset device options to default.

Parameters **option** (list of int) – taken from `pyrealsense.constants.rs_option`.

set_device_option (*option, value*)

Set device option.

Parameters

- **option** (*int*) – taken from `pyrealsense.constants.rs_option`.
- **value** (*double*) – value to be set for the option.

set_device_options (*options, values*)

Set device options.

Parameters

- **option** (list of int) – taken from `pyrealsense.constants.rs_option`.

- **values** (list of double) – options values.

stop()

End data acquisition. :raises: `utils.RealsenseError` – in case librealsense reports a problem.

wait_for_frames()

Block until new frames are available.

Raises `utils.RealsenseError` – in case librealsense reports a problem.

class `pyrealsense.core.Service`

Bases: `object`

Context manager for librealsense service.

Device (*args, **kwargs)

Factory function which returns a `Device`, also accepts optionnal arguments.

get_device_modes (device_id)

Generates all different modes for the device which *id* is provided.

Parameters `device_id` (*int*) – the device id as hinted by the output from `start()` or `get_devices()`.

Returns: generator that yields all possible streaming modes as `StreamMode`.

get_devices ()

Returns a generator that yields a dictionary containing 'id', 'name', 'serial', 'firmware' and 'is_streaming' keys.

is_device_streaming (device_id)

Indicates if device is streaming.

Utility function which does not require to enumerate all devices or to initialize a `Device` object.

start ()

Start librealsense service.

stop ()

Stop librealsense service.

pyrealsense.stream module

class `pyrealsense.stream.CADStream` (*name='cad', width=640, height=480, fps=30, color_format='rgb'*)

Bases: `pyrealsense.stream.Stream`

CAD stream from device, with default parameters.

class `pyrealsense.stream.ColorStream` (*name='color', width=640, height=480, fps=30, color_format='rgb'*)

Bases: `pyrealsense.stream.Stream`

Color stream from device, with default parameters.

class `pyrealsense.stream.DACStream` (*name='dac', width=640, height=480, fps=30*)

Bases: `pyrealsense.stream.Stream`

DAC stream from device, with default parameters.

class `pyrealsense.stream.DepthStream` (*name='depth', width=640, height=480, fps=30*)

Bases: `pyrealsense.stream.Stream`

Depth stream from device, with default parameters.

```
class pyrealsense.stream.InfraredStream(name='infrared', width=640, height=480, fps=30)
    Bases: pyrealsense.stream.Stream
```

Infrared stream from device, with default parameters.

```
class pyrealsense.stream.PointStream(name='points', width=640, height=480, fps=30)
    Bases: pyrealsense.stream.Stream
```

Point stream from device, with default parameters.

```
class pyrealsense.stream.Stream(name, native, stream, width, height, format, fps)
    Bases: object
```

Stream object that stores all necessary information for interaction with librealsense. See for possible combinations.

Parameters

- **name** (*str*) – name of stream which will be used to create a @property on `pyrealsense.core.DeviceBase`.
- **native** (*bool*) – whether the stream is native or composite
- **stream** (*int*) – from `pyrealsense.constants.rs_stream`
- **width** (*int*) – width
- **height** (*int*) – height
- **format** (*int*) – from `pyrealsense.constants.rs_format`
- **fps** (*int*) – fps

pyrealsense.offline module

pyrealsense.extlib module

This module loads rsutilwrapper and librealsense library.

pyrealsense.extstruct module

This module manually wraps structures defined in rs.h.

```
class pyrealsense.extstruct.rs_context
    Bases: _ctypes.Structure
```

This is a placeholder for the context. It is only defined to hold a reference to a pointer.

```
class pyrealsense.extstruct.rs_device
    Bases: _ctypes.Structure
```

This is a placeholder for the context. It is only defined to hold a reference to a pointer.

```
class pyrealsense.extstruct.rs_error
    Bases: _ctypes.Structure
```

This is a 1-to-1 mapping to rs_error from librealsense.

The `_fields_` class variable is defined as follows:

- `message (c_char_p)`: error message
- `function (pointer(c_char))`: function which caused the error
- `args (c_char_p)`: arguments to the function which caused the error

class `pyrealsense.extstruct.rs_extrinsics`

Bases: `_ctypes.Structure`

This is a 1-to-1 mapping to `rs_extrinsics` from `librealsense`.

The `_fields_` class variable is defined as follows:

- `rotation (c_float*9)`: column-major 3x3 rotation matrix
- `height (c_float*3)`: 3 element translation vector, in meters

class `pyrealsense.extstruct.rs_intrinsics`

Bases: `_ctypes.Structure`

This is a 1-to-1 mapping to `rs_intrinsics` from `librealsense`.

The `_fields_` class variable is defined as follows:

- `width (c_int)`: width of the image in pixels
- `height (c_int)`: height of the image in pixels
- `ppx (c_float)`: horizontal coordinate of the principal point of the image, as a pixel offset from the left edge
- `ppy (c_float)`: vertical coordinate of the principal point of the image, as a pixel offset from the top edge
- `fx (c_float)`: focal length of the image plane, as a multiple of pixel width
- `fy (c_float)`: focal length of the image plane, as a multiple of pixel height
- `model (c_int)`: distortion model of the image
- `coeffs (c_float*5)`: distortion coefficients

pyrealsense.utils module

This module creates utility classes to objects that do not exist in RS API, as well as a wrapper for RS error and its pretty printing.

class `pyrealsense.utils.DeviceOptionRange` (*option, min, max, step, default*)

Bases: `tuple`

default

Alias for field number 4

max

Alias for field number 2

min

Alias for field number 1

option

Alias for field number 0

step

Alias for field number 3

exception `pyrealsense.utils.RealsenseError` (*function, args, message*)

Bases: `exceptions.Exception`

Error thrown during the processing in case the processing chain needs to be exited. Will printout the error message as received from librealSense.

class `pyrealsense.utils.StreamMode` (*stream, width, height, format, fps*)

Bases: `tuple`

format

Alias for field number 3

fps

Alias for field number 4

height

Alias for field number 2

stream

Alias for field number 0

width

Alias for field number 1

`pyrealsense.utils.pp` (*fun, *args*)

Wrapper for printing char pointer from ctypes.

pyrealsense.constants module

This module extract the RS_API_VERSION to which pyrealsense is binded and wraps several enums from rs.h into classes with the same name.

class `pyrealsense.constants.rs_capabilities`

Bases: `object`

RS_CAPABILITIES_ADAPTER_BOARD = 7

RS_CAPABILITIES_COLOR = 1

RS_CAPABILITIES_COUNT = 9

RS_CAPABILITIES_DEPTH = 0

RS_CAPABILITIES_ENUMERATION = 8

RS_CAPABILITIES_FISH_EYE = 4

RS_CAPABILITIES_INFRARED = 2

RS_CAPABILITIES_INFRARED2 = 3

RS_CAPABILITIES_MOTION_EVENTS = 5

RS_CAPABILITIES_MOTION_MODULE_FW_UPDATE = 6

name_for_value = {0: 'RS_CAPABILITIES_DEPTH', 1: 'RS_CAPABILITIES_COLOR', 2: 'RS_CAPABILITIES_DEPTH', 3: 'RS_CAPABILITIES_INFRARED2', 4: 'RS_CAPABILITIES_FISH_EYE', 5: 'RS_CAPABILITIES_MOTION_EVENTS', 6: 'RS_CAPABILITIES_MOTION_MODULE_FW_UPDATE', 7: 'RS_CAPABILITIES_ADAPTER_BOARD', 8: 'RS_CAPABILITIES_ENUMERATION', 9: 'RS_CAPABILITIES_COUNT'}

class `pyrealsense.constants.rs_distortion`

Bases: `object`

RS_DISTORTION_COUNT = 4

RS_DISTORTION_FTHETA = 3

```
RS_DISTORTION_INVERSE_BROWN_CONRADY = 2
RS_DISTORTION_MODIFIED_BROWN_CONRADY = 1
RS_DISTORTION_NONE = 0
name_for_value = {0: 'RS_DISTORTION_NONE', 1: 'RS_DISTORTION_MODIFIED_BROWN_CONRADY', 2: 'RS_DISTORTION_INVERSE_BROWN_CONRADY'}

class pyrealsense.constants.rs_format
    Bases: object
    RS_FORMAT_ANY = 0
    RS_FORMAT_BGR8 = 6
    RS_FORMAT_BGRA8 = 8
    RS_FORMAT_COUNT = 14
    RS_FORMAT_DISPARITY16 = 2
    RS_FORMAT_RAW10 = 11
    RS_FORMAT_RAW16 = 12
    RS_FORMAT_RAW8 = 13
    RS_FORMAT_RGB8 = 5
    RS_FORMAT_RGBA8 = 7
    RS_FORMAT_XYZ32F = 3
    RS_FORMAT_Y16 = 10
    RS_FORMAT_Y8 = 9
    RS_FORMAT_YUYV = 4
    RS_FORMAT_Z16 = 1
    name_for_value = {0: 'RS_FORMAT_ANY', 1: 'RS_FORMAT_Z16', 2: 'RS_FORMAT_DISPARITY16', 3: 'RS_FORMAT_XYZ32F', 4: 'RS_FORMAT_YUYV', 5: 'RS_FORMAT_RGB8', 6: 'RS_FORMAT_BGR8', 7: 'RS_FORMAT_RGBA8', 8: 'RS_FORMAT_BGRA8', 9: 'RS_FORMAT_Y8', 10: 'RS_FORMAT_Y16', 11: 'RS_FORMAT_RAW10', 12: 'RS_FORMAT_RAW16', 13: 'RS_FORMAT_RAW8', 14: 'RS_FORMAT_COUNT'}

class pyrealsense.constants.rs_ivcam_preset
    Bases: object
    RS_IVCAM_PRESET_BACKGROUND_SEGMENTATION = 2
    RS_IVCAM_PRESET_COUNT = 11
    RS_IVCAM_PRESET_DEFAULT = 8
    RS_IVCAM_PRESET_FACE_ANALYTICS = 5
    RS_IVCAM_PRESET_FACE_LOGIN = 6
    RS_IVCAM_PRESET_GESTURE_RECOGNITION = 3
    RS_IVCAM_PRESET_GR_CURSOR = 7
    RS_IVCAM_PRESET_IR_ONLY = 10
    RS_IVCAM_PRESET_LONG_RANGE = 1
    RS_IVCAM_PRESET_MID_RANGE = 9
    RS_IVCAM_PRESET_OBJECT_SCANNING = 4
    RS_IVCAM_PRESET_SHORT_RANGE = 0
    name_for_value = {0: 'RS_IVCAM_PRESET_SHORT_RANGE', 1: 'RS_IVCAM_PRESET_LONG_RANGE', 2: 'RS_IVCAM_PRESET_MID_RANGE', 3: 'RS_IVCAM_PRESET_GESTURE_RECOGNITION', 4: 'RS_IVCAM_PRESET_OBJECT_SCANNING', 5: 'RS_IVCAM_PRESET_FACE_ANALYTICS', 6: 'RS_IVCAM_PRESET_FACE_LOGIN', 7: 'RS_IVCAM_PRESET_GR_CURSOR', 8: 'RS_IVCAM_PRESET_DEFAULT', 9: 'RS_IVCAM_PRESET_MID_RANGE', 10: 'RS_IVCAM_PRESET_IR_ONLY', 11: 'RS_IVCAM_PRESET_COUNT', 12: 'RS_IVCAM_PRESET_BACKGROUND_SEGMENTATION'}
```



```

class pyrealsense.constants.rs_option
    Bases: object

    RS_OPTION_COLOR_BACKLIGHT_COMPENSATION = 0
    RS_OPTION_COLOR_BRIGHTNESS = 1
    RS_OPTION_COLOR_CONTRAST = 2
    RS_OPTION_COLOR_ENABLE_AUTO_EXPOSURE = 10
    RS_OPTION_COLOR_ENABLE_AUTO_WHITE_BALANCE = 11
    RS_OPTION_COLOR_EXPOSURE = 3
    RS_OPTION_COLOR_GAIN = 4
    RS_OPTION_COLOR_GAMMA = 5
    RS_OPTION_COLOR_HUE = 6
    RS_OPTION_COLOR_SATURATION = 7
    RS_OPTION_COLOR_SHARPNESS = 8
    RS_OPTION_COLOR_WHITE_BALANCE = 9
    RS_OPTION_COUNT = 68
    RS_OPTION_F200_ACCURACY = 13
    RS_OPTION_F200_CONFIDENCE_THRESHOLD = 16
    RS_OPTION_F200_DYNAMIC_FPS = 17
    RS_OPTION_F200_FILTER_OPTION = 15
    RS_OPTION_F200_LASER_POWER = 12
    RS_OPTION_F200_MOTION_RANGE = 14
    RS_OPTION_FISHEYE_AUTO_EXPOSURE_ANTIFLICKER_RATE = 62
    RS_OPTION_FISHEYE_AUTO_EXPOSURE_MODE = 61
    RS_OPTION_FISHEYE_AUTO_EXPOSURE_PIXEL_SAMPLE_RATE = 63
    RS_OPTION_FISHEYE_AUTO_EXPOSURE_SKIP_FRAMES = 64
    RS_OPTION_FISHEYE_ENABLE_AUTO_EXPOSURE = 60
    RS_OPTION_FISHEYE_EXPOSURE = 56
    RS_OPTION_FISHEYE_EXTERNAL_TRIGGER = 59
    RS_OPTION_FISHEYE_GAIN = 57
    RS_OPTION_FISHEYE_STROBE = 58
    RS_OPTION_FRAMES_QUEUE_SIZE = 65
    RS_OPTION_HARDWARE_LOGGER_ENABLED = 66
    RS_OPTION_R200_AUTO_EXPOSURE_BOTTOM_EDGE = 43
    RS_OPTION_R200_AUTO_EXPOSURE_BRIGHT_RATIO_SET_POINT = 38
    RS_OPTION_R200_AUTO_EXPOSURE_KP_DARK_THRESHOLD = 41
    RS_OPTION_R200_AUTO_EXPOSURE_KP_EXPOSURE = 40

```

```
RS_OPTION_R200_AUTO_EXPOSURE_KP_GAIN = 39
RS_OPTION_R200_AUTO_EXPOSURE_LEFT_EDGE = 44
RS_OPTION_R200_AUTO_EXPOSURE_MEAN_INTENSITY_SET_POINT = 37
RS_OPTION_R200_AUTO_EXPOSURE_RIGHT_EDGE = 45
RS_OPTION_R200_AUTO_EXPOSURE_TOP_EDGE = 42
RS_OPTION_R200_DEPTH_CLAMP_MAX = 34
RS_OPTION_R200_DEPTH_CLAMP_MIN = 33
RS_OPTION_R200_DEPTH_CONTROL_ESTIMATE_MEDIAN_DECREMENT = 46
RS_OPTION_R200_DEPTH_CONTROL_ESTIMATE_MEDIAN_INCREMENT = 47
RS_OPTION_R200_DEPTH_CONTROL_LR_THRESHOLD = 55
RS_OPTION_R200_DEPTH_CONTROL_MEDIAN_THRESHOLD = 48
RS_OPTION_R200_DEPTH_CONTROL_NEIGHBOR_THRESHOLD = 54
RS_OPTION_R200_DEPTH_CONTROL_SCORE_MAXIMUM_THRESHOLD = 50
RS_OPTION_R200_DEPTH_CONTROL_SCORE_MINIMUM_THRESHOLD = 49
RS_OPTION_R200_DEPTH_CONTROL_SECOND_PEAK_THRESHOLD = 53
RS_OPTION_R200_DEPTH_CONTROL_TEXTURE_COUNT_THRESHOLD = 51
RS_OPTION_R200_DEPTH_CONTROL_TEXTURE_DIFFERENCE_THRESHOLD = 52
RS_OPTION_R200_DEPTH_UNITS = 32
RS_OPTION_R200_DISPARITY_MULTIPLIER = 35
RS_OPTION_R200_DISPARITY_SHIFT = 36
RS_OPTION_R200_EMITTER_ENABLED = 31
RS_OPTION_R200_LR_AUTO_EXPOSURE_ENABLED = 28
RS_OPTION_R200_LR_EXPOSURE = 30
RS_OPTION_R200_LR_GAIN = 29
RS_OPTION_SR300_AUTO_RANGE_ENABLE_LASER = 19
RS_OPTION_SR300_AUTO_RANGE_ENABLE_MOTION_VERSUS_RANGE = 18
RS_OPTION_SR300_AUTO_RANGE_LOWER_THRESHOLD = 27
RS_OPTION_SR300_AUTO_RANGE_MAX_LASER = 24
RS_OPTION_SR300_AUTO_RANGE_MAX_MOTION_VERSUS_RANGE = 21
RS_OPTION_SR300_AUTO_RANGE_MIN_LASER = 23
RS_OPTION_SR300_AUTO_RANGE_MIN_MOTION_VERSUS_RANGE = 20
RS_OPTION_SR300_AUTO_RANGE_START_LASER = 25
RS_OPTION_SR300_AUTO_RANGE_START_MOTION_VERSUS_RANGE = 22
RS_OPTION_SR300_AUTO_RANGE_UPPER_THRESHOLD = 26
RS_OPTION_TOTAL_FRAME_DROPS = 67
name_for_value = {0: 'RS_OPTION_COLOR_BACKLIGHT_COMPENSATION', 1: 'RS_OPTION_COLOR_BRIG
```

```
class pyrealsense.constants.rs_stream
    Bases: object

    RS_STREAM_COLOR = 1
    RS_STREAM_COLOR_ALIGNED_TO_DEPTH = 7
    RS_STREAM_COUNT = 12
    RS_STREAM_DEPTH = 0
    RS_STREAM_DEPTH_ALIGNED_TO_COLOR = 9
    RS_STREAM_DEPTH_ALIGNED_TO_INFRARED2 = 11
    RS_STREAM_DEPTH_ALIGNED_TO_RECTIFIED_COLOR = 10
    RS_STREAM_FISHEYE = 4
    RS_STREAM_INFRARED = 2
    RS_STREAM_INFRARED2 = 3
    RS_STREAM_INFRARED2_ALIGNED_TO_DEPTH = 8
    RS_STREAM_POINTS = 5
    RS_STREAM_RECTIFIED_COLOR = 6
    name_for_value = {0: 'RS_STREAM_DEPTH', 1: 'RS_STREAM_COLOR', 2: 'RS_STREAM_INFRARED', 3: 'RS'
```


with Matplotlib

```
import logging
logging.basicConfig(level=logging.INFO)

import matplotlib.pyplot as plt

import pyrealsense as pyrs

with pyrs.Service()
    dev = pyrs.Device()

    dev.wait_for_frame()
    plt.imshow(dev.colour)
    plt.show()
```

with OpenCV

```
import logging
logging.basicConfig(level=logging.INFO)

import time
import numpy as np
import cv2
import pyrealsense as pyrs

with pyrs.Service() as serv:
    with serv.Device() as dev:

        dev.apply_ivcam_preset(0)
```

```
cnt = 0
last = time.time()
smoothing = 0.9
fps_smooth = 30

while True:

    cnt += 1
    if (cnt % 10) == 0:
        now = time.time()
        dt = now - last
        fps = 10/dt
        fps_smooth = (fps_smooth * smoothing) + (fps * (1.0-smoothing))
        last = now

    dev.wait_for_frames()
    c = dev.color
    c = cv2.cvtColor(c, cv2.COLOR_RGB2BGR)
    d = dev.depth * dev.depth_scale * 1000
    d = cv2.applyColorMap(d.astype(np.uint8), cv2.COLORMAP_RAINBOW)

    cd = np.concatenate((c, d), axis=1)

    cv2.putText(cd, str(fps_smooth)[:4], (0, 50), cv2.FONT_HERSHEY_SIMPLEX, 2,
    ↪ (0, 0, 0))

    cv2.imshow('', cd)
    if cv2.waitKey(1) & 0xFF == ord('q'):
        break
```

with VTK

```
import time
import threading

import numpy as np

import vtk
import vtk.util.numpy_support as vtk_np

import pyrealsense as pyrs
serv = pyrs.Service()
serv.start()
cam = serv.Device()

class VTKActorWrapper(object):
    def __init__(self, nparray):
        super(VTKActorWrapper, self).__init__()

        self.nparray = nparray

        nCoords = nparray.shape[0]
```

```

nElem = nparray.shape[1]

self.verts = vtk.vtkPoints()
self.cells = vtk.vtkCellArray()
self.scalars = None

self.pd = vtk.vtkPolyData()
self.verts.SetData(vtk_np.numpy_to_vtk(nparray))
self.cells_npy = np.vstack([np.ones(nCoords, dtype=np.int64),
                             np.arange(nCoords, dtype=np.int64)]).T.flatten()
self.cells.SetCells(nCoords, vtk_np.numpy_to_vtkIdTypeArray(self.cells_npy))
self.pd.SetPoints(self.verts)
self.pd.SetVerts(self.cells)

self.mapper = vtk.vtkPolyDataMapper()
self.mapper.SetInputDataObject(self.pd)

self.actor = vtk.vtkActor()
self.actor.SetMapper(self.mapper)
self.actor.GetProperty().SetRepresentationToPoints()
self.actor.GetProperty().SetColor(0.0, 1.0, 0.0)

def update(self, threadLock, update_on):
    thread = threading.Thread(target=self.update_actor, args=(threadLock, update_
↪on))
    thread.start()

def update_actor(self, threadLock, update_on):
    while (update_on.is_set()):
        time.sleep(0.01)
        threadLock.acquire()
        cam.wait_for_frames()
        self.nparray[:] = cam.points.reshape(-1, 3)
        self.pd.Modified()
        threadLock.release()

class VTKVisualisation(object):
    def __init__(self, threadLock, actorWrapper, axis=True,):
        super(VTKVisualisation, self).__init__()

        self.threadLock = threadLock

        self.ren = vtk.vtkRenderer()
        self.ren.AddActor(actorWrapper.actor)

        self.axesActor = vtk.vtkAxesActor()
        self.axesActor.AxisLabelsOff()
        self.axesActor.SetTotalLength(1, 1, 1)
        self.ren.AddActor(self.axesActor)

        self.renWin = vtk.vtkRenderWindow()
        self.renWin.AddRenderer(self.ren)

        ## IREN
        self.iren = vtk.vtkRenderWindowInteractor()
        self.iren.SetRenderWindow(self.renWin)
        self.iren.Initialize()

```

```
self.style = vtk.vtkInteractorStyleTrackballCamera()
self.iren.SetInteractorStyle(self.style)

self.iren.AddObserver("TimerEvent", self.update_visualisation)
dt = 30 # ms
timer_id = self.iren.CreateRepeatingTimer(dt)

def update_visualisation(self, obj=None, event=None):
    time.sleep(0.01)
    self.threadLock.acquire()
    self.ren.GetRenderWindow().Render()
    self.threadLock.release()

def main():
    update_on = threading.Event()
    update_on.set()

    threadLock = threading.Lock()

    cam.wait_for_frames()
    pc = cam.points.reshape(-1, 3)
    actorWrapper = VTKActorWrapper(pc)
    actorWrapper.update(threadLock, update_on)

    viz = VTKVisualisation(threadLock, actorWrapper)
    viz.iren.Start()
    update_on.clear()

main()
cam.stop()
serv.stop()
```

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