

# Vzense Nebula SDK

## User Guide

Linux

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Vzense Technology, Inc.

# About This Document

This guide is mainly to introduce how to use Vzense TOF Camera and the Nebula SDK.

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# 1 Overview

Vzense TOF Camera is a series of 3D camera modules developed by Vzense which uses TOF (Time of Flight) technology. It has the advantages of high precision, strong environmental adaptability, small size and so on.

Nebula SDK is a software development kit based on Vzense products, which is currently available for Windows, Linux, ARM Linux operating systems, provide friendly APIs and application examples for developer.

High precision depth image data, gray image data and point cloud data can be got using the SDK. It is convenient to develop gesture recognition, projection touch, face recognition, fatigue detection, 3D modeling, navigation, obstacle avoidance and so on.

The SDK download link:

<https://github.com/Vzense/NebulaSDK>

<https://gitee.com/Vzense/NebulaSDK>

## 2 Products

Nebula SDK currently supports products like:

- DS77 Lite/Pro
- DS77C Lite/Pro

### 2.1 DS77 Lite/Pro



Model	DS77 Lite	DS77 Pro
Sensor	SONY DepthSense ToF	
Laser	940nm VCSEL * 2	
TOF Resolution	640 * 480, Max. 25fps	
TOF FOV	70°(H) * 50°(V)	
Pixel Format	12bit Depth, 8bit IR	
Digital Interface	1000M Ethernet, RS485	
Power Supply	12V ~ 24V DC	12V ~ 24V DC or POE+
Accuracy	< 1% (4mm@1m)	
Detect Range	0.15m ~ 5m	
Operating Temperature	-20℃ ~ 50℃	
OS Support	Windows, Linux, Arm Linux	
Software Support	Nebula SDK, C++, C, Python	
Ingress Protection	IP42	IP67

## 2.2 DS77C Lite/Pro



Model	DS77C Lite	DS77C Pro
Sensor	SONY DepthSense ToF + RGB	
Laser	940nm VCSEL * 2	
TOF Resolution	640 * 480, Max. 25fps	
RGB Resolution	1600*1200, Max. 25fps	
TOF FOV	70°(H) * 50°(V)	
RGB FOV	77°(H) * 55°(V)	
Pixel Format	12bit Depth, 8bit IR, MJPEG RGB	
Digital Interface	1000M Ethernet, RS485	
Power Supply	12V ~ 24V DC	12V ~ 24V DC or POE+
Accuracy	< 1% (4mm@1m)	
Detect Range	0.15m ~ 5m	
Operating Temperature	-20℃ ~ 50℃	
OS Support	Windows, Linux, Arm Linux	
Software Support	Nebula SDK, C++, C, Python	
Ingress Protection	IP42	IP67

## 3 Installation

### 3.1 Recommended Operation System

Item	Recommended Configuration
Operation System	Ubuntu 20.04 64bit
	Ubuntu 18.04 64bit
	ARM Linux(AArch64)

### 3.2 Device Installation

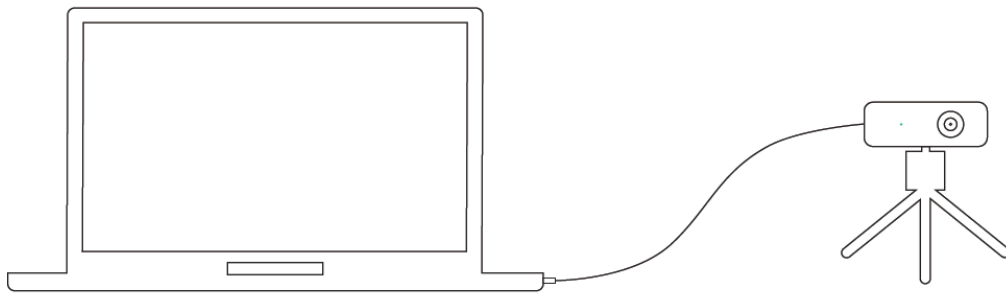


Figure 3.1 Device Installation

Vzense cameras support two connection method: static IP address and DHCP. Static IP address is the default mode of Vzense devices. The IP address, subnet mask and DHCP enable also can be changed with [NebulaGUITool](#).

#### 3.2.1 Static Address

Using static address connection method device can be connected to computer directly, or with one network switch repeat. But please ensure the camera and computer are resided on the same network segment.

For example, the direct connection: one end of the cable is connected to the camera, and the other end is plugged into RJ45 port of the PC. The default IP address of Vzense camera is 192.168.1.101, so the address of the PC can be set to 192.168.1.100. In Ubuntu system, the below picture can be referenced to set the network up.

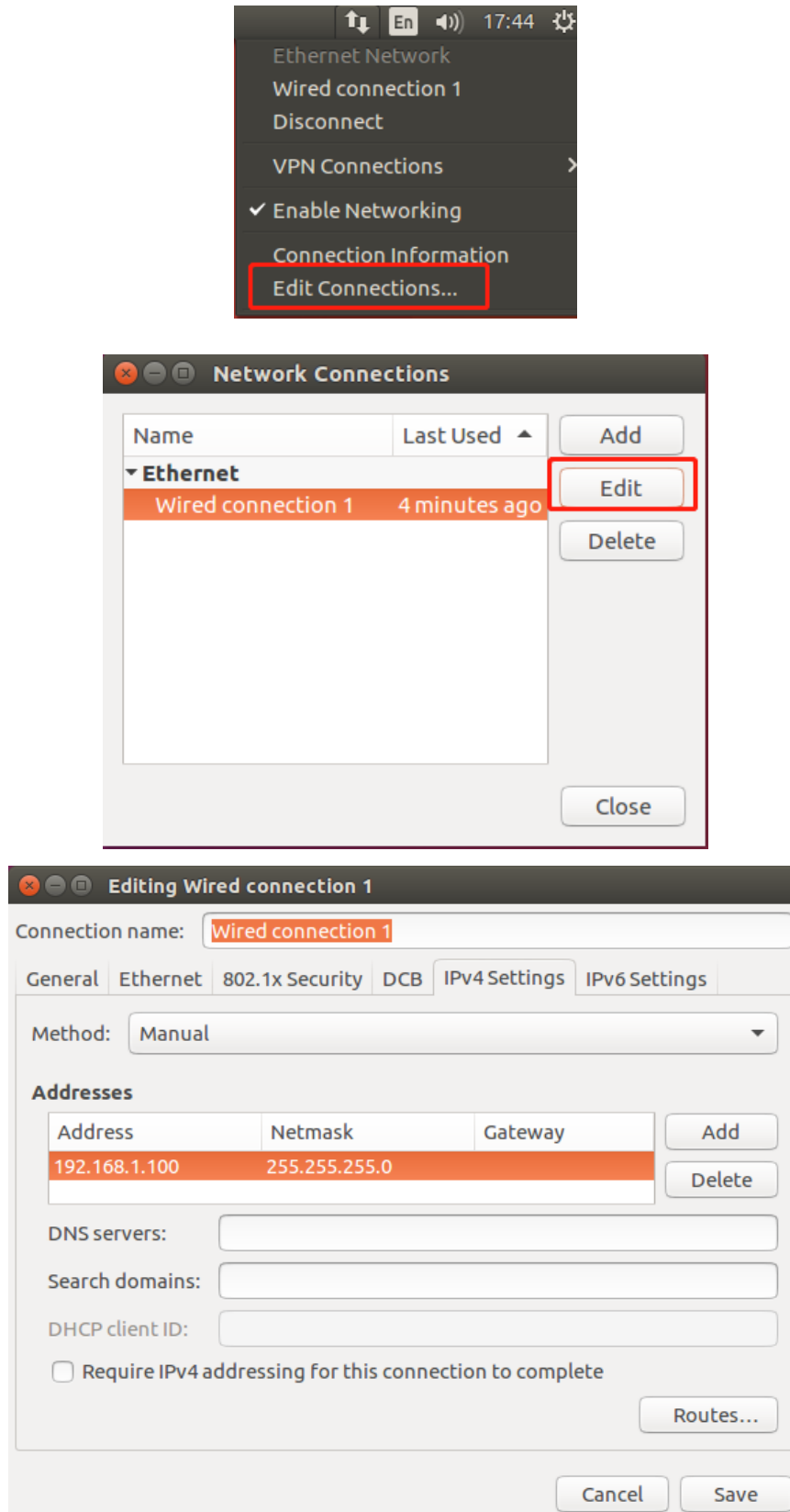


Figure 3.1 Static IP Address Configuration

### 3.2.2 DHCP

Using DHCP connection mode the Vzense camera and PC need be set to 'DHCP' mode, then connect them to one same LAN that have router. For details on how to set the camera to DHCP connection mode, refer to the [NebulaGUITool](#) documentation. Setting the 'local connection' of the PC to obtain the IP address automatically is the recommended method.

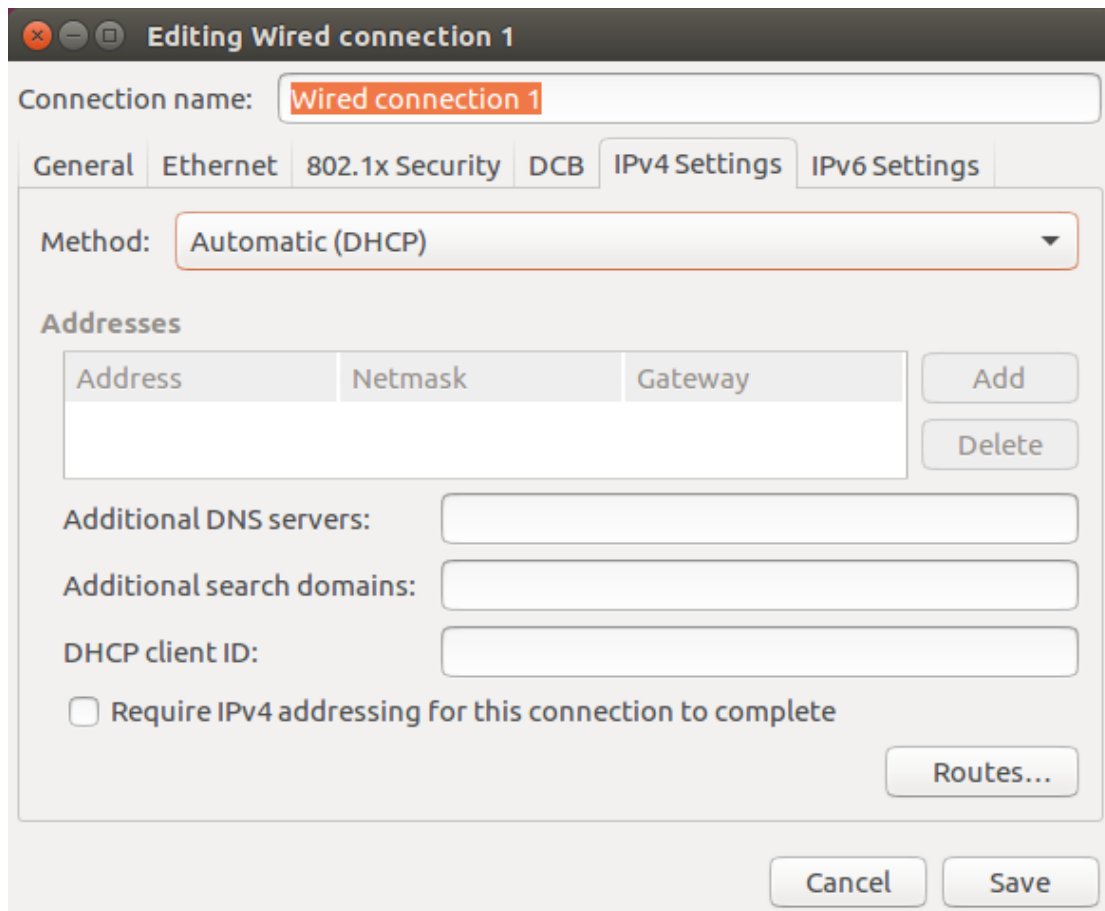


Figure 3.2 DHCP

Note: The network card, router or switch all of these have to meet the requirements of 1000Mbps Ethernet.

## 4 Nebula SDK Instruction

### 4.1 Nebula SDK Structure

In Vzense Nebula SDK, there are several directories: Document, Include, Lib, PrecompiledSamples, Samples.

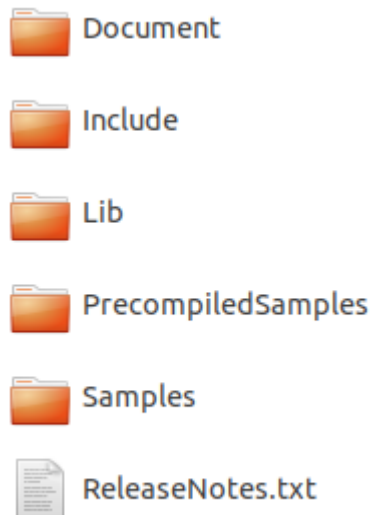


Figure 4.1 Linux SDK directory

- Document contains documents of Nebula SDK.
- Include contains header files of Nebula SDK
- Lib contains the dynamic library files of the Nebula SDK
- PrecompiledSamples contain several prebuild samples that can be executed directly for depth, IR and color images previewing.
- Samples contains several example codes. The examples have two different parts: Base and OpenCV. Base part is the basic APIs using example. And the other part is used to demonstrate how to use third-party library like OpenCV. In the OpenCV sample depth image, IR image and color image can be previewed using imshow method. All of the example use CMake as build tool.

## 4.2 Development Guidelines

### 4.2.1 Project Configuration

Developing new projects with Nebula SDK need configure the Include and Lib path in the CMakeList.txt. For details, please refer the CMake example in samples.

### 4.2.2 API Invoke Flow

The API of Nebula SDK invoking flow chat like below:

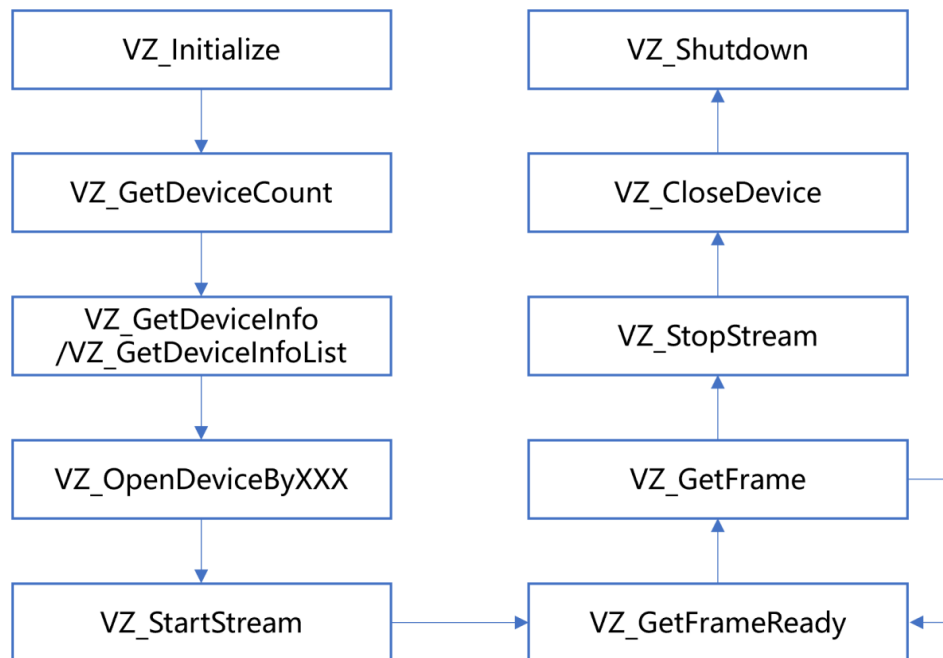


Figure 4.2 SDK APIs Invoke Flow Chat

#### 1. VZ\_Initialize and VZ\_Shutdown

VZ\_Initialize: initialize the SDK

VZShutdown: deinitialize the SDK, and destroy all of the resources.

#### 2. VZ\_GetDeviceCount and VZ\_GetDeviceInfoList/VZ\_GetDeviceInfo

VZ\_GetDeviceCount: get the number of connected devices.



VZ\_GetDeviceInfoList/VZ\_GetDeviceInfo: get the information of connected devices.

### **3. VZ\_OpenDeviceByXXX and VZ\_CloseDevice**

VZ\_OpenDeviceByXXX: open the specified device, the interface can support using URI, IP Address and alias.

VZ\_CloseDevice: close the specified device.

### **4. VZ\_StartStream and VZ\_StopStream**

VZ\_StartStream: start streaming of the specified device.

VZ\_StopStream: stop streaming of the specified device.

### **5. VZ\_GetFrameReady and VZ\_GetFrame**

In the main loop of capture, VZ\_GetFrameReady is called first to check the frames, then call VZ\_GetFrame to obtain the frame image data of the specified image type.

### **6. Set and Get**

The SDK provides Set and Get interface for writing and reading properties, parameters of device, as detailed in Section 5.3.

## **4.3 SDK Sample**

Nebula software development kit provide several sample codes for API interface using demonstration in the Samples folder of the SDK. The following directories are currently available:

- Base: the basic APIs using example
- OpenCV: the example works with third-party library OpenCV

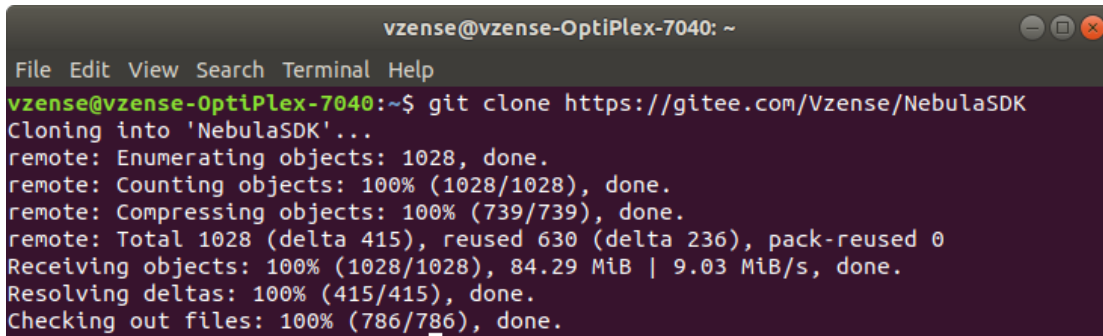
### **4.3.1 Base Samples**

The base sample is used to demonstrate the single feature of basic APIs. In order to help

developer familiar with SDK quickly, the examples are classified according to products, such as DS77, DS77C, etc. Open device, image acquisition, software/ hardware trigger, point cloud store are all included in the SDK example codes.

#### 1. Download Nebula SDK from GitHub/Gitee

> git clone https://github.com/Vzense/NebulaSDK



```

vzense@vzense-OptiPlex-7040: ~
File Edit View Search Terminal Help
vzense@vzense-OptiPlex-7040:~$ git clone https://gitee.com/Vzense/NebulaSDK
Cloning into 'NebulaSDK'...
remote: Enumerating objects: 1028, done.
remote: Counting objects: 100% (1028/1028), done.
remote: Compressing objects: 100% (739/739), done.
remote: Total 1028 (delta 415), reused 630 (delta 236), pack-reused 0
Receiving objects: 100% (1028/1028), 84.29 MiB | 9.03 MiB/s, done.
Resolving deltas: 100% (415/415), done.
Checking out files: 100% (786/786), done.

```

Figure 4.3 Download Nebula SDK

#### 2. Select the corresponding example according to the device. For example, the DeviceConnectByAlias example of DS77C

> cd NebulaSDK/Ubuntu18.04/Samples/Base/DS77C/

> mkdir build

> cd build/

> cmake ../

> make

```

-- The C compiler identification is GNU 7.5.0
-- The CXX compiler identification is GNU 7.5.0
-- Check for working C compiler: /usr/bin/cc
-- Check for working C compiler: /usr/bin/cc -- works
-- Detecting C compiler ABI info
-- Detecting C compiler ABI info - done
-- Detecting C compile features
-- Detecting C compile features - done
-- Check for working CXX compiler: /usr/bin/c++
-- Check for working CXX compiler: /usr/bin/c++ -- works
-- Detecting CXX compiler ABI info
-- Detecting CXX compiler ABI info - done
-- Detecting CXX compile features
-- Detecting CXX compile features - done
-- Configuring done
-- Generating done
-- Build files have been written to: /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/Samples/Base/DS77C/build

```

```

[ 161] Building CXX object DeviceConnectByIP/MakeFiles/DeviceConnectByIP.dir/DeviceConnectByIP.cpp.o
[ 204] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/DeviceConnectByIP
[ 204] Built target DeviceConnectByIP
Scanning dependencies of target DeviceSWTriggerMode
[ 234] Building CXX object DeviceSWTriggerMode/MakeFiles/DeviceSWTriggerMode.dir/DeviceSWTriggerMode.cpp.o
[ 264] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/DeviceSWTriggerMode
[ 264] Built target DeviceSWTriggerMode
Scanning dependencies of target DeviceInfoGet
[ 304] Building CXX object DeviceInfoGet/MakeFiles/DeviceInfoGet.dir/DeviceInfoGet.cpp.o
[ 334] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/DeviceInfoGet
[ 334] Built target DeviceInfoGet
Scanning dependencies of target DeviceParamGet
[ 364] Building CXX object DeviceParamGet/MakeFiles/DeviceParamGet.dir/DeviceParamGet.cpp.o
[ 404] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/DeviceParamGet
[ 404] Built target DeviceParamGet
Scanning dependencies of target DeviceSearchAndConnect
[ 434] Building CXX object DeviceSearchAndConnect/MakeFiles/DeviceSearchAndConnect.dir/DeviceSearchAndConnect.cpp.o
[ 464] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/DeviceSearchAndConnect
[ 464] Built target DeviceSearchAndConnect
Scanning dependencies of target DeviceStartStopSteaming
[ 504] Building CXX object DeviceStartStopSteaming/MakeFiles/DeviceStartStopSteaming.dir/DeviceStartStopSteaming.cpp.o
[ 534] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/DeviceStartStopSteaming
[ 534] Built target DeviceStartStopSteaming
Scanning dependencies of target DeviceSWTriggerMode
[ 564] Building CXX object DeviceSWTriggerMode/MakeFiles/DeviceSWTriggerMode.dir/DeviceSWTriggerMode.cpp.o
[ 604] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/DeviceSWTriggerMode
[ 604] Built target DeviceSWTriggerMode
Scanning dependencies of target FrameCaptureAndSave
[ 634] Building CXX object FrameCaptureAndSave/MakeFiles/FrameCaptureAndSave.dir/FrameCaptureAndSave.cpp.o
[ 664] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/FrameCaptureAndSave
[ 664] Built target FrameCaptureAndSave
Scanning dependencies of target MultiConnection
[ 704] Building CXX object MultiConnection/MakeFiles/MultiConnection.dir/MultiConnection.cpp.o
[ 734] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/MultiConnection
[ 734] Built target MultiConnection
Scanning dependencies of target PointCloudCaptureAndSave
[ 764] Building CXX object PointCloudCaptureAndSave/MakeFiles/PointCloudCaptureAndSave.dir/PointCloudCaptureAndSave.cpp.o
[ 804] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/PointCloudCaptureAndSave
[ 804] Built target PointCloudCaptureAndSave
Scanning dependencies of target RGBResolutionChange
[ 834] Building CXX object RGBResolutionChange/MakeFiles/RGBResolutionChange.dir/RGBResolutionChange.cpp.o
[ 864] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/RGBResolutionChange
[ 864] Built target RGBResolutionChange
Scanning dependencies of target TransformColorImgToDepthSensorFrame
[ 904] Building CXX object TransformColorImgToDepthSensorFrame/MakeFiles/TransformColorImgToDepthSensorFrame.dir/TransformColorImgToDepthSensorFrame.cpp.o
[ 934] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/TransformColorImgToDepthSensorFrame
[ 934] Built target TransformColorImgToDepthSensorFrame
Scanning dependencies of target TransformDepthImgToColorSensorFrame
[ 964] Building CXX object TransformDepthImgToColorSensorFrame/MakeFiles/TransformDepthImgToColorSensorFrame.dir/TransformDepthImgToColorSensorFrame.cpp.o
[ 1004] Linking CXX executable /home/peter/work/develop/sdk_release/NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/TransformDepthImgToColorSensorFrame
[ 1004] Built target TransformDepthImgToColorSensorFrame

```

Figure 4.4 Compilation

3. After compilation, the output path is PrecompiledSamples, into the directory and run it.

```
> cd NebulaSDK/Ubuntu18.04/PrecompiledSamples/DS77C_Samples/
```

```
> ./DeviceConnectByAlias
```

```

vzense@vzense-Inspiron-7580:~/work/gitee/DS-BaseSDK/Ubuntu18.04/
PrecompiledSamples/DS77C_Samples$ ./DeviceConnectByAlias
---DeviceConnectByAlias---
Get device count: 0
Get device count: 0
Get device count: 1
uri:DS77CLite:VDS7CLCJC7140040P
alias:VDS7CLCJC7140040P
ip:192.168.1.101
connectStatus:2

```

Figure 4.5 Execution

### 4.3.2 OpenCV Samples

The OpenCV samples show how to use Nebula SDK with third-party libraries. The example uses the image mapping function of OpenCV to display color depth image, IR

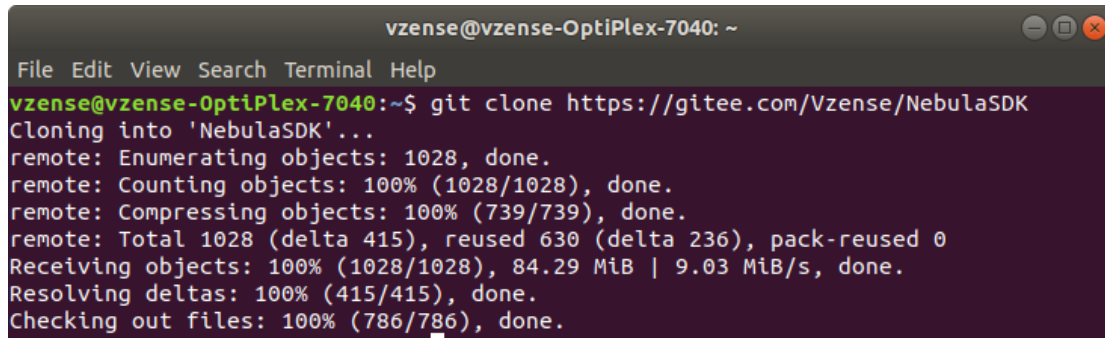
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image and color image.

### 1. Download Nebula SDK from GitHub/Gitee

> git clone https://github.com/Vzense/NebulaSDK



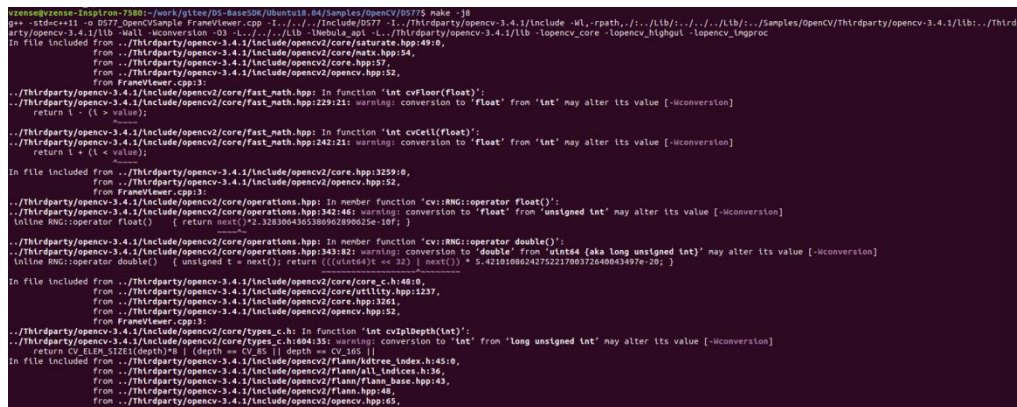
```
vzense@vzense-OptiPlex-7040: ~
File Edit View Search Terminal Help
vzense@vzense-OptiPlex-7040:~$ git clone https://gitee.com/Vzense/NebulaSDK
Cloning into 'NebulaSDK'...
remote: Enumerating objects: 1028, done.
remote: Counting objects: 100% (1028/1028), done.
remote: Compressing objects: 100% (739/739), done.
remote: Total 1028 (delta 415), reused 630 (delta 236), pack-reused 0
Receiving objects: 100% (1028/1028), 84.29 MiB | 9.03 MiB/s, done.
Resolving deltas: 100% (415/415), done.
Checking out files: 100% (786/786), done.
```

Figure 4.6 Download Nebula SDK

### 2. Select the corresponding example according to the device, for example DS77C

> cd NebulaSDK/Ubuntu18.04/Samples/OpenCV/DS77C

> make



```
vzense@vzense-Inspiron-7580: /work/gitee/05-BaseSDK/Ubuntu18.04/Samples/OpenCV/DS77C$ make -j8
g++ -std=c++11 -O 0577_OpenCVSample_Feature.cpp -I./../include/0577 -I../Thirdparty/opencv-3.4.1/include -Wl,-rpath,./lib -L./lib -L../Thirdparty/opencv-3.4.1/lib -lopencv_core -lopencv_highgui -lopencv_imgproc
In file included from ./Thirdparty/opencv-3.4.1/include/opencv2/core/saturate.hpp:54:
from ./Thirdparty/opencv-3.4.1/include/opencv2/core/math.hpp:54:
from ./Thirdparty/opencv-3.4.1/include/opencv2/core.hpp:57:
from ./Thirdparty/opencv-3.4.1/include/opencv2/opencv.hpp:52:
from ./Thirdparty/opencv-3.4.1/include/opencv2/core/fast_math.hpp: In function 'int cvFloor(float)':
return t - (t > value);
./Thirdparty/opencv-3.4.1/include/opencv2/core/fast_math.hpp:229:21: warning: conversion to 'float' from 'int' may alter its value [-Wconversion]
return t + (t < value);
./Thirdparty/opencv-3.4.1/include/opencv2/core/fast_math.hpp: In function 'int cvCeil(float)':
return t + (t < value);
./Thirdparty/opencv-3.4.1/include/opencv2/core/fast_math.hpp:242:21: warning: conversion to 'float' from 'int' may alter its value [-Wconversion]
return t - (t < value);
In file included from ./Thirdparty/opencv-3.4.1/include/opencv2/core.hpp:3259:0,
from ./Thirdparty/opencv-3.4.1/include/opencv2/opencv.hpp:52,
from ./Thirdparty/opencv-3.4.1/include/opencv2/core/operations.hpp: In member function 'cv::RNG::operator float()':
./Thirdparty/opencv-3.4.1/include/opencv2/core/operations.hpp:342:46: warning: conversion to 'float' from 'unsigned int' may alter its value [-Wconversion]
inline RNG::operator float() { return next(12539045353869628990525e-10f); }
./Thirdparty/opencv-3.4.1/include/opencv2/core/operations.hpp: In member function 'cv::RNG::operator double()':
./Thirdparty/opencv-3.4.1/include/opencv2/core/operations.hpp:343:82: warning: conversion to 'double' from 'uint64 (aka long unsigned int)' may alter its value [-Wconversion]
inline RNG::operator double() { unsigned t = next(); return (((uint64)t << 32) | next()) * 5.4210108624275221780372640043497e-20; }
In file included from ./Thirdparty/opencv-3.4.1/include/opencv2/core/core_c.h:48:0,
from ./Thirdparty/opencv-3.4.1/include/opencv2/core/utlility.hpp:1237,
from ./Thirdparty/opencv-3.4.1/include/opencv2/core.hpp:3261,
from ./Thirdparty/opencv-3.4.1/include/opencv2/opencv.hpp:52,
from ./Thirdparty/opencv-3.4.1/include/opencv2/core/types_c.h: In function 'int cvIpDepth(int)':
return CV_SDP_DEPTH(depth) & (depth == CV_8U ? 1 : depth == CV_16S ? 1 : 0);
In file included from ./Thirdparty/opencv-3.4.1/include/opencv2/flann/kdtree_index.h:45:0,
from ./Thirdparty/opencv-3.4.1/include/opencv2/flann/all_indices.h:36,
from ./Thirdparty/opencv-3.4.1/include/opencv2/flann/flann_base.hpp:43,
from ./Thirdparty/opencv-3.4.1/include/opencv2/flann.hpp:48,
from ./Thirdparty/opencv-3.4.1/include/opencv2/opencv.hpp:65,
from ./Thirdparty/opencv-3.4.1/include/opencv2/opencv.hpp:65,
```

Figure 4.7 Compilation

### 3. Run the compiled demo

> ./DS77C\_OpenCVSample

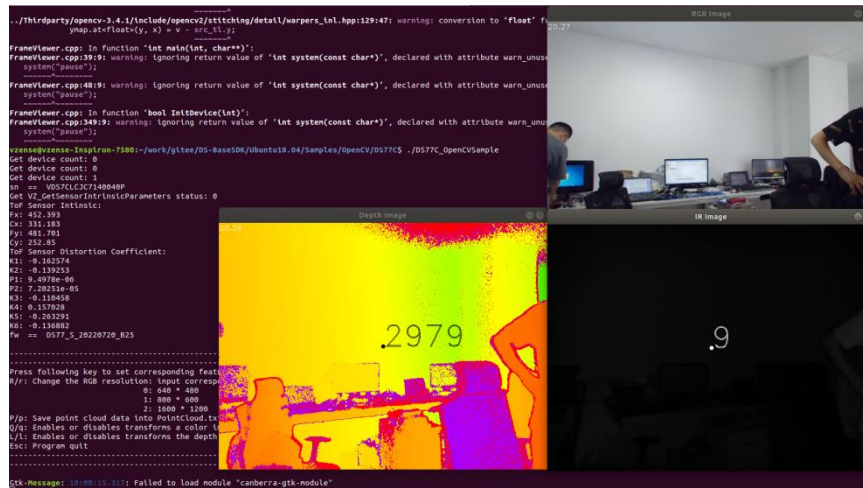


Figure 4.8 Execution

## 5 Nebula SDK API Introduction

### 5.1 Enum Type

#### 5.1.1 VzFrameType

**Description:**

Image type.

**PS:** The number of enumerated values may vary depending on the product model.

**Enumerator:**

VzDepthFrame: depth frame with 16 bits per pixel in millimeters

VzIRFrame: ir frame with 8 bits per pixel

VzColorFrame: color frame with 24 bits per pixel in RGB/BGR format

VzTransformColorImgToDepthSensorFrame: color frame with 24 bits per pixel in RGB/BGR format, that is transformed to depth sensor space where the resolution is the same as the depth frame's resolution. This frame type can be enabled `VZ_SetTransformColorImgToDepthSensorEnabled`.

VzTransformDepthImgToColorSensorFrame: depth frame with 16 bits per pixel, in millimeters, that is transformed to color sensor space where the resolution is same as the color frame's resolution. This frame type can be enabled using `VZ_SetTransformDepthImgToColorSensorEnabled`.

VzConfidenceFrame: Laser intensity image.

## 5.1.2 VzPixelFormat

### Description:

Pixel type of image data.

**PS:** The number of enumerated values may vary depending on the product model.

### Enumerator:

VzPixelFormatDepthMM16: Represents the 16-bit depth value of each pixel data in millimeters

VzPixelFormatGray8: Indicates the 8-bit grayscale value of each pixel

VzPixelFormatRGB888: Represents the 24-bit RGB value of each pixel data

VzPixelFormatBGR888: Represents the 24-bit BGR value of each pixel

## 5.1.3 VzSensorType

### Description:

Sensor Type

**PS:** The number of enumerated values may vary depending on the product model.

### Enumerator:

VzToFSensor: represents a depth image sensor

VzColorSensor: represents a color image sensor.

## 5.1.4 VzReturnStatus

### Description:

Returns of an interface function.

**PS:** The number of enumerated values may vary depending on the product model. For details, see Include

### Enumerator:

VzRetOK: indicates that the call is successful

VzRetNoDeviceConnected: indicates that no device is connected

VzRetInvalidDeviceIndex: indicates that the incoming device serial number is invalid

VzRetDevicePointerIsNull: indicates that the passed device pointer is null

VzRetInvalidFrameType: indicates that the incoming image type is invalid

VzRetFramePointerIsNull: indicates that the passed image pointer is null

VzRetNoPropertyValueGet: indicates that the current property value cannot be obtained

VzRetNoPropertyValueSet: indicates that the current property value cannot be set

VzRetPropertyPointerIsNull: said the incoming pointer to storage property value of the cache is empty

VzRetPropertySizeNotEnough: said the incoming cache space to store the value of an attribute

VzRetInvalidDepthRange: indicates that the passed depth range is invalid



VzRetGetFrameReadyTimeOut: access to images

VzRetInputPointerIsNull: indicates that the incoming pointer is null

VzRetCameraNotOpened: indicates that the camera is not opened

VzRetInvalidCameraType: indicates that the incoming camera type is invalid

VzRetInvalidParams: indicates that the passed parameters are invalid

VzRetCurrentVersionNotSupport: said the current version is not supported

VzRetUpgradelmError: indicates that the camera firmware upgrade fails

VzRetUpgradelmPathTooLong: said the incoming camera firmware path length is too long

VzRetUpgradeCallbackNotSet: said not set the camera to upgrade the callback function

VzRetNoAdapterConnected: indicates that the power adapter is not connected

VzRetReinitialized: indicates repeated initialization

VzRetNoInitalized: indicates that the initialization is not performed

VzRetCameraOpened: indicates that the camera is opened

VzRetCmdError: The command fails to be delivered

VzRetCmdSyncTimeOut: indicates that the command is successfully sent, but synchronization fails

VzRetIPNotMatch: indicates that the camera IP address and host IP address are on different network segments

VzRetNotStopStream: indicates that the data stream is not opened

VzRetOthers: indicates another error

### 5.1.5 VzResolution

**Description:**

Image resolution type

**PS:** The number of enumerated values may vary depending on the product model. For details, see Include

**Enumerator:**

VzColor\_Resolution\_640\_480: indicates that the image resolution is 640x480 (w x h)

VzColor\_Resolution\_800\_600: indicates that the image resolution is 800x600

VzColor\_Resolution\_1600\_1200: indicates that the image resolution is 1600x1200

### 5.1.6 VzConnectStatus

**Description:**

Device connection status.

**PS:** The number of enumerated values may vary depending on the product model. For details, see Include.

**Enumerator:**

VzConnectUNKNOWN: indicates that the connection status is unknown

VzUnconnected: indicates that the device is not connected

VzConnected: indicates that the device is connected

VzOpened: indicates that the device is opened

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VzUpgradeUnconnected: indicates that the device is in the upgrade state

VzUpgradeConnected: indicates that the device is upgraded and connected

### 5.1.7 VzDeviceType

**Description:**

Device type

**Enumerator:**

VzDS77Lite: indicates a DS77Lite camera that uses an RJ45 port and provides only ToF data.

VzDS77CLite: indicates a DS77CLite camera that uses an RJ45 interface and provides ToF+RGB data.

VzDS77Pro: indicates a DS77Pro camera, which uses an aviation plug and provides only ToF data.

VzDS77CPro: Represents a DS77CPro camera, using an aviation plug, while providing ToF+RGB data.

### 5.1.8 VzWorkMode

**Description:**

Equipment working condition.

**Enumerator:**

VzActiveMode: indicates that the device is actively working. At this point, after using API to open the camera, the device will actively upload image data.

VzHardwareTriggerMode: indicates that the device is in passive working state. At

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this time, after the API is used to open the camera, the device will upload the image data when the hardware triggers.

VzSoftwareTriggerMode: indicates that the device is in passive working state. At this time, after using API to open the camera, the device will upload the image data when triggered by the software.

### 5.1.9 VzExposureControlMode

**Description:**

Exposure mode of the sensor

**Enumerator:**

VzExposureControlMode\_Auto: indicates that the sensor uses automatic exposure mode

VzExposureControlMode\_Manual: indicates that the sensor uses manual exposure mode

## 5.2 Struct Type

### 5.2.1 VzRGB888Pixel

**Function:**

Color image pixel type RGB888.

PS: Different models may not support RGB, for example, DCAM550. Please refer to the definition in the Include folder.

**Members:**

Uint8\_t R: indicates the red channel

UInt8\_t g: indicates the green channel

UInt8\_t b: indicates the blue channel

### 5.2.2 VzBGR888Pixel

#### Function:

Color image pixel type BGR888.

PS: Different models may not support RGB, for example, DCAM550. Please refer to the definition in the Include folder.

#### Members:

UInt8\_t b: indicates the blue channel

UInt8\_t g: indicates the green channel

UInt8\_t R: indicates the red channel

### 5.2.3 VzVector3f

#### Function:

Three dimensional point coordinates in millimeters.

#### Members:

Float x: Represents the coordinate value along the X-axis

Float y: Represents the coordinate value along the y axis

Float Z: Represents the coordinate value along the z axis

### 5.2.4 VzVector2u16

#### Function:

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Two dimensional point coordinates.

**Members:**

Float x: Represents the coordinate value along the X-axis

Float y: Represents the coordinate value along the y axis

### 5.2.5 VzDepthVector3

**Function:**

A pixel representation of a depth image.

**Members:**

Int depthX: indicates the coordinate value along the X-axis in the image coordinate system

Int depthY: represents the coordinate value along the Y-axis in the image coordinate system

VzDepthPixel depthZ: Indicates the depth value at pixel coordinates (depthX, depthY), in millimeters

### 5.2.6 VzSensorIntrinsicParameters

**Function:**

Lens parameters and distortion parameters of the sensor. The internal parameter is usually used to calculate the point cloud and the distortion parameter is used in the image anti-distortion algorithm.

SDK has realized the function of converting depth image to point cloud and image anti-distortion, please refer to the routine to use the relevant interface.

**Members:**

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Double FX: Focal length x (pixel)

Double FY: Focal length Y (pixel)

Double CX: Principal Point X (Pixel)

Double cy: Principal point Y (pixel)

Double K1: Radial distortion coefficient, 1st-order

Double K2: Radial distortion coefficient, 2nd-order

Double P1: Tangential distortion coefficient

Double P2: Tangential distortion coefficient

Double K3: Radial distortion coefficient, 3rd-order

Double K4: Radial distortion coefficient, 4ST-order

Double K5: Radial distortion coefficient, 5ND-order

Double K6: Radial distortion coefficient, 6RD-Order

## 5.2.7 VzSensorExtrinsicParameters

### Function:

The external parameters R and T of the camera are used to align depth with RGB images. The reference formula is as follows:

$$\begin{bmatrix} X_{rgb} \\ Y_{rgb} \\ Z_{rgb} \end{bmatrix} = \begin{bmatrix} r_0 & r_1 & r_2 \\ r_3 & r_4 & r_5 \\ r_6 & r_7 & r_8 \end{bmatrix} * \begin{bmatrix} X_{depth} \\ Y_{depth} \\ Z_{depth} \end{bmatrix} + \begin{bmatrix} t_0 \\ t_1 \\ t_2 \end{bmatrix}$$

### Members:

Double rotation[9] : A 3×3 rotation matrix

Double translation[3] :  $3 \times 1$  translation matrix

## 5.2.8 VzFrame

### Function:

Image information

### Members:

UInt32\_t frameIndex: indicates the image frameIndex number

VzFrameType frameType: indicates the image data type

VzPixelFormat pixelFormat: indicates the pixel type

UInt8\_t \* pFrameData: a pointer to the image data cache

UInt32\_t dataLen: Indicates the length of image data in bytes

Float exposureTime: exposureTime, in microseconds

UInt8\_t depthRange: indicates the depthRange of the current frame, valid only for depth images

UInt16\_t Width: indicates the image width

UInt16\_t height: indicates image height

UInt64\_t deviceTimestamp: represents image timestamp

## 5.2.9 VzFrameReady

### Function:

Whether the image data is ready (1 means ready, 0 means not ready)

### Members:

UInt32\_t Depth: 1: indicates whether the depth image data is ready

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UInt32\_t IR: 1: Indicates whether grayscale image data is ready

UInt32\_t Color: 1: indicates whether color image data is ready

UInt32\_t transformedColor: 1: Indicates whether the color image aligned to the depth sensor space is ready

UInt32\_t transformedDepth: 1: indicates whether the depth image is ready to align to the color sensor space

UInt32\_t Confidence: 1: indicates whether the laser intensity image data is ready

UInt32\_t reserved: 26: : Reserved bit

## 5.2.10 VzDeviceInfo

### Function:

Equipment information

### Members:

Int SessionCount: indicates the number of depth sensors in the device

VzDeviceType devicetype: indicates the devicetype

Char URI [256] : indicates the device identifier

Char alias[64] : indicates the device alias

Char serialNumber[64] : indicates the serialNumber of the device

Char IP [17] : indicates the IP address of the device

VzConnectStatus Status: indicates the connection status of the device

## 5.2.11 VzConfidenceFilterParams

### Function:

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Confidence filtering parameter

**Members:**

Bool ENABLE: indicates whether filtering is enabled. True indicates that filtering is enabled. False indicates that filtering is disabled

Int threshold: indicates the filtering threshold

## 5.2.12 VzFlyingPixelFilterParams

**Function:**

To fly point filter parameters

**Members:**

bool enable: indicates whether filtering is enabled. True indicates that filtering is enabled. False indicates that filtering is disabled

Int threshold: indicates the filtering threshold

## 5.2.13 VzSpatialFilterParams

**Function:**

Spatial filtering parameters.

**Members:**

bool enable: indicates whether filtering is enabled. True indicates that filtering is enabled. False indicates that filtering is disabled

Int validCount: indicates the number of reference points used in filtering calculation

Int threshold: indicates the filtering threshold

Int doCount: indicates how many times the filtering is performed

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## 5.2.14 VzFillHoleFilterParams

### Function:

Parameter of hole filling filter

### Members:

bool enable: indicates whether filtering is enabled. True indicates that filtering is enabled. False indicates that filtering is disabled

Int validCount: indicates the number of reference points used in filtering calculation

Int threshold: indicates the filtering threshold

Int doCount: indicates how many times the filtering is performed

## 5.2.15 VzExposureTimeParams

### Function:

Sensor exposure parameter

### Members:

VzExposureControlMode Mode: sensor exposure type

Int exposureTime: sensor exposureTime in microseconds

## 5.3 API

### 5.3.1 VZ\_Initialize

#### Prototype:

VzReturnStatus VZ\_Initialize()

**Description:**

To complete initialization of the SDK, you need to call it before calling other apis

**Parameters:**

void

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.2 VZ\_Shutdown

**Prototype:**

VzReturnStatus VZ\_Shutdown()

**Description:**

The SDK is deregistered and all resources created during the SDK use are released. After this interface is called, no other interfaces other than VZ\_Initialize should be called

**Parameters:**

void

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.3 VZ\_GetSDKVersion

**Prototype:**

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```
const char* VZ_GetSDKVersion()
```

**Description:**

Obtain the SDK version: X.X.X

**Parameters:**

There is no

**Returns:**

The SDK version number

### 5.3.4 VZ\_GetDeviceCount

**Prototype:**

```
VzReturnStatus VZ_GetDeviceCount(uint32_t* pDeviceCount)
```

**Description:**

Get the number of connected devices

**Parameters:**

Uint32\_t \* pDeviceCount: Returns the number of connected devices

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.5 VZ\_GetDeviceInfo

**Prototype:**

```
VzReturnStatus VZ_GetDeviceInfo(uint32_t deviceIndex, VzDeviceInfo*  
pDevicesInfo)
```

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**Description:**

Gets information about the device with the specified index number

**Parameters:**

UInt32\_t deviceIndex: deviceIndex number

VzDeviceInfo\* pDevicesInfo: Returns device information

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.6 VZ\_GetDeviceInfoList

**Prototype:**

```
VzReturnStatus VZ_GetDeviceInfoList(uint32_t deviceCount, VzDeviceInfo*  
pDevicesInfoList)
```

**Description:**

Obtain the device list of the number of Devicecounts

**Parameters:**

UInt32\_t deviceCount: Number of devices that need to get the information list

VzDeviceInfo\* pDevicesInfo: Returns a list of device information that should point to a cache of size sizeof(VzDeviceInfo)\*deviceCount

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.7 VZ\_OpenDeviceByUri

**Prototype:**

```
VzReturnStatus VZ_OpenDeviceByUri(const char* pURI, VzDeviceHandle*  
pDevice)
```

**Description:**

Open the device using the device identifier

**Parameters:**

Const char\* pURI: indicates the device identifier

VzDeviceHandle\* pDevice: The device handle returned after successfully opening the device

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.8 VZ\_OpenDeviceByAlias

**Prototype:**

```
VzReturnStatus VZ_OpenDeviceByAlias(const char* pAlias, VzDeviceHandle*  
pDevice)
```

**Description:**

Open the device using the device alias

**Parameters:**

Const char\* pAlias: indicates the device alias

VzDeviceHandle\* pDevice: The device handle returned after successfully opening the device

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.9 VZ\_OpenDeviceByIP

**Prototype:**

```
VzReturnStatus VZ_OpenDeviceByIP(const char* pIP, VzDeviceHandle* pDevice)
```

**Description:**

Use the device IP address to open the device

**Parameters:**

Const char\* pIP: indicates the IP address of the device

VzDeviceHandle\* pDevice: The device handle returned after successfully opening the device

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.10 VZ\_CloseDevice

**Prototype:**

```
VzReturnStatus VZ_CloseDevice(VzDeviceHandle* pDevice)
```



**Description:**

Close the equipment

**Parameters:**

VzDeviceHandle\* pDevice: Handle to the device to close

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.11 VZ\_StartStream

**Prototype:**

VzReturnStatus VZ\_StartStream(VzDeviceHandle device)

**Description:**

Open data Stream

**Parameters:**

VzDeviceHandle Device: Handle to the device on which the data stream is to be closed

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.12 VZ\_StopStream

**Prototype:**

VzReturnStatus VZ\_StopStream(VzDeviceHandle device)

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**Description:**

Close the data stream

**Parameters:**

VzDeviceHandle Device: Handle to the device on which the data stream is to be closed

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.13 VZ\_GetFrameReady

**Prototype:**

```
VzReturnStatus VZ_GetFrameReady(VzDeviceHandle device, uint16_t  
waitTime, VzFrameReady* pFrameReady)
```

**Description:**

Gets the image ready state. This function must be called before calling VZ\_GetFrame, otherwise the image cannot be retrieved.

**Parameters:**

VzDeviceHandle Device: Device handle

Uint16\_t waitTime: Allows timeout duration (ms) for waiting for image to be ready. This value depends on the frame rate of the image. The recommended value is  $2 \times 1000 / \text{FPS}$ . For example, if the current frame rate is 20, you are advised to set waitTime to  $2 \times 1000 / 20 = 100$ . If set waitTime of 40, call the function might return VzRetGetFrameReadyTimeOut.

VzFrameReady\* pFrameReady: Returns the ready state of the image

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.14 VZ\_GetFrame

**Prototype:**

```
VzReturnStatus VZ_GetFrame(VzDeviceHandle device, VzFrameType  
frameType, VzFrame* pVzFrame)
```

**Description:**

Gets image data of the specified image type. VZ\_GetFrameReady must be called before calling this function.

**Parameters:**

VzDeviceHandle Device: Device handle

VzFrameType frameType: specifies the type of the image to be obtained

VzFrame\* pVzFrame: The returned image data

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.15 VZ\_SetWorkMode

**Prototype:**

```
VzReturnStatus VZ_SetWorkMode(VzDeviceHandle device, VzWorkMode  
mode)
```

**Description:**

Set the camera working mode

**Parameters:**

VzDeviceHandle Device: Device handle

VzWorkMode mode: indicates the working mode to be set

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.16 VZ\_GetWorkMode

**Prototype:**

```
VzReturnStatus VZ_GetWorkMode(VzDeviceHandle device, VzWorkMode*  
pMode)
```

**Description:**

Gets the working mode of the camera

**Parameters:**

VzDeviceHandle Device: Device handle

VzWorkMode\* pMode: indicates the working mode of the obtained device

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.17 VZ\_SetSoftwareSlaveTrigger

**Prototype:**

VzReturnStatus VZ\_SetSoftwareSlaveTrigger(VzDeviceHandle device)

**Description:**

Performs a software trigger, valid only when the camera is in  
VzSoftwareTriggerMode

**Parameters:**

VzDeviceHandle Device: Device handle

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.18 VZ\_GetSensorIntrinsicParameters

**Prototype:**

VzReturnStatus VZ\_GetSensorIntrinsicParameters(VzDeviceHandle device,  
VzSensorType sensorType, VzSensorIntrinsicParameters\*  
pSensorIntrinsicParameters)

**Description:**

Gets an internal parameter for the sensor lens

**Parameters:**

VzDeviceHandle Device: Device handle

VzSensorType sensorType: indicates the sensorType

VzSensorIntrinsicParameters \* pSensorIntrinsicParameters: return sensor inside the lens

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.19 VZ\_GetSensorExtrinsicParameters

**Prototype:**

```
VzReturnStatus VZ_GetSensorExtrinsicParameters(VzDeviceHandle device,  
VzSensorExtrinsicParameters* pSensorExtrinsicParameters)
```

**Description:**

Obtain the foreign parameter of the device

**Parameters:**

VzDeviceHandle Device: Device handle

VzSensorExtrinsicParameters \* pSensorExtrinsicParameters: return outside the cords of the equipment

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.20 VZ\_GetFirmwareVersion

**Prototype:**

```
VzReturnStatus VZ_GetFirmwareVersion(VzDeviceHandle device, char*  
pFirmwareVersion, int length)
```

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**Description:**

Obtain the firmware version of the device

**Parameters:**

VzDeviceHandle Device: Device handle

Char \* pFirmwareVersion: indicates the firmware version of the device

Int length: indicates the byte length of the cache that pFirmwareVersion points to

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.21 VZ\_GetDeviceMACAddress

**Prototype:**

```
VzReturnStatus VZ_GetDeviceMACAddress(VzDeviceHandle device, char*  
pMACAddress)
```

**Description:**

Obtain the MAC address of the device

**Parameters:**

VzDeviceHandle Device: Device handle

Char \* pMACAddress: Returns the MAC address of the device. By default, it is a string of 18 bytes ending in '\0'

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

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### 5.3.22 VZ\_SetIRGMMGain

**Prototype:**

```
VzReturnStatus VZ_SetIRGMMGain(VzDeviceHandle device, uint8_t gmmgain)
```

**Description:**

Set the digital gain of IR image

**Parameters:**

VzDeviceHandle Device: Device handle

Uint8\_t GMmgain: IR gain value to set to the device

**Return:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.23 VZ\_GetIRGMMGain

**Prototype:**

```
VzReturnStatus VZ_GetIRGMMGain(VzDeviceHandle device, uint8_t*  
pGmmgain)
```

**Description:**

The digital gain of IR image is obtained

**Parameters:**

VzDeviceHandle Device: Device handle

Uint8\_t \* pGmmgain: Returns the IR gain value of the device



**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.24 VZ\_SetColorPixelFormat

**Prototype:**

```
VzReturnStatus VZ_SetColorPixelFormat(VzDeviceHandle device,  
VzPixelFormat pixelFormat)
```

**Description:**

Sets the pixel format of the color image

**Parameters:**

VzDeviceHandle Device: Device handle

VzPixelFormat pixelFormat: pixelFormat for the color image to set

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.25 VZ\_GetColorResolution

**Prototype:**

```
VzReturnStatus VZ_GetColorResolution(VzDeviceHandle device, VzResolution*  
pResolution)
```

**Description:**

Gets the pixel format of a color image

**Parameters:**

VzDeviceHandle Device: Device handle

VzResolution\* pResolution: Returns the pixel format of the color image

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.26 VZ\_SetFrameRate

**Prototype:**

VzReturnStatus VZ\_SetFrameRate(VzDeviceHandle device, int value)

**Description:**

Sets the device's image frame rate for both depth and color images. This interface is a synchronization interface, which takes about 500ms

**Parameters:**

VzDeviceHandle Device: Device handle

Int value: target frame rate to be set

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.27 VZ\_GetFrameRate

**Prototype:**

VzReturnStatus VZ\_GetFrameRate(VzDeviceHandle device, int\* pValue)

**Description:**

Gets the image frame rate of the device

**Parameters:**

VzDeviceHandle Device: Device handle

Int \* pValue: Returns the frame rate of the device image

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

## 5.3.28 VZ\_SetExposureControlMode

**Prototype:**

```
VzReturnStatus VZ_SetExposureControlMode(VzDeviceHandle device,  
VzSensorType sensorType, VzExposureControlMode controlMode)
```

**Description:**

Set the exposure mode of the sensor

**Parameters:**

VzDeviceHandle Device: Device handle

VzSensorType sensorType: sensorType for which the exposure mode is to be set

VzExposureControlMode controlMode: Exposure mode to set

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

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### 5.3.29 VZ\_GetExposureControlMode

**Prototype:**

```
VzReturnStatus VZ_GetExposureControlMode(VzDeviceHandle device,  
VzSensorType sensorType, VzExposureControlMode* pControlMode)
```

**Description:**

Gets the exposure mode of the sensor

**Parameters:**

VzDeviceHandle Device: Device handle

VzSensorType sensorType: sensorType to obtain the exposure mode

VzExposureControlMode controlMode: Returns the sensor's exposure mode

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.30 VZ\_SetExposureTime

**Prototype:**

```
VzReturnStatus VZ_SetExposureTime(VzDeviceHandle device, VzSensorType  
sensorType, VzExposureTimeParams exposureTime)
```

**Description:**

Set the exposure time of the sensor

Depth sensor, only support manual exposure mode, set exposure time

Color sensor, support in automatic exposure mode, set the maximum exposure

time; The exposure time can be set in manual exposure mode

**Parameters:**

VzDeviceHandle Device: Device handle

VzSensorType sensorType: sensorType to obtain the exposure time

VzExposureTimeParams exposureTime: exposureTime parameter to set

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.31 VZ\_GetExposureTime

**Prototype:**

```
VzReturnStatus VZ_GetExposureTime(VzDeviceHandle device, VzSensorType  
sensorType, VzExposureTimeParams* pExposureTime)
```

**Description:**

Obtain the exposure time of the sensor

Depth sensor, support in manual exposure mode, access to exposure time;

The maximum exposure time can be obtained

Color sensor, support in manual exposure mode, access to exposure time;

The maximum exposure time can be obtained

**Parameters:**

VzDeviceHandle Device: Device handle

VzSensorType sensorType: sensorType to obtain the exposure time

VzExposureTimeParams\* pExposureTime: Returns the acquired exposure time parameter

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.32 VZ\_SetTimeFilterEnabled

**Prototype:**

```
VzReturnStatus VZ_SetTimeFilterEnabled(VzDeviceHandle device, bool  
bEnabled)
```

**Description:**

Set the time domain filter switch of depth image

**Parameters:**

VzDeviceHandle Device: Device handle

Bool bEnabled: True indicates that filtering is enabled. False indicates that filtering is disabled

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.33 VZ\_GetTimeFilterEnabled

**Prototype:**

```
VzReturnStatus VZ_GetTimeFilterEnabled(VzDeviceHandle device, bool  
*pEnabled)
```

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**Description:**

Obtain the time domain filter switch state of depth image

**Parameters:**

VzDeviceHandle Device: Device handle

Bool \*pEnabled: Returns filtering switch status

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.34 VZ\_SetConfidenceFilterParams

**Prototype:**

```
VzReturnStatus VZ_SetConfidenceFilterParams(VzDeviceHandle device,  
VzConfidenceFilterParams params)
```

**Description:**

Set the confidence filtering parameter of depth image

VzDeviceHandle Device: Device handle

Bool \*pEnabled: Returns filtering switch status

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.35 VZ\_GetConfidenceFilterParams

**Prototype:**

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```
VzReturnStatus VZ_GetConfidenceFilterParams(VzDeviceHandle device,  
VzConfidenceFilterParams *pParams)
```

**Description:**

The confidence filter parameters of depth image are obtained

**Parameters:**

VzDeviceHandle Device: Device handle

Bool \*pEnabled: Returns filtering switch status

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.36 VZ\_SetFlyingPixelFilterParams

**Prototype:**

```
VzReturnStatus VZ_SetFlyingPixelFilterParams(VzDeviceHandle device, const  
VzFlyingPixelFilterParams params)
```

**Description:**

Set the fly - point filter parameter of depth image

**Parameters:**

VzDeviceHandle Device: Device handle

Const VzFlyingPixelFilterParams params: filter parameters

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

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### 5.3.37 VZ\_GetFlyingPixelFilterParams

**Prototype:**

```
VzReturnStatus VZ_GetFlyingPixelFilterParams(VzDeviceHandle device,  
VzFlyingPixelFilterParams* params)
```

**Description:**

To obtain the flying point filter parameters of depth image

**Parameters:**

VzDeviceHandle Device: Device handle

VzFlyingPixelFilterParams \* params: filter parameters

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.38 VZ\_SetFillHoleFilterParams

**Prototype:**

```
VzReturnStatus VZ_SetFillHoleFilterParams(VzDeviceHandle device, const  
VzFillHoleFilterParams params)
```

**Description:**

Set the hole filling filter parameters of depth image

**Parameters:**

VzDeviceHandle Device: Device handle

Const VzFillHoleFilterParams Params: indicates the filtering parameter

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.39 VZ\_GetFillHoleFilterParams

**Prototype:**

```
VzReturnStatus VZ_GetFillHoleFilterParams(VzDeviceHandle device,  
VzFillHoleFilterParams* params)
```

**Description:**

The hole filling filter parameters of depth image are obtained

**Parameters:**

VzDeviceHandle Device: Device handle

VzFillHoleFilterParams\* Params: indicates the obtained filtering parameter

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.40 VZ\_SetSpatialFilterParams

**Prototype:**

```
VzReturnStatus VZ_SetSpatialFilterParams(VzDeviceHandle device, const  
VzSpatialFilterParams params)
```

**Description:**

Set the spatial filtering parameters of the depth image

**Parameters:**

VzDeviceHandle Device: Device handle

Const VzSpatialFilterParams Params: indicates the filtering parameter

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.41 VZ\_GetSpatialFilterParams

**Prototype:**

```
VzReturnStatus VZ_GetSpatialFilterParams(VzDeviceHandle device,  
VzSpatialFilterParams* params)
```

**Description:**

Set the spatial filtering parameters of the depth image

**Parameters:**

VzDeviceHandle Device: Device handle

VzSpatialFilterParams\* Params: indicates the obtained filtering parameter

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.42 VZ\_SetTransformColorImgToDepthSensorEnabled

**Prototype:**

```
VzReturnStatus
```

Vzense Technology, Inc.

VZ\_SetTransformColorImgToDepthSensorEnabled(VzDeviceHandle device,  
bool bEnabled)

**Description:**

Switch to set color image alignment to depth camera space. Only devices with color sensors support this operation. If turn on the switch, then call VZ\_GetFrameReady, VzFrameReady. TransformedColor value is 1, Then call VZ\_GetFrame can get VzTransformColorImgToDepthSensorFrame types of color image, the image size is the same size and depth.

**Parameters:**

VzDeviceHandle Device: Device handle

Bool bEnabled: True turns alignment on, false turns alignment off

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.43 VZ\_GetTransformColorImgToDepthSensorEnabled

**Prototype:**

VzReturnStatus  
VZ\_GetTransformColorImgToDepthSensorEnabled(VzDeviceHandle device,  
bool \*bEnabled)

**Description:**

Gets the on/off state for color image alignment to depth camera space

**Parameters:**

VzDeviceHandle Device: Device handle

Bool \*bEnabled: Return switch status

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.44 VZ\_SetTransformDepthImgToColorSensorEnabled

**Prototype:**

VzReturnStatus

VZ\_SetTransformDepthImgToColorSensorEnabled(VzDeviceHandle device,  
bool bEnabled)

**Description:**

Switch that sets the alignment of depth images to color camera space. Only devices with color sensors support this operation. If turn on the switch, then call VZ\_GetFrameReady, VzFrameReady. TransformedDepth value is 1, Then call VZ\_GetFrame can get VzTransformDepthImgToColorSensorFrame type of depth image, its size and color image size is the same.

**Parameters:**

VzDeviceHandle Device: Device handle

Bool bEnabled: True turns alignment on, false turns alignment off

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.45 VZ\_GetTransformDepthImgToColorSensorEnabled

**Prototype:**

```
VzReturnStatus  
VZ_GetTransformDepthImgToColorSensorEnabled(VzDeviceHandle device,  
bool *bEnabled)
```

**Description:**

Gets the on/off state of the depth image alignment to color camera space

**Parameters:**

VzDeviceHandle Device: Device handle

Bool \*bEnabled: Return switch status

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.46 VZ\_TransformedDepthPointToColorPoint

**Prototype:**

```
VzReturnStatus VZ_TransformedDepthPointToColorPoint(const  
VzDeviceHandle device, const VzDepthVector3 depthPoint, const  
VzVector2u16 colorSize, VzVector2u16* pPointInColor)
```

**Description:**

Align the points on the depth image to the color image space to obtain the coordinates of the points corresponding to the passing depth image coordinate points on the color image

**Parameters:**

VzDeviceHandle Device: Device handle

Const VzDepthVector3 depthPoint: Coordinate point of the depth image

Const VzVector2u16 colorSize: Color image size

VzVector2u16\* pPointInColor: obtained color image coordinate points  
corresponding to the depth image coordinate points

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.47 VZ\_ConvertDepthToPointCloud

**Prototype:**

```
VzReturnStatus VZ_ConvertDepthToPointCloud(VzDeviceHandle device,  
VzDepthVector3* pDepthVector, VzVector3f* pWorldVector, int32_t pointCount,  
VzSensorIntrinsicParameters* pSensorParam)
```

**Description:**

The incoming depth image coordinate point set is converted to the world coordinate point set. The origin of world coordinates is in the center of the depth sensor lens, and the Z-axis is perpendicular to the front cover of the device, and its positive direction is pointing away from the device. The X-axis points to the laser from the depth lens, and its positive direction points to the distance from the device; The Y-axis is perpendicular to the device pointing to the ground, and its positive direction is pointing away from the device.

**Parameters:**

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VzDeviceHandle Device: Device handle

VzDepthVector3\* pDepthVector: A collection of coordinate points of the depth image

VzVector3f\* pWorldVector: The set of coordinate points of the transformed point cloud

Int32\_t pointCount: indicates the number of coordinate points

VzSensorIntrinsicParameters \* pSensorParam: sensor inside

**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.48 VZ\_ConvertDepthFrameToPointCloudVector

**Prototype:**

```
VzReturnStatus VZ_ConvertDepthFrameToPointCloudVector(VzDeviceHandle device, const VzFrame* pDepthFrame, VzVector3f* pWorldVector)
```

**Description:**

Convert the depth image to a set of world frame points. The size of the converted world frame points is vzframe.width \* vzframe.height, Support VzDepthFrame and VzTransformDepthImgToColorSensorFrame images

**Parameters:**

VzDeviceHandle Device: Device handle

Const VzFrame\* pDepthFrame: Depth image

VzVector3f\* pWorldVector: The set of coordinate points of the transformed point cloud



**Returns:**

VzRetOK: The call is successful

Other values: Call failed

### 5.3.49 VZ\_SetHotPlugStatusCallback

**Prototype:**

```
VzReturnStatus VZ_SetHotPlugStatusCallback(PtrHotPlugStatusCallback  
pCallback, const void* pUserData)
```

**Description:**

Sets hotplug status callback function

**Parameters:**

PtrHotPlugStatusCallback pCallback: indicates the callback function

Const void\* pUserData: user data; may be empty

**Returns:**

VzRetOK: The call is successful

Other values: Call fail

## 6 FAQ

### 6.1 Where is SDK log stored?

For Linux, default location: /home/<user name>/.config/Vzense/Log

### 6.2 Nebula SDK cannot search the camera

Following lists need to be checked if Ethernet access cameras can't be searched.

1. Make sure good connection between the DUT and the host, and confirm if the network adapter of the host works well.
2. Make sure the DUT is under the same LAN as the host. If the DUT is set in non-DHCP mode, make sure the DUT's fixed IP is in the same internet segment as the host, like 192.168.1.X; If the DUT is set in DHCP mode, make sure the DUT is in the same LAN as the host, and the router/switch has DHCP server function.
3. Make sure the software's internet permission is not prohibited.
4. Make sure Internet UDP function is not prohibited by LAN safety policy.
5. Make sure LAN 9007, 9008, 9009 port is not prohibited
6. Make sure power supply is correct. If not POE approach, make sure power adapter is plugged.

If the above check items are OK, but the camera still cannot be opened, please contact FAE.

Email: [info@vzense.com](mailto:info@vzense.com)