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namespace Microsoft . Kinect 
. public sealed class 
KinectSensor 
ruKinectSensor() 
. INoti fyPrope rtyChanged 
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. public 
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. public 
InfraredFrameSource InfraredFrameSource { get ; 
bool IsOpen { get; } 
bool IsAvai1ab1e { get; } 
KinectCapabi1ities KinectCapabi1ities { get ; 
AudioSource 
AudioSource { get; } 
BodyFrameSource 
BodyFrameSource { get; } 
BodylndexFrameSource 
BodylndexFrameSource { get; } 
LongExposureInfraredFrameSource LongExposureInfraredFrameSource { get; 
string UniqueKinectId { get; } 
DepthFrameSource DepthFrameSource { get ; 
ColorFrameSou rce 
ColorFrameSource { get ; 
CoordinateMappe { get ; 
Coordinatemapper 
PropertyChangedEventHand1er 
Pm»ertyChanged ; 
event 
event EventHand1er< IsAvai1ab1eChangedEventArgs> IsAvai1ab1eChanged; 
GetDefau1t(); 
static 
KinectSensor 
o; 
void Close 
void Open(); 
Multi SourceFrameReader OpenMu1tiSourceFrameReader(FrameSourceTypes 
enabledFrameSourceTypes) ; 

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namespace Microsoft . Kinect 
public sealed class 
Coordinatemappe 
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public 
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public 
event EventHand1er< CoordinateMappingChangedEventArgs> CoordinateMappingChanged; 
o; 
Cameralntrinsics 
GetDepthCameraIntrinsics 
PointFC] GetDepthFrameToCameraSpaceTab1e(); 
void MapCameraPointsToC010rSpace(CameraSpacePointC] cameraPoints, 
void MapCameraPointsToC010rSpaceUsingIntPtr(IntPtr 
cameraPoints , 
void MapCameraPointsToDepthSpace(CameraSpacePoint 
C] cameraPoints, 
void MapCameraPointsToDepthSpaceUsingIntPtr(IntPtr 
cameraPoints , 
ColorSpacePointC] colorpoints) ; 
uint cameraPointsSize, 
colorPt 
IntPtr 
] depthpoints); 
DepthSpacePoint 
uint cameraPointsSize, 
depthPt 
IntPtr 
ColorSpacePoint MapCameraPointToC010rSpace(CameraSpacePoint camerapoint) ; 
DepthSpacePoint MapCameraPointToDepthSpace(CameraSpacePoint camerapoint) ; 
void 
void 
void 
void 
void 
void 
void 
void 
void 
MapC010rFrameToCameraSpace(ushortC] depthFrameData, 
CameraSpacePoint[] cameraSpacePoints) ; 
MapC010rFrame ToCameraSpaceUsingIntPtr(IntPtr 
depthFrameData, uint depthFrameSize, 
CameraSpacePoil 
MapC010rFrame ToCameraSpaceUsingIntPtr(IntPtr 
depthFrameData, uint depthFrameSize, 
IntPtr 
cameraSl 
MapC010rFrameToDepthSpace(ushortC] depthFrameData, 
DepthSpacePointC] depthspacepoints) ; 
MapC010rFrameToDepthSpaceUsingIntPtr(IntPtr 
depthFrameData, uint depthFrameSize , 
DepthSpacePoint 
MapC010rFrame ToDepthSpaceUsingIntPtr(IntPtr 
depthFrameData, uint depthFrameSize , 
depthSpa. 
IntPtr 
MapDepthFrameToCameraSpace(ushortC] depthFrameData, 
CameraSpacePoint[] cameraSpacePoints) ; 
MapDepthFrame ToCameraSpaceUsingIntPtr(IntPtr 
depthFrameData, uint depthFrameSize, 
IntPtr 
cameraSl 
Mao De DthFrame ToCameraSoaceUsin21ntPtr( Int Ptr 
deothFrameData. uint deothFrameSize 
CameraSDacePoil 

Tekst alternatywny wygenerowany przez komputer:
Enamespace Microsoft.Kinect
public struct Cameralntrinsics
{
15 . . . public float RadialDistortionSixthOrder { get; set; }
19 4 ... public float RadialDistortionFourthOrder { get; set; }
23 ... public float RadialDistortionSecondOrder { get; set; }
27 . . . public float PrincipalPointY { get; set; )
31 . . . public float PrincipalPointX { get; set; J
35 . . . public float FocalLengthY ( get; set; J
39 . . . public float FocalLengthX { get; set; J