

# Vzense TOF Camera SDK User Guide

Windows

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Vzense Technology, Inc.

# About This Document

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

## Document Structure

Chapter	Title	Contents
1	Overview	Introduce general information of Vzense SDK
2	Products	Introduce general information of Vzense products
3	Installation	Introduce how to install Vzense TOF Depth Camera and SDK
4	SDK Instruction	Introduce how to use Vzense SDK
5	API Introduction	Introduce APIs of Vzense SDK
6	Update Firmware	Introduce how to update firmware
7	APIs examples	Introduce some initialization examples
8	FAQs	

## Release Record

Date	Version	Instruction
2019/12/24	V3.0.0.7	Optimize SDK framework and code
2020/12/04	V3.2.2	Add DCAM550
2021/01/12	V3.4.8	Add DCAM560

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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.

The Vzense SDK is a development kit based on Vzense TOF Camera, which is currently applicable to Windows/Linux. It provides a series of friendly APIs and simple application examples for developers.

Developers can get high precision depth image data, gray image data and point cloud data through the SDK. It is convenient for users 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/Vzense\\_SDK\\_Windows](https://github.com/Vzense/Vzense_SDK_Windows)

[https://gitee.com/Vzense/Vzense\\_SDK\\_windows](https://gitee.com/Vzense/Vzense_SDK_windows)

## 2. Products

### 2.1. DCAM710



Figure 2.1 Vzense TOF RGBD Camera : DCAM710

DCAM710 is a 3D camera module developed by Vzense which uses TOF (Time of Flight) technology. The depth information it outputs can be applied to the next generation of UI which is based on gesture recognition, TV and Game motion-sensitivity interaction, face recognition, robot obstacle avoidance, advanced automotive vision system, industrial control and other frontier creative technologies.

### 2.2. DCAM550U



Figure 2.2 Vzense TOF Camera : DCAM550U

DCAM550U is a 3D camera based on TOF technology specially developed by Vzense for Vzense Technology, Inc.

industrial application scenarios. It supports USB2.0 type A interface with lock. DCAM550U can support trigger mode and synchronization mode for different application scenarios.

## 2.3. DCAM550P



Figure 2.3 Vzense TOF Camera : DCAM550P

DCAM550P is a 3D camera based on TOF technology specially developed by Vzense for industrial application scenarios. It supports 100M Ethernet. DCAM550P can support trigger mode and synchronization mode for different application scenarios.

## 2.4. DCAM550E



Figure 2.4 Vzense TOF Camera: DCAM550E

DCAM550E is a 3D camera based on TOF technology specially developed by Vzense for

industrial application scenarios. It supports 100M Ethernet. DCAM550E can support trigger mode, synchronization mode and IP67 protection level for different application scenarios.

## 2.5. DCAM560CPRO



Figure 2.5 Vzense TOF RGBD Camera : DCAM560CPRO

DCAM560CPRO is a 3D + RGB camera based on TOF technology specially developed by Vzense for industrial application scenarios. It supports 1000M Ethernet. DCAM560CPRO can support trigger mode, synchronization mode and IP67 protection level for different application scenarios.

## 2.6. DCAM560CLITE



Figure 2.6 Vzense TOF RGBD Camera : DCAM560CLITE

DCAM560CLITE is a 3D + RGB camera based on TOF technology specially developed by Vzense for industrial application scenarios. It supports 1000M Ethernet. DCAM560CLITE can support trigger mode and synchronization mode for different application scenarios.

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## 3. Installation

### 3.1. Recommended Development Environment

Item	Recommended Configuration
OS	Win7 32/64 bits Win10 32/64 bits
RAM	4G or above

### 3.2. Installation Instruction

#### 3.2.1. Hardware Installation

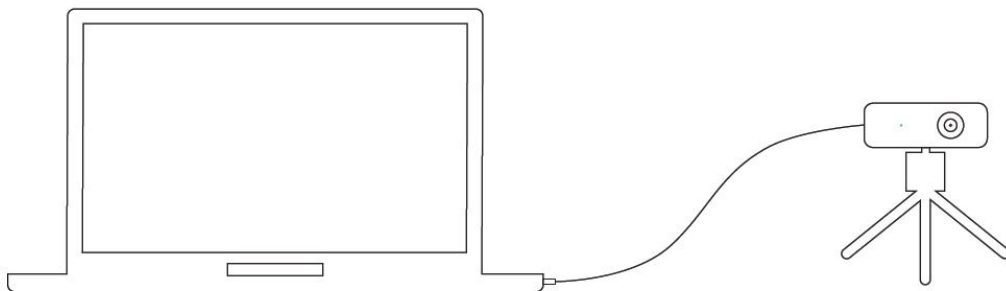


Figure 3.1 Hardware Installation

##### 3.2.1.1. USB

Connect the camera module to PC USB interface through USB cable.

In Windows, when the camera module is successfully connected, it will pop up the notice of the device driver installation. After the driver is auto-installed successfully, it will display the **Vzense RGBD Camera** device in Windows Device Manger.

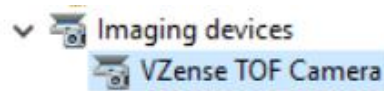


Figure 3.2 Vzense RGBD Camera

### 3.2.1.2. Network

Network cable connection can be divided into fixed address direct connection and DHCP connection.

#### 1. Fixed address

The fixed address connection can be directly connected to the camera and the computer, or it can be configured to be used in the switch of the same network segment.

Direct connection: one end is connected to the camera, and the other end is connected to the network cable interface of the PC host. The default IP of the camera is 192.168.1.101. On the PC side, set the subnet mask of "local connection" to 255.255.255.0, and the IP address to the same network segment (such as 192.168.1.100).

General

You can get IP settings assigned automatically if your network supports this capability. Otherwise, you need to ask your network administrator for the appropriate IP settings.

☐ Obtain an IP address automatically

☒ Use the following IP address:

IP address: 192 . 168 . 1 . 100

Subnet mask: 255 . 255 . 255 . 0

Default gateway: . . .

☐ Obtain DNS server address automatically

☒ Use the following DNS server addresses

Preferred DNS server: . . .

Alternate DNS server: . . .

☐ Validate settings upon exit

Advanced...

OK Cancel

Figure 3.3 Direct connection

## 2. DHCP

For the DHCP connection mode, the camera needs to be connected to the router with DHCP enabled, and the PC in the same LAN is used for connection. It is recommended to set the "local connection" of the PC to obtain the IP address automatically.

**General** **Alternate Configuration**

You can get IP settings assigned automatically if your network supports this capability. Otherwise, you need to ask your network administrator for the appropriate IP settings.

☒ Obtain an IP address automatically

☐ Use the following IP address:

IP address:

Subnet mask:

Default gateway:

☒ Obtain DNS server address automatically

☐ Use the following DNS server addresses

Preferred DNS server:

Alternate DNS server:

☐ Validate settings upon exit

Advanced...

OK Cancel

Figure 3.4 DHCP

Note:

1. The network card, router and switch used at the PC end shall meet the requirements of Gigabit
2. When you first run the SDK, set permissions for the SDK to pass through the system firewall.

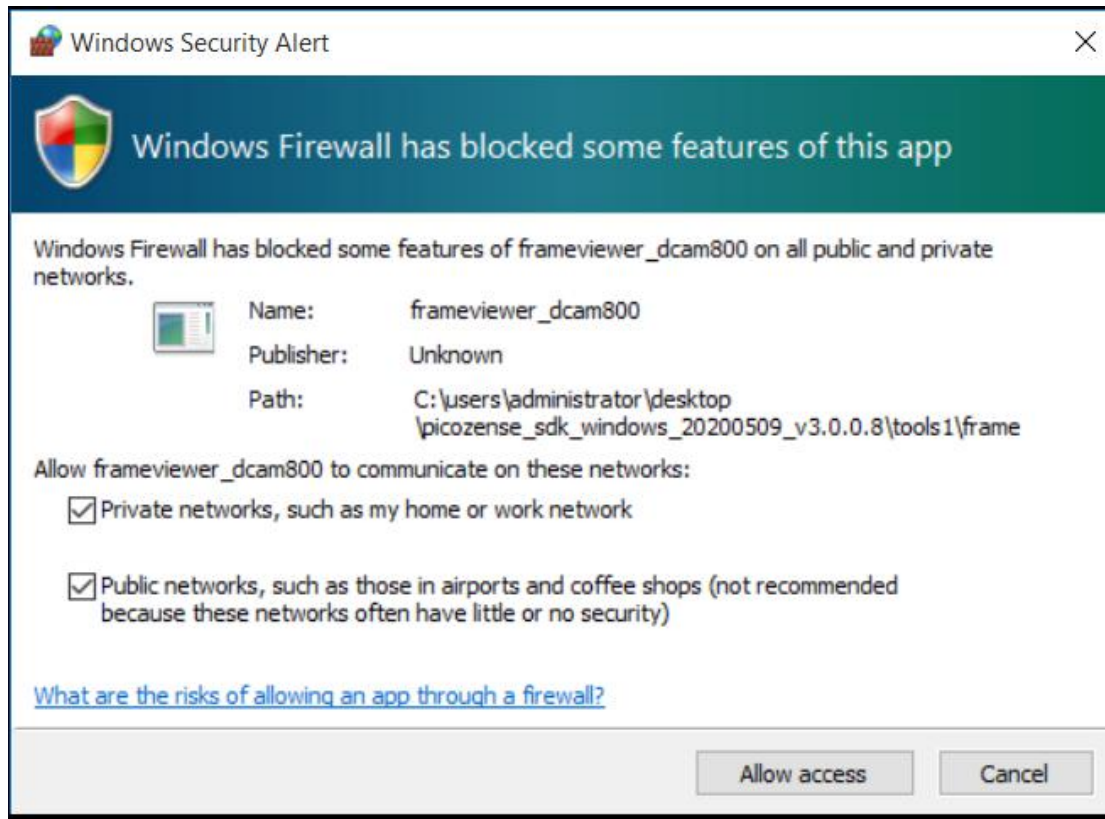


Figure 3.5 firewall setting

### 3.2.2. Software Environment Setup

No other software needed in Windows.

## 4. SDK Instruction

### 4.1. SDK Structure

Vzense SDK contains several directories, including Bin, Document, Include, Lib, Samples, Tools.

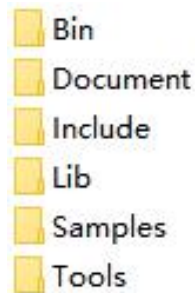
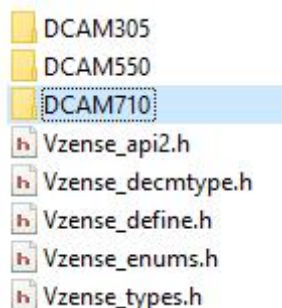


Figure 4.1 Windows SDK directory

The Bin directory has Vzense Windows SDK DLLs, such as Vzense\_api.dll, including both x64 and x86 versions. Before running the application developed by the Vzense SDK, it needs to copy the vzense\_api.dll and whole Config directory to the directory in which executable application locates.

The Document directory contains English and Chinese version of SDK user guide. Include mainly includes the general header files of SDK(Vzense\_decmttype.h, Vzense\_api2.h, Vzense\_define.h, Vzense\_enums.h, Vzense\_type.h) and folders containing specific header files required by different models of products, such as DCAM710.



The Lib directory contains the lib files of the Windows SDK, such as vzense\_api.lib.

The Samples directory mainly includes some code samples which are developed based on the Vzense SDK.

The Tools directory includes the tool FrameViewer which can show depth and IR images of the Vzense camera.

## 4.2. Tool Usage

Connect Vzense Camera to PC. Run FrameViewer.exe in the Tools directory. This application will show two windows to display IR image and depth image separately. As illustrated below, the RGB image displays normally without stutters, it indicates that the camera works normally.



Figure 4.2 Running the FrameViewer tool

## 4.3. Development Process

### 4.3.1. Project Configuration

For Windows, create a new application project in Visual Studio 2013. Set the project property to add the Include path of Vzense SDK to [Include Directories] and add the Lib path to [Library Directories]. Additionally, it needs to add the vzense\_api.lib to [Additional Dependencies]. The project configuration in Samples can be a reference.

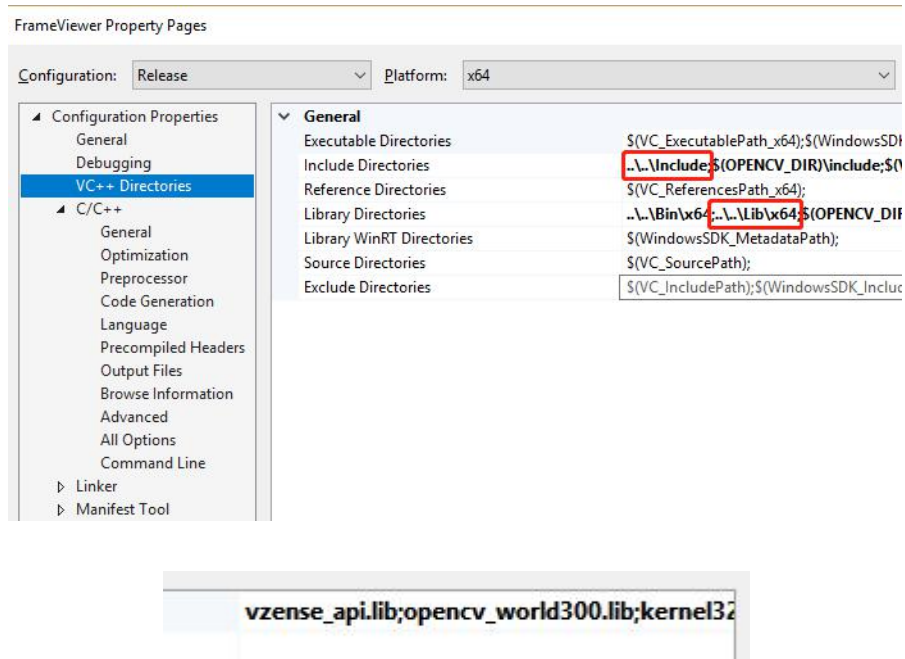


Figure 4.3 SDK Project Configuration

### 4.3.2. API Invoke Process

The API of Vzense SDK invoking process is as below:

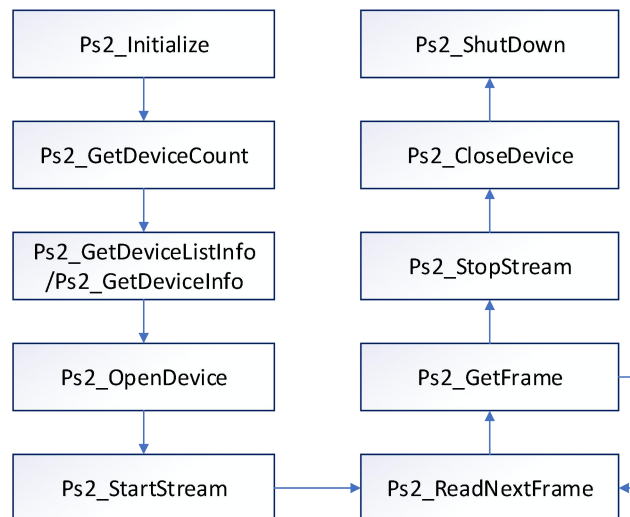


Figure 4.4 SDK API Invoke Process



### 1. Ps2\_Initialize&Ps2\_Shutdown

Call the Ps2\_Initialize interface and initialize the SDK. Call the PsShutdown interface finally to log out the SDK and release all the resources created by the SDK.

### 2. Ps2\_GetDeviceCount &Ps2\_GetDeviceListInfo/Ps2\_GetDeviceInfo

Call the Ps2\_GetDeviceCount interface to get the number of devices currently connected. Call the Ps2\_GetDeviceListInfo/Ps2\_GetDeviceInfo interface to get the info of devices currently connected.

### 3. Ps2\_OpenDevice&Ps2\_CloseDevice

Call the Ps2\_OpenDevice interface to open the specified depth camera device. Call the Ps2\_CloseDevice interface to close the specified device.

### 4. Ps2\_StartStream&Ps2\_StopStream

Call the Ps2\_StartStream interface to open the stream of the camera device. Call the Ps2\_StopStream interface to close the stream of the camera device.

### 5. Ps2\_ReadNextFrame&Ps2\_GetFrame

In the main loop of image processing, each time Ps2\_ReadNextFrame is called first to collect a frame image, and then call Ps2\_GetFrame to obtain a frame image data of the specified image type, which is used for corresponding image processing.

### 6. Set&Get

The SDK provides a rich **Set** and **Get** type interface for setting and acquiring camera properties, parameters and data, as detailed in Section 4.3. If you need change the camera parameters before call the Ps2\_ReadNextFrame, please invoking as below:

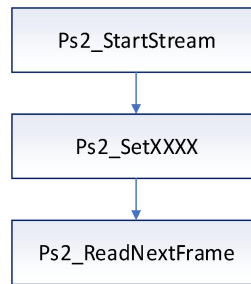


Figure 4.5 SDK API Invoke Process

## 4.4. SDK Sample

The sample of Vzense SDK is used to demonstrate the using of APIs. In sample the OpenCV is used for depth image showing with colorized, if user do not want to show the images, the OpenCV is not necessary.

1. Download and install OpenCV3.0.0 from OpenCV official website:

<http://opencv.org/releases.html>.

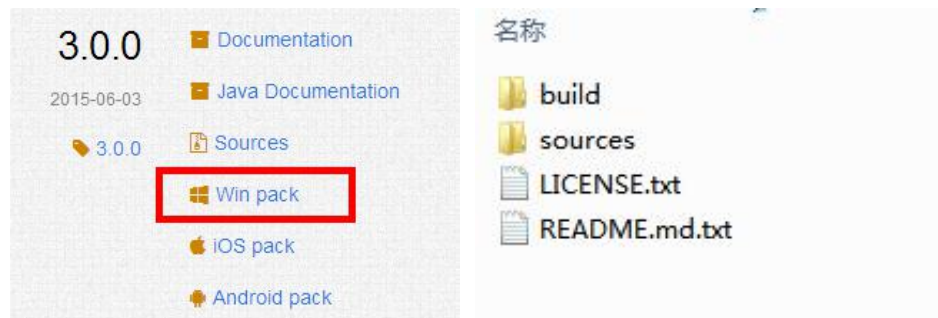


Figure 4.6 Download and Install OpenCV3.0.0

2. Set the environment variable OPENCV\_DIR. Its value is the absolute path of the “build” directory of OpenCV, for example, D:\Program Files\opencv-3.0.0\build.

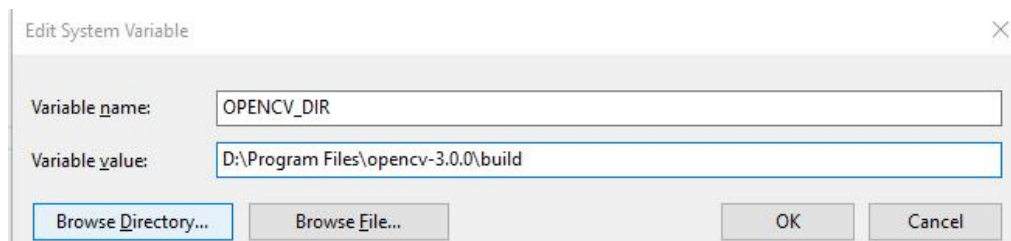


Figure 4.7 Set the Environment Variable OPENCV\_DIR

3. Open the solution FrameViewer.sln in Vzense Technology, Inc.

VzenseSDK\_Windows\_xxx\Samples\FrameViewer with Visual Studio 2013, then build the solution.

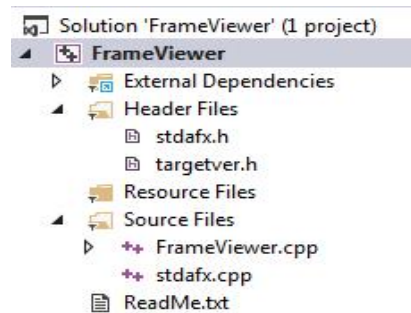


Figure 4.8 FrameViewer Project

4. The project configuration can automatically copy opencv\_world300.dll, vzense\_api.dll and all Config files to designated directory. Of course, the developer can also copy these files to the executable directory manually.
5. Run and debug the program. It works like FrameViewer application in Tools directory.

## 4.5. Notices

When using include, you need to modify the macro definition status in Vzense\_decctype.h according to different models of devices. For example, if you use DCAM550, only the DCAM\_550 macro definition is reserved, and other definitions are commented out. The DCAM800, DCAM800LITE, DCAM500 and DCAM550 use the same api.

```
#ifndef VZENSE_DECCTYPE_H
#define VZENSE_DECCTYPE_H

// #define DCAM_550
// #define DCAM_305
#define DCAM_710

#endif /* VZENSE_DECCTYPE_H */
```

When the Frameviewer project in the Samples directory is compiled, the Frameviewer.cpp has defined different modules according to the macro definition in Vzense\_decctype.h. In the actual development process, please refer to the header file under the specific model folder in Include.

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## 5. SDK API Introduction

### 5.1. Enum Type

#### 5.1.1. PsDepthRange

##### Description:

Depth Range mode

##### Enumerator:

PsNearRange: Near Range mode, Range0

PsMidRange: Middle Range mode, Range1

PsFarRange: Far Range mode, Range2

PsXNearRange: XNear range mode, Range3

PsXMidRange: XMid range mode, Range4

PsXFarRange: XFar range mode, Range5

PsXXNearRange: XXNear range mode, Range6

PsXXMidRange: XXMiddle range mode, Range7

PsXXFarRange: XXFar range mode, Range8

Note: Partial cameras may only support part of these nine modes.

#### 5.1.2. PsDataMode

##### Description:

Data mode setting, determine which frame output from device and frame fps.

**PS:** the definition of enumeration values corresponding to different model products may be different. Please refer to the definition under the specific model folder in include.

#### **Enumerator:**

PsDepthAndRGB\_30: Output both Depth and RGB frames in 30fps. Resolution of depth frame is 640\*480. Resolution of RGB can be set by PsSetFrameMode, which support 1920\*1080/1280\*720/640\*480/640\*360;

PsDepth\_30: Output only Depth frames in 30fps. Resolution of depth frame is 640\*480.

PsIRAndRGB\_30: Output both IR and RGB frames in 30fps. Resolution of ir frame is 640\*480. Resolution of RGB can be set by PsSetFrameMode, which support 1920\*1080/1280\*720/640\*480/640\*360;

PsIR\_30: Output only IR frames in 30fps. Resolution of IR frame is 640\*480.

PsDepthAndIR\_30: Output both Depth and IR frames in 30fps. Resolution of both Depth and IR frames is 640\*480

PsDepthAndIR\_15\_RGB\_30: Output Depth/IR frames alternatively in 15fps , resolution of both Depth and IR frames is 640\*480. Resolution of RGB can be set by PsSetFrameMode, which support 1920\*1080/1280\*720/640\*480/640\*360.

PsDepthAndIR\_15: Output only Depth/IR frames alternatively in 15fp, Resolution of both Depth and IR frames is 640\*480.

PsWDR\_Depth: WDR(Wide Dynamic Range) Depth mode, support multi range depth frame output alternatively, like Near/Far/Near/Far/Near..., and can be make fusion to one WDR frame.

### 5.1.3. PsPropertyType

**Description:**

Specific property type. It is not recommended to use in user applications.

**PS:** the number of enumeration values corresponding to different models of products may be different. Please refer to the definition under the specific model folder in include.

**Enumerator:**

PsPropertyDataModeList: Get the supportive datamode list.

PsPropertyDepthRangeList: Get the supportive depthrange list.

### 5.1.4. PsFrameType

**Description:**

Specific image frame type.

**PS:** the number of enumeration values corresponding to different models of products may be different. Please refer to the definition under the specific model folder in include.

**Enumerator:**

PsDepthFrame: depth image frame

PsIRFrame: IR gray image frame.

PsRGBFrame: RGB image frame.

PsMappedRGBFrame: RGB image which is mapped to Depth space.

PsMappedDepthFrame: Depth image which is mapped to RGB space.

PsMappedIRFrame: IR image which is mapped to RGB space.

PsWDRDepthFrame: WDR depth frame with 16bits per pixel in mm, only take  
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effect when data mode set to PsWDR\_Depth.

### 5.1.5. PsSensorType

#### Description:

The camera sensor type.

**PS:** the number of enumeration values corresponding to different models of products may be different. Please refer to the definition under the specific model folder in include.

#### Enumerator:

PsDepthSensor: Depth camera

PsRgbSensor: RGB camera

### 5.1.6. PsPixelFormat

#### Description:

Specific image pixel type

**PS:** the number of enumeration values corresponding to different models of products may be different. Please refer to the definition under the specific model folder in include.

#### Enumerator:

PsPixelFormatDepthMM16: Data of each pixel is 16bit depth value  
(in millimeter).

PsPixelFormatGray16: Data of each pixel is 16bit gray value

PsPixelFormatGray8: Data of each pixel is 8bit gray value

PsPixelFormatRGB888: Data of each pixel is 24bit RGB value

PsPixelFormatBGR888: Data of each pixel is 16bit BGR value

### 5.1.7. PsReturnStatus

#### Description:

Return status of API

#### Enumerator:

PsRetOK: Succeed

PsRetNoDeviceConnected: No depth camera connected or the camera connected abnormally. Please check HW connection or try to plug out and plug camera in again.

PsRetInvalidDeviceIndex: The input device index is invalid

PsRetDevicePointerIsNull: The device structure pointer is null

PsRetInvalidFrameType: The input frame type is invalid

PsRetFramePointerIsNull: The output frame is empty

PsRetNoPropertyValueGet: Cannot get the property value

PsRetNoPropertyValueSet: Cannot set the property value

PsRetPropertyPointerIsNull: The input property value buffer pointer is null

PsRetPropertySizeNotEnough: The input property value buffer size is not enough to store the returned property value

PsRetInvalidDepthRange: The input depth range mode is invalid

PsRetReadNextFrameError: Error when capturing the next image frame

PsRetCameraNotOpened: Camera is not opened

PsRetInvalidCameraType: The type of camera is invalid



PsRetInvalidParams: Parameter is invalid

PsRetCurrentVersionNotSupport: This feature is not supported in the current version

PsRetUpgradelmngError : There is an error in the upgrade file

PsRetUpgradelmngPathTooLong: Upgrade file path length greater than 260

PsRetUpgradeCallbackNotSet: Ps2\_SetUpgradeStatusCallback is not called

PsRetNoAdapterConnected: There is no adapter connected

PsRetReinitialized: The SDK has been initialized

PsRetNoInitialized: The SDK has not been initialized

PsRetCameraOpened: The camera has been opened

PsRetCmdError: Set/Get cmd control error

PsRetCmdSyncTimeOut: Set cmd ok, but time out for the sync return

PsRetOthers: Other error

### 5.1.8. PsWDRTotalRange

#### Description:

Count of ranges alternatively output in WDR mode.

#### Enumerator:

PsWDRTotalRange\_Two: like Near/Far/Near/Far...

PsWDRTotalRange\_Three: like Near/Mid/Far/Near/Mid/Far...

### 5.1.9. PsWDRStyle

**Description:**

WDR style setting used for API PsSetWDRStyle, which determine WDR image output is fusion from multi range (e.g. Near/Far) or output alternatively (e.g. Near/Far/Near/Far...)

**Enumerator:**

PsWDR\_FUSION: WDR image output is fusion from multi range

PsWDR\_ALTERNATION: WDR image output alternatively(e.g. Near/Far/Near/Far...)

### 5.1.10. PsResolution

**Description:**

Rgb frame resloution

**PS:** some model may not support RGB, such as DCAM550.some model may has the different RGB Resolution, such as DCAM560CPRO. Please refer to the definition under the specific model folder in include.

**Enumerator:**

PsRGB\_Resolution\_1920\_1080: 1080P

PsRGB\_Resolution\_1280\_720: 720P

PsRGB\_Resolution\_640\_480: 480P

PsRGB\_Resolution\_640\_360: 360P

## 5.2. Struct Type

### 5.2.1. PsRGB888Pixel

**Description:**

Color image pixel type in 24-bit RGB format

**PS:** some model may not support RGB, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Members:**

r: red

g: green

b: blue

### 5.2.2. PsBGR888Pixel

**Description:**

Color image pixel type in 24-bit BGR format

**PS:** some model may not support RGB, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Members:**

b: blue

g: green

b: blue

### 5.2.3. PsVector3f

**Description:**

Vector for float data, it is the point value of world axis and the unit is mm.

**Members:**

float x, y, z

### 5.2.4. PsDepthVector3

**Description:**

Depth Image Coordination Vector, it the point value of image axis.

**Members:**

depthX: x in pixel

depthY: y in pixel

depthZ: z in mm

### 5.2.5. PsCameraParameters

**Description:**

Parameters of camera

**Members:**

fx: Focal length x (pixel)

fy: Focal length y (pixel)

cx: Principal point x (pixel)

cy: Principal point y (pixel)

k1: Radial distortion coefficient, 1st-order

k2: Radial distortion coefficient, 2nd-order

p1: Tangential distortion coefficient

p2: Tangential distortion coefficient

k3: Radial distortion coefficient, 3rd-order

k4: Radial distortion coefficient, 4st-order

k5: Radial distortion coefficient, 5nd-order

k6: Radial distortion coefficient, 6rd-order

## 5.2.6. PsCameraExtrinsicParameters

### Description:

Camera extrinsic parameters, it is used for mapping between the depth image and rgb image. The formula is:

$$\begin{bmatrix} x_{rgb} \\ y_{rgb} \\ z_{rgb} \end{bmatrix} = \begin{bmatrix} r0 & r1 & r2 \\ r3 & r4 & r5 \\ r6 & r7 & r8 \end{bmatrix} \times \begin{bmatrix} x_{depth} \\ y_{depth} \\ z_{depth} \end{bmatrix} + \begin{bmatrix} t0 \\ t1 \\ t2 \end{bmatrix}$$

### Members:

rotation[9]: 3x3 rotation matrix

translation[3]: 3×1 translation matrix

## 5.2.7. PsFrame

### Description:

The image information

### Members:

frameIndex: Frame index

frameType: type of frame

pixelFormat: Pixel type

imuFrameNo: Used to synchronize with IMU

pFrameData: frame data

dataLen: Length of data

exposureTime: exposure time(ms)

depthRange: Depth range of current frame, only for depth frame

width: width of the image

height: height of the image

### 5.2.8. PsWDROutputMode

#### Description:

Parameters of camera

#### Members:

totalRange: Currently only 2 or 3 ranges output setting supported

range1: First range

range1Count: Count of successive range1 frame

range2: Second range

range2Count: Count of successive range2 frame

range3: Third range, only take effect when totalRange is set to 3

range3Count: Count of successive range3 frame

### 5.2.9. PsMeasuringRange

#### Description:

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Measuring range of camera

**Members:**

depthMode :0(near/mid/far) 1(xnear/xmid/xfar) 2 (xxnear/xxmid/xxfar)

depthMaxNear:the max depth value,in near range ,in “depthMode”

depthMaxMid:the max depth value,in mid range ,in “depthMode”

depthMaxFar:the max depth value,in far range ,in “depthMode”

effectDepthMaxNear:the effect max depth value,in near range ,in “depthMode”

effectDepthMaxMid:the effect max depth value,in mid range ,in “depthMode”

effectDepthMaxFar:the effect max depth value,in far range ,in “depthMode”

effectDepthMinNear:the effect min depth value,in near range ,in “depthMode”

effectDepthMinMid:the effect min depth value,in mid range ,in “depthMode”

effectDepthMinFar:the effect min depth value,in far range ,in “depthMode”

## 5.2.10. PsDeviceInfo

**Description:**

The information of device

**Members:**

SessionCount:the count of session

devicetype:the type of device

uri:the identification of device

fw:the firmware version

status:the connect status

## 5.2.11. PsDataModeList

### Description:

The supportive datamode list of camera

### Members:

index:fixed value 0x00

count: the count of datamode that supported

datamodelist:the list of datamode that supported

## 5.2.12. PsDepthRangeList

### Description:

The supportive depthrange list of camera

### Members:

index:fixed value 0x01

count: the count of depthrange that supported

depthrangelist:the list of depthrange that supported

## 5.2.13. PsFrameReady

### Description:

The flg of the ready frame.1:available,0: unavailable

**PS:** the image types available for different models of products are different. Please refer to the definition under the specific model folder in the include.

### Members:



depth:flg of the ready depth frame

ir:flg of the ready ir frame

rgb:flg of the ready RGB frame

mappedRGB:flg of the ready mappedRGB frame

mappedDepth:flg of the ready mappedDepth frame

mappedIR:flg of the ready mappedIR frame

confidence:flg of the ready confidence frame

wdrDepth:flg of the ready wdrdepth frame

reserved:not used

## 5.2.14. PsWDRConfidenceThreshold

### Description:

The WDR Condifence Threshold

### Members:

threshold1: The confidence threshold of the first range.

threshold2: The confidence threshold of the second range.

threshold3: The confidence threshold of the third range.

## 5.3. API

### 5.3.1. Ps2\_Initialize

#### Prototype:

```
PsReturnStatus Ps2_Initialize()
```

#### Description:

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Initialize Vzense SDK. It should be called first before calling any other API

**Parameters:**

None

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.2. Ps2\_Shutdown

**Prototype:**

```
PsReturnStatus Ps2_Shutdown()
```

**Description:**

Shutdown the Vzense SDK. It is forbidden to call any other SDK API after the PsShutdown is called.

**Parameters:**

None

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.3. Ps2\_GetDeviceCount

**Prototype:**

```
PsReturnStatus Ps2_GetDeviceCount(int32_t* pDeviceCount)
```

**Description:**

Get the connected device count.

**Parameters:**

pDeviceCount **[out]**:The pointer to the variable that need to store the returned device count. It needs to create an int variable first and then pass its pointer to this function.

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**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.4. Ps2\_GetDeviceListInfo

**Prototype:**

```
PsReturnStatus Ps2_GetDeviceListInfo(PsDeviceInfo* pDevicesList,  
uint32_t deviceCount)
```

**Description:**

Get the info list of devices currently connected

**Parameters:**

deviceCount[in]: the count of devices

pDevicesList[out]: The pointer to the variable that need to store the returned devices info.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.5. Ps2\_GetDeviceInfo

**Prototype:**

```
PsReturnStatus Ps2_GetDeviceInfo(PsDeviceInfo* pDevices,  
uint32_t deviceIndex)
```

**Description:**

Get the info of the device which index is deviceIndex

**Parameters:**

deviceIndex[in]: the index of device

pDevices[out]: The pointer to the variable that need to store the returned

device info.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.6. Ps2\_OpenDevice

**Prototype:**

```
PsReturnStatus Ps2_OpenDevice(const char* uri, PsDeviceHandle *pDevice)
```

**Description:**

Open the specific device indicated by uri and return the device handle.

**Parameters:**

uri[in]: the Identifier of device

pDevice[out]: The handle of the device

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.7. Ps2\_CloseDevice

**Prototype:**

```
PsReturnStatus Ps2_CloseDevice(PsDeviceHandle* device)
```

**Description:**

Close the specific device indicated by pDevice.

**Parameters:**

device[in]: The device handle.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.8. Ps2\_StartStream

**Prototype:**

```
PsReturnStatus Ps2_StartStream(PsDeviceHandle device,  
  
uint32_t sessionIndex)
```

**Description:**

Start to capture the specific session stream indicated by device and sessionIndex.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: The index of the session that include N TOF sensors and maximum N RGB sensors.range from 0 to ::SessionCount - 1. See ::PsDeviceInfo for more information. For example, the camera has 2 TOF sensor and 1 RGB sensor, the ::SessionCount is 2.If the sessionIndex is 0 mean that start 1 TOF stream and the RGB stream, and if the sessionIndex is 1 mean that start only 1 TOF stream.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.9. Ps2\_StopStream

**Prototype:**

```
PsReturnStatus Ps2_StopStream(int32_t deviceIndex,  
  
PsFrameType frameType)
```

**Description:**

Stop to capture the specific session stream indicated by device and sessionIndex.

**Parameters:**

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**device[in]:** The device handle.

**sessionIndex[in]:** The index of the session that include N TOF sensors and maximum N RGB sensors.range from 0 to ::SessionCount - 1. See ::PsDeviceInfo for more information. For example, the camera has 2 TOF sensor and 1 RGB sensor, the ::SessionCount is 2.If the sessionIndex is 0 mean that stop 1 TOF stream and the RGB stream, and if the sessionIndex is 1 mean that stop only 1 TOF stream.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.10. Ps2\_ReadNextFrame

**Prototype:**

```
PsReturnStatus Ps2_ReadNextFrame(PsDeviceHandle device,
    uint32_t sessionIndex, PsFrameReady* pFrameReady)
```

**Description:**

Capture the next image frame of the specific device. This API should be called

first before getting the frame data using Ps2\_GetFrame.

**Parameters:**

**device[in]:** The device handle.

**sessionIndex[in]:** the session index. see Ps2\_StartStream Ps2\_StopStream for more info.

**pFrameReady[out]:** the flg of ready frame, see Ps2\_FrameReady for more info.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.11. Ps2\_GetFrame

**Prototype:**

```
PsReturnStatus Ps2_GetFrame(PsDeviceHandle device, uint32_t sessionIndex,  
  
PsFrameType frameType, PsFrame* pPsFrame)
```

**Description:**

Get the image data of current frame indicated by frame type. It needs to call Ps2\_ReadNextFrame to capture one frame of image first before calling this API.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

frameType[in]: the frame type.see PsFrameType for more info.

pPsFrame[out]: The pointer of buffer to store the returned image data.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.12. Ps2\_SetDataMode

**Prototype:**

```
PsReturnStatus Ps2_SetDataMode(PsDeviceHandle device,  
  
uint32_t sessionIndex, PsDataMode dataMode)
```

**Description:**

Set the output data mode

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

dataMode[in]: output data mode, refer to PsDataMode

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.13. Ps2\_GetDataMode

**Prototype:**

```
PsReturnStatus Ps2_GetDataMode(PsDeviceHandle device,  
                                uint32_t sessionIndex, PsDataMode* dataMode)
```

**Description:**

Set the output data mode

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

dataMode[out]: output data mode, refer to PsDataMode

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.14. Ps2\_GetDepthRange

**Prototype:**

```
PsReturnStatus Ps2_GetDepthRange(PsDeviceHandle device,
```



uint32\_t sessionIndex, PsDepthRange\* pDepthRange)

**Description:**

Get the depth range mode of the specific device.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pDepthRange [out]: The pointer of variable to store the returned depth range mode. Refer to PsDepthRange.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.15. Ps2\_SetDepthRange

**Prototype:**

PsReturnStatus Ps2\_SetDepthRange(PsDeviceHandle device,  
uint32\_t sessionIndex, PsDepthRange depthRange)

**Description:**

Set the depth range mode of the specific device.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

depthRange [in]: The depth range that needs to set. Refer to PsDepthRange.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.16. Ps2\_GetThreshold

#### Prototype:

```
PsReturnStatus Ps2_GetThreshold(PsDeviceHandle device,  
  
uint32_t sessionIndex, uint16_t * pThreshold)
```

#### Description:

Get the threshold value of depth image

#### Parameters:

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pThreshold [out]: the threshold value

#### Returns:

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.17. Ps2\_SetThreshold

#### Prototype:

```
PsReturnStatus Ps2_SetThreshold(PsDeviceHandle device,  
  
uint32_t sessionIndex, uint16_t threshold)
```

#### Description:

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Set the threshold value of depth image

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pThreshold [in]: the threshold value

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.18. Ps2\_GetPulseCount

**Prototype:**

```
PsReturnStatus Ps2_GetPulseCount(PsDeviceHandle device,  
uint32_t sessionIndex, uint16_t pPulseCount)
```

**Description:**

Get the pulse count of depth image, PulseCount is used for exposure.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pPulseCount [out]: pointer to the variable that used to store returned pulse count

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.19. Ps2\_SetPulseCount

#### Prototype:

```
PsReturnStatus Ps2_SetPulseCount(PsDeviceHandle device,  
    uint32_t sessionIndex, uint16_t pulseCount)
```

#### Description:

Set the pulse count of depth image, PulseCount is used for exposure.

#### Parameters:

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pPulseCount [in]: the pulse count value

#### Returns:

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.20. Ps2\_GetGMMGain

#### Prototype:

```
PsReturnStatus Ps2_GetGMMGain(PsDeviceHandle device,  
    uint32_t sessionIndex, uint16_t* gmmgain)
```

#### Description:

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Get Gamma gain of depth image

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

gmmgain[out]: To store the returned Gamma value variable pointer, you need to first create an unsigned short type variable and pass its pointer to the function

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.21. Ps2\_SetGMMGain

**Prototype:**

```
PsReturnStatus Ps2_SetGMMGain(PsDeviceHandle device,  
  
uint32_t sessionIndex, uint16_t* gmmgain)
```

**Description:**

Set Gamma gain of depth image

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

gmmgain [in]: Gamma gain to be set

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

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### 5.3.22. Ps2\_GetProperty

**Prototype:**

```
PsReturnStatus Ps2_GetProperty(PsDeviceHandle device,  
  
uint32_t sessionIndex, PsPropertyType propertyType,  
  
void* pData, int32_t* pDataSize)
```

**Description:**

Get the property value of the specific device indicated by deviceIndex.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

propertyType [in]: The property type. Refer to PsPropertyType.

pData [out]: The pointer of buffer to store the returned property value.

pDataSize [in/out]: Pass the buffer size of pData. Also return the actual size of returned property value in byte.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.23. Ps2\_SetProperty

**Prototype:**

```
PsReturnStatus Ps2_SetProperty(PsDeviceHandle device,  
  
uint32_t sessionIndex, PsPropertyType  
propertyType, const void* pData, int32_t dataSize)
```

**Description:**

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Set the property value of the specific device.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

propertyType [in]: The property type. Refer to PsPropertyType.

pData [in]: The pointer of buffer which stores the property value to set.

pDataSize [in]: The property value size.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.24. Ps2\_GetCameraParameters

**Prototype:**

```
PsReturnStatus Ps2_GetCameraParameters(PsDeviceHandle device,  
  
uint32_t sessionIndex, PsSensorType sensorType,  
  
PsCameraParameters* pCameraParameters)
```

**Description:**

Get the camera internal parameters

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

sensorType **[in]** : Type of sensor, 0 indicates the depth camera , 1 indicates the RGB camera

pCameraParameters**[out]**: Output the camera internal parameters, refer to PsCameraParameters

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.25. Ps2\_GetCameraExtrinsicParameters

**Prototype:**

```
PsReturnStatus Ps2_GetCameraExtrinsicParameters(PsDeviceHandle device,  
uint32_t sessionIndex, PsCameraExtrinsicParameters*  
pCameraExtrinsicParameters)
```

**Description:**

Get camera rotation and transmission coefficient parameters

**Parameters:**

device**[in]**: The device handle.

sessionIndex**[in]**: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pCameraExtrinsicParameters **[out]**: Pointer to the structural variable used to store the returned camera parameters

**Returns:**



PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.26. Ps2\_SetColorPixelFormat

#### Prototype:

```
PsReturnStatus Ps2_SetColorPixelFormat(PsDeviceHandle device,  
uint32_t sessionIndex, const PsPixelFormat pixelFormat);
```

#### Description:

Set the format of pixel

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

#### Parameters:

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pixelFormat [in]: format of pixel,

#### Returns:

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.27. Ps2\_SetRGBResolution

#### Prototype:

```
PsReturnStatus Ps2_SetRGBResolution(PsDeviceHandle device,
```

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```
uint32_t sessionIndex,PsResolution resolution);
```

**Description:**

Set RGB resolution

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

resolution[**in**]: RGB resolution,See PsResolution for more info.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.28. Ps2\_GetRGBResolution

**Prototype:**

```
PsReturnStatus Ps2_GetRGBResolution(PsDeviceHandle device,  
  
uint32_t sessionIndex,uint16_t* resolution);
```

**Description:**

Get RGB resolution

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

resolution[**out**]: RGB resolution,See PsResolution for more info.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.29. Ps2\_SetWDROutputMode

**Prototype:**

```
PsReturnStatus Ps2_SetWDROutputMode(PsDeviceHandle device,  
uint32_t sessionIndex, PsWDROutputMode* pWDRMode)
```

**Description:**

Set WDR output mode, refer to PsWDROutputMode

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pWDRMode[**In**]: the WDR output mode, refer to PsWDROutputMode

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.30. Ps2\_GetWDROutputMode

**Prototype:**

```
PsReturnStatus Ps2_GetWDROutputMode(PsDeviceHandle device,  
  
uint32_t sessionIndex, PsWDROutputMode* pWDRMode)
```

**Description:**

Get WDR mode.

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pWDRMode[**Out**]: the WDR mode, refer to PsWDROutputMode

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.31. Ps2\_SetWDRStyle

**Prototype:**

```
PsReturnStatus Ps2_SetWDRStyle(PsDeviceHandle device,  
  
uint32_t sessionIndex, PsWDRStyle wdrStyle)
```

**Description:**

Set output style of WDR mode

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for Vzense Technology, Inc.

more info.

wdrStyle[in]: the output style, in fusion or alternation, refer to PsWDRStyle

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.32. Ps2\_GetMeasuringRange

**Prototype:**

```
PsReturnStatus Ps2_GetMeasuringRange(PsDeviceHandle device,  
  
uint32_t sessionIndex, PsDepthRange depthRange,  
  
PsMeasuringRange* pMeasuringRange)
```

**Description:**

Get Measuring Range

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

depthRange[in]: the depth range.

pMeasuringRange[Out]: the measuring range, refer to PsMeasuringRange

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.33. Ps2\_ConvertWorldToDepth

**Prototype:**

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```
PsReturnStatus Ps_ConvertWorldToDepth(PsDeviceHandle device,  
  
uint32_t sessionIndex, PsVector3f* pWorldVector,  
  
PsDepthVector3* pDepthVector, int32_t pointCount)
```

**Description:**

Convert the input points from the World coordinate system to the Depth coordinate system.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pWorldVector [in]: The pointer to the buffer which stored the x,y,z value of world coordinate of the input points to be converted, measured in millimeters.

pDepthVect [out]: The pointer to the buffer to store the output x,y,z value of depth coordinate. (x,y) is measured in pixels with (0,0) at the top left of the image. z is measured in millimeters, it is the depth value of the point to be converted.

pointCount [in]: The point count to be converted.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.34. Ps2\_ConvertDepthToWorld

**Prototype:**

```
PsReturnStatus Ps_2ConvertDepthToWorld(PsDeviceHandle device,  
  
uint32_t sessionIndex, PsDepthVector3* pDepthVector,  
  
PsVector3f* pWorldVector, int32_t pointCount)
```

**Description:**

Vzense Technology, Inc.

Convert the input points from the Depth coordinate system to the World coordinate system.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pDepthVect [in]: The pointer to the buffer to store the output x,y,z value of depth coordinate. (x,y) is measured in pixels with (0,0) at the top left of the image. z is measured in millimeters, it is the depth value of the point to be converted.

pWorldVector [out]: The pointer to the buffer which stored the x,y,z value of world coordinate of the input points to be converted, measured in millimeters.

pointCount [in]: The point count to be converted.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.35. Ps2\_ConvertDepthFrameToWorldVector

**Prototype:**

```
PsReturnStatus Ps_2ConvertDepthFrameToWorldVector(PsDeviceHandle
device, uint32_t sessionIndex, const PsFrame& depthFrame,
PsVector3f* pWorldVector)
```

**Description:**

Convert all points in depthframe from the Depth coordinate system to the World coordinate system.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

depthFrame[in]: The depth frame.

pWorldVector[out]: The pointer to the buffer which stored the x,y,z value of world coordinate of the input points to be converted, measured in millimeters.

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.36. Ps2\_SetSynchronizeEnable

**Prototype:**

```
PsReturnStatus Ps2_SetSynchronizeEnabled (PsDeviceHandle device,  
uint32_t sessionIndex,, bool bEnabled)
```

**Description:**

Set whether the output RGB, Depth, IR and other images are synchronized in time

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: True is set to synchronize and false is set to asynchronize

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7



### 5.3.37. Ps2\_GetSynchronizeEnable

**Prototype:**

```
PsReturnStatus Ps2_GetSynchronizeEnabled (PsDeviceHandle device,  
  
uint32_t sessionIndex,, bool* bEnabled)
```

**Description:**

Get whether the output RGB, Depth, IR and other images are synchronized in time

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [**out**]: True is set to synchronize and false is set to asynchronize

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section5.1.7

### 5.3.38. Ps2\_SetDepthDistortionCorrectionEnabled

**Prototype:**

```
PsReturnStatus Ps2_SetDepthDistortionCorrectionEnabled(PsDeviceHandle  
  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Set to enable or disable the Depth distortion correction feature

**Parameters:**

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device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.39. Ps2\_GetDepthDistortionCorrectionEnabled

**Prototype:**

```
PsReturnStatus Ps2_GetDepthDistortionCorrectionEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool* bEnabled)
```

**Description:**

Get the Depth distortion correction feature, enable or disable

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [out]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.40. Ps2\_SetIrrDistortionCorrectionEnabled

**Prototype:**

```
PsReturnStatus Ps2_SetIrrDistortionCorrectionEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Set to enable or disable the IR distortion correction feature

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index. see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.41. Ps2\_GetIrrDistortionCorrectionEnabled

**Prototype:**

```
PsReturnStatus Ps2_GetIrrDistortionCorrectionEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool* bEnabled)
```

**Description:**

Get the IR distortion correction feature, enable or disable

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [out]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.42. Ps2\_SetRGBDistortionCorrectionEnabled

**Prototype:**

```
PsReturnStatus Ps_SetRGBDistortionCorrectionEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Set to enable or disable the RGB distortion correction feature

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

**5.3.43. Ps2\_GetRGBDistortionCorrectionEnabled****Prototype:**

```
PsReturnStatus Ps_GetRGBDistortionCorrectionEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool* bEnabled)
```

**Description:**

Get the RGB distortion correction feature, enable or disable

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [out]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

**5.3.44. Ps2\_SetComputeRealDepthCorrectionEnabled****Prototype:**

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PsReturnStatus **Ps2\_SetComputeRealDepthCorrectionEnabled**

(PsDeviceHandle device, uint32\_t sessionIndex, bool bEnabled)

**Description:**

Set to enable or disable the computer real depth correction feature

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.45. Ps2\_GetComputeRealDepthCorrectionEnabled

**Prototype:**

PsReturnStatus **Ps2\_GetComputeRealDepthCorrectionEnabled**

(PsDeviceHandle device, uint32\_t sessionIndex, bool\* bEnabled)

**Description:**

Set the computer real depth correction feature,enable or disable.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for

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more info.

bEnabled **[out]**: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.46. Ps2\_SetSpatialFilterEnabled

**Prototype:**

```
PsReturnStatus Ps_SetSpatialFilterEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Set to enable or disable the Spatial Filter feature

**Parameters:**

device**[in]**: The device handle.

sessionIndex**[in]**: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled **[in]**: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.47. Ps2\_GetSpatialFilterEnabled

**Prototype:**

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```
PsReturnStatus Ps_GetSpatialFilterEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Get the Spatial Filter feature,enable or disable

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [**out**]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.48. Ps2\_SetTimeFilterEnabled

**Prototype:**

```
PsReturnStatus Ps_SetTimeFilterEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Set to enable or disable the Time Filter feature

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for



more info.

bEnabled **[in]**: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.49. Ps2\_GetTimeFilterEnabled

**Prototype:**

```
PsReturnStatus Ps_GetTimeFilterEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Get the Time Filter feature,enable or disable

**Parameters:**

device**[in]**: The device handle.

sessionIndex**[in]**: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled **[out]**: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.50. Ps2\_SetDepthFrameEnabled

**Prototype:**

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```
PsReturnStatus Ps2_SetDepthFrameEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Enables or disables the Depth stream feature

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.51. Ps2\_SetIrFrameEnabled

**Prototype:**

```
PsReturnStatus Ps2_SetIrFrameEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Enables or disables the IR stream feature

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for

more info.

bEnabled **[in]**: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.52. Ps2\_SetRgbFrameEnabled

**Prototype:**

```
PsReturnStatus Ps2_SetRgbFrameEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Enables or disables the RGB stream feature

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device**[in]**: The device handle.

sessionIndex**[in]**: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled **[in]**: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.53. Ps2\_SetImageMirror

**Prototype:**

```
PsReturnStatus Ps2_SetImageMirror(PsDeviceHandle device, uint32_t  
sessionIndex, int32_t type)
```

**Description:**

Set image mirror

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

type[in]: 1 left-right mirror; 2 up-down mirror;3 both mirror (rotation 180)

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.54. Ps2\_SetImageRotation

**Prototype:**

```
PsReturnStatus Ps2_SetImageRotation(PsDeviceHandle device, uint32_t  
sessionIndex, int32_t type)
```

**Description:**

Set image mirror

**Parameters:**

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device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

type[in]: 0 counterclock 906y; 1 counterclock 1806y;2 counterclock 2706y

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.55. Ps2\_SetMapperEnabledDepthToRGB

**Prototype:**

```
PsReturnStatus Ps2_SetMappedEnabledDepthToRGB(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Set to enable or disable the feature of mapping RGB image to depth camera space,if this feature is enabled, the mapped RGB image can be get through PsGetFrame with input frame type "PsMappedRGBFrame"

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

**5.3.56. Ps2\_GetMapperEnabledDepthToRGB****Prototype:**

```
PsReturnStatus Ps2_GetMappedEnabledDepthToRGB(PsDeviceHandle  
device, uint32_t sessionIndex, bool* bEnabled)
```

**Description:**

Get the feature of mapping RGB image to depth camera space, if this feature is enabled, the mapped RGB image can be get through PsGetFrame with input frame type "PsMappedRGBFrame"

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index. see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [out]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.57. Ps2\_SetMapperEnabledRGBToDepth

#### Prototype:

```
PsReturnStatus Ps2_SetMappedEnabledRGBToDepth(int32_t deviceIndex, bool  
bEnabled)
```

#### Description:

Set to enable or disable the feature of mapping depth image to RGB camera space, if this feature is enabled, the mapped depth image can be get through PsGetFrame with input frame type "PsMappedDepthFrame"

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

#### Parameters:

device[in]: The device handle.

sessionIndex[in]: the session index. see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature

#### Returns:

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.58. Ps2\_GetMapperEnabledRGBToDepth

#### Prototype:

```
PsReturnStatus Ps2_GetMappedEnabledRGBToDepth(int32_t deviceIndex,
```

bool\* bEnabled)

**Description:**

Get the feature of mapping depth image to RGB camera space,if this feature is enabled, the mapped depth image can be get through PsGetFrame with input frame type "PsMappedDepthFrame"

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [out]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.59. Ps2\_SetHotPlugStatusCallback

**Prototype:**

```
PsReturnStatus Ps2_SetHotPlugStatusCallback(PtrHotPlugStatusCallback  
pCallback)
```

**Description:**

Set the callbcak function

**Parameters:**

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pCallback[in]: The Callback function

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.60. Ps2\_SetHotPlugStatusCallback\_

**Prototype:**

```
PsReturnStatus Ps2_SetHotPlugStatusCallback_(PtrHotPlugStatusCallback_  
pCallback, void* contex)
```

**Description:**

Set the callbcak function for c++

**Parameters:**

pCallback[in]: The Callback function

contex[in]: Pointer to the object of C++ class

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.61. Ps2\_GetWDRPulseCount

**Prototype:**

```
PsReturnStatus Ps2_GetWDRPulseCount(PsDeviceHandle device, uint32_t  
sessionIndex, PsWDRPulseCount* pwdrPulseCount)
```

**Description:**

Vzense Technology, Inc.

Get the pulsecount in WDR mode

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

pwdrPulseCount[out]: the pulsecount value

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.62. Ps2\_SetWDRPulseCount

**Prototype:**

```
PsReturnStatus Ps2_SetWDRPulseCount(PsDeviceHandle device, uint32_t  
sessionIndex, PsWDRPulseCount wdrPulseCount)
```

**Description:**

Set the pulsecount in WDR mode

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

wdrPulseCount[in]: the pulsecount value

**Returns:**

PsRetOK: Succeed

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Others: Failed. Reference to section 5.1.7

### 5.3.63. Ps2\_GetSerialNumber

#### Prototype:

```
PsReturnStatus Ps2_GetSerialNumber(PsDeviceHandle device, uint32_t  
sessionIndex, char* sn,int length)
```

#### Description:

Get the serial number

#### Parameters:

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

sn[out]: the sn value

length[in]: The max length is 63.

#### Returns:

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.64. Ps2\_GetFirmwareVersionNumber

#### Prototype:

```
PsReturnStatus Ps2_GetFirmwareVersionNumber(PsDeviceHandle device,  
uint32_t sessionIndex, char* fw,int length)
```

#### Description:

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Get the firmware version number

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

fw[out]: the fw value

length[in]: The max length is 63.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.65. Ps2\_SetDSPEnabled

**Prototype:**

```
PsReturnStatus Ps2_SetDSPEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Enables or disables the DSP feature for tof frame.

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled **[in]**: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.66. Ps2\_GetDSPEnabled

**Prototype:**

```
PsReturnStatus Ps2_GetDSPEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool* bEnabled)
```

**Description:**

Returns the Boolean value of whether the DSP feature is enabled or disabled

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device**[in]**: The device handle.

sessionIndex**[in]**: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled **[out]**: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.67. Ps2\_SetSlaveModeEnabled

**Prototype:**

```
PsReturnStatus Ps2_SetSlaveModeEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Enables or disables the SlaveMode feature

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.68. Ps2\_SetTofFrameRate

**Prototype:**

```
PsReturnStatus Ps2_SetTofFrameRate(PsDeviceHandle device, uint32_t  
sessionIndex, uint8_t value)
```

**Description:**

Sets the tof frame rate

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

value[in]: the value of rate,in 3,5,6,10,15,30.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.69. Ps2\_GetTofFrameRate

**Prototype:**

```
PsReturnStatus Ps2_GetTofFrameRate(PsDeviceHandle device, uint32_t  
sessionIndex, uint8_t* value)
```

**Description:**

Get the tof frame rate

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

value[out]: the value of rate

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.70. Ps2\_SetStandByEnabled

**Prototype:**

```
PsReturnStatus Ps2_SetStandByEnabled(PsDeviceHandle  
  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Enables or disables the StandBy feature

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.71. Ps2\_OpenDeviceByAlias

**Prototype:**

```
PsReturnStatus Ps2_OpenDeviceByAlias(const char* alias,  
  
PsDeviceHandle *pDevice)
```

**Description:**

Open the specific device indicated by alias and return the device handle.

**Parameters:**

alias [in]: the alias of device



pDevice[out]: The handle of the device

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.72. Ps2\_SetWaitTimeOfReadNextFrame

**Prototype:**

```
PsReturnStatus Ps2_SetWaitTimeOfReadNextFrame(PsDeviceHandle device,  
uint32_t sessionIndex, uint16_t time)
```

**Description:**

Set the waittime of read next frame

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

time[in]:the waittime

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.73. Ps2\_GetSDKVersion

**Prototype:**

```
PsReturnStatus Ps2_GetSDKVersion(char* version, int length)
```

**Description:**

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Get the version of SDK

**Parameters:**

version[**out**]: the SDK version

length[**in**]: The max length is 63.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.74. Ps2\_GetMappedPointDepthToRGB

**Prototype:**

```
PsReturnStatus Ps2_GetMappedPointDepthToRGB(const PsDeviceHandle  
device, const uint32_t sessionIndex, const PsDepthVector3 depthPoint, const  
PsVector2u16 rgbSize, PsVector2u16* pPosInRGB)
```

**Description:**

Get the point value of the frame that the mapping of the depth image to RGB space

**PS:** some model may not support the API, such as DCAM550. Please refer to the definition under the specific model folder in include.

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

depthPoint[**in**]: the point in Depth frame

rgbSize[**in**]: the size of RGB frame

pPosInRGB [**out**]: the point value

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.75. Ps2\_SetSlaveTrigger

**Prototype:**

```
PsReturnStatus Ps2_SetSlaveTrigger(PsDeviceHandle device, uint32_t  
sessionIndex)
```

**Description:**

Trigger frame data once in slave mode

**PS:** some model may not support the API, such as DCAM710. Please refer to the definition under the specific model folder in include.

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.76. Ps2\_GetDeviceIP

**Prototype:**

```
PsReturnStatus Ps2_GetDeviceIP(const char* uri, char* ip)
```

**Description:**

Get the IP of the series device of the DCAM560

**Parameters:**

uri[**in**]: the Identifier of device

ip[**out**]: the ip value, the buffer default size is 17, and the last buffer set '\0'.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.77. Ps2\_GetDeviceMAC

**Prototype:**

```
PsReturnStatus Ps2_GetDeviceMAC(PsDeviceHandle device, uint32_t  
sessionIndex, char* mac)
```

**Description:**

Get the MAC of the series device of the DCAM560

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for

more info.

mac[out]: the mac value, the buffer default size is 18, and the last buffer set '\0'.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.78. Ps2\_SetRGBBrightness

**Prototype:**

```
PsReturnStatus Ps2_SetRGBBrightness(PsDeviceHandle device, uint32_t  
sessionIndex, char value)
```

**Description:**

Set the RGB brightness of the series device of the DCAM560

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

value[in]: the brightness value, in [-64,64]

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.79. Ps2\_GetRGBBrightness

**Prototype:**

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```
PsReturnStatus Ps2_GetRGBBrightness(PsDeviceHandle device, uint32_t  
sessionIndex, char* value)
```

**Description:**

Get the RGB brightness of the series device of the DCAM560

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

value[out]: the brightness value, in [-64,64]

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.80. Ps2\_SetRGBAutoExposure

**Prototype:**

```
PsReturnStatus Ps2_SetRGBAutoExposure(PsDeviceHandle device, uint32_t  
sessionIndex, uint8_t value)
```

**Description:**

Set the RGB auto exposure of the series device of the DCAM560

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

value[in]: the brightness value, in [1,30] and the unit is 1ms

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.81. Ps2\_GetRGBAutoExposure

**Prototype:**

```
PsReturnStatus Ps2_GetRGBAutoExposure(PsDeviceHandle device, uint32_t  
sessionIndex, uint8_t* value)
```

**Description:**

Get the RGB auto exposure of the series device of the DCAM560

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

value[out]: the brightness value, in [1,30] and the unit is 1ms

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.82. Ps2\_RebootCamera

**Prototype:**

```
PsReturnStatus Ps2_RebootCamera(PsDeviceHandle device, uint32_t
```

sessionIndex)

**Description:**

Reboot the Camera

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.83. Ps2\_SetLegacyAlgorithmicEnabled

**Prototype:**

```
PsReturnStatus Ps_SetLegacyAlgorithmicEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Set to enable or disable the Legacy Algorithmic feature, default disable

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature



**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

**5.3.84. Ps2\_SetConfidenceFilterEnabled****Prototype:**

```
PsReturnStatus Ps_SetConfidenceFilterEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool bEnabled)
```

**Description:**

Set to enable or disable the Confidence Filter feature

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [in]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

**5.3.85. Ps2\_GetConfidenceFilterEnabled****Prototype:**

```
PsReturnStatus Ps_GetConfidenceFilterEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool* bEnabled)
```

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**Description:**

Get the Confidence Filter feature,enable or disable

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

bEnabled [out]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

## 5.3.86. Ps2\_SetConfidenceFilterThreshold

**Prototype:**

```
PsReturnStatus Ps2_SetConfidenceFilterThreshold(PsDeviceHandle device,  
uint32_t sessionIndex, uint16_t threshold)
```

**Description:**

Set the Confidence Filter threshold value of depth image

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

threshold [in]: the threshold value

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

**5.3.87. Ps2\_GetConfidenceFilterThreshold****Prototype:**

```
PsReturnStatus Ps2_GetConfidenceFilterThreshold(PsDeviceHandle device,  
uint32_t sessionIndex, uint16_t * threshold)
```

**Description:**

Get the Confidence Filter threshold value of depth image

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

threshold[out]: the threshold value

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

**5.3.88. Ps2\_SeWDRConfidenceFilterThreshold****Prototype:**

```
PsReturnStatus Ps2_SetWDRConfidenceFilterThreshold(PsDeviceHandle
```

device, uint32\_t sessionIndex, PsWDRConfidenceThreshold  
wdrconfidencethreshold)

**Description:**

Set the WDR Confidence Filter threshold value of depth image

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

wdrconfidencethreshold[in]: the threshold value

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.89. Ps2\_GetWDRConfidenceFilterThreshold

**Prototype:**

```
PsReturnStatus Ps2_GetWDRConfidenceFilterThreshold(PsDeviceHandle  
device, uint32_t sessionIndex, PsWDRConfidenceThreshold  
*wdrconfidencethreshold)
```

**Description:**

Get the WDR Confidence Filter threshold value of depth image

**Parameters:**

device[in]: The device handle.

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sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

wdrconfidencethreshold[out]: the threshold value

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.90. Ps2\_OpenDeviceByIP

**Prototype:**

```
PsReturnStatus Ps2_OpenDeviceByIP(const char* ip,  
  
PsDeviceHandle *pDevice)
```

**Description:**

Open the specific device indicated by IP and return the device handle.

**Parameters:**

ip[in]: the ip of device

pDevice[out]: Thehandle of the device

**Returns:**

PsRetOK: Succeed

Others: Failed, refer to PsReturnStatus. Reference to section 5.1.7

### 5.3.91. Ps2\_SetRGBManualExposureEnabled

**Prototype:**

```
PsReturnStatus Ps_SetRGBManualExposureEnabled(PsDeviceHandle  
  
device, uint32_t sessionIndex, bool enabled)
```

**Description:**

Set to enable or disable the RGB manual exposure feature for the series device of the DCAM560

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

enabled[in]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.92. Ps2\_GetRGBManualExposureEnabled

**Prototype:**

```
PsReturnStatus Ps_GetRGBManualExposureEnabled(PsDeviceHandle  
device, uint32_t sessionIndex, bool* enabled)
```

**Description:**

Get the RGB manual exposure feature,enable or disable.for the series device of the DCAM560

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

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enabled[**out**]: true to enable the feature, false to disable the feature

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.93. Ps2\_SetRGBAbsoluteExposure

**Prototype:**

```
PsReturnStatus Ps2_SetRGBAbsoluteExposure(PsDeviceHandle device,  
uint32_t sessionIndex, uint16_t value)
```

**Description:**

Set the RGB absolute exposure for the series device of the DCAM560

**Parameters:**

device[**in**]: The device handle.

sessionIndex[**in**]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

value[**in**]: the exposure value in [1, 4000] and the unit is 100us.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

### 5.3.94. Ps2\_GetRGBAbsoluteExposure

**Prototype:**

```
PsReturnStatus Ps2_GetRGBAbsoluteExposure(PsDeviceHandle device,  
uint32_t sessionIndex, uint16_t * value)
```

**Description:**

Get the RGB absolute exposure for the series device of the DCAM560

**Parameters:**

device[in]: The device handle.

sessionIndex[in]: the session index.see Ps2\_StartStream Ps2\_StopStream for more info.

value[out]: the exposure value in [1, 4000] and the unit is 100us.

**Returns:**

PsRetOK: Succeed

Others: Failed. Reference to section 5.1.7

## 6. Update Firmware

To upgrade firmware you need the upgrade tool VzenseUpgradeTool, which can be downloaded from the link.

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

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

## 7. APIs example

### 7.1. Initialize normal mode

```
Ps2_Initialize
```

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```
Ps2_GetDeviceCount  
Ps2_GetDeviceListInfo  
Ps2_OpenDevice  
Ps2_StartStream  
While(1)  
{  
    Ps2_ReadNextFrame  
    Ps2_GetFrame  
}  
Ps2_StopStream  
Ps2_CloseDevice  
Ps2_Shutdown
```

## 7.2. Initialize slave mode

```
Ps2_Initialize  
Ps2_GetDeviceCount  
Ps2_GetDeviceListInfo  
Ps2_OpenDevice  
Ps2_StartStream  
Ps2_SetSlaveModeEnabled  
While(1)  
{  
    Ps2_ReadNextFrame  
    Ps2_GetFrame  
}  
Ps2_StopStream  
Ps2_CloseDevice  
Ps2_Shutdown
```

## 7.3. Initialize WDR mode

```
Ps2_Initialize  
  
Ps2_GetDeviceCount  
  
Ps2_GetDeviceListInfo  
  
Ps2_OpenDevice  
  
Ps2_StartStream  
  
Ps2_SetWDROutputMode  
  
Ps2_SetDataMode  
  
Ps2_SetWDRStyle  
  
While(1)  
{  
    Ps2_ReadNextFrame  
    Ps2_GetFrame  
}  
  
Ps2_StopStream  
  
Ps2_CloseDevice  
  
Ps2_Shutdown
```

## 8. FAQ

### 8.1. USB

#### 8.1.1. USB device can not be detected

1. First, make sure the SUB cable can be used for communication.
2. Make sure the USB port of host having enough power to supply, the USB 3.0 port is the recommended choice.
3. If the device manager has one yellow mark on the Vzense USB camera, please use 3<sup>rd</sup> part driver tool to reinstall the UVC driver in system and try again.

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## 8.2. Network

### 8.2.1. SDK cannot open the camera

4. First, make sure whether the camera has been modified with static IP. If you are not sure, open the camera with DHCP, with reference to 3.2.1.2, Otherwise go to the next step.

5. Connect the camera directly to the PC, open the 'network connection' on the control panel, and determine if the Ethernet connection is successful, as shown below. If the Ethernet network connection fails, check whether the physical path is normal and proceed to the next step if the connection is successful

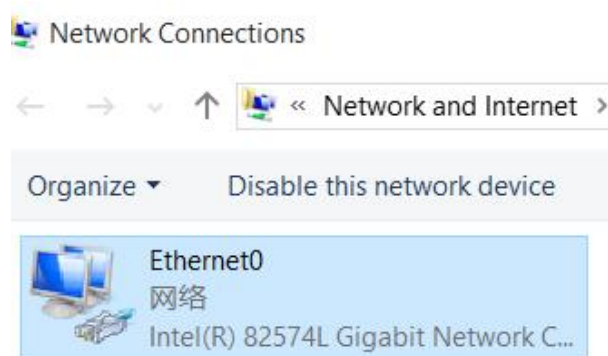


Figure 7.1 network connection

6. Ping the static IP of the camera on the PC side (the default is 192.168.1.101). If it fails, check the IP address configuration of the PC, with reference to 3.2.1.2. If successful, proceed to the next step.

```
C:\Users\Administrator>ping 192.168.1.101

Pinging 192.168.1.101 with 32 bytes of data:
Reply from 192.168.1.100: Destination host unreachable.
Reply from 192.168.1.100: Destination host unreachable.
Reply from 192.168.1.100: Destination host unreachable.
Reply from 192.168.1.100: Destination host unreachable.

Ping statistics for 192.168.1.101:
    Packets: Sent = 4, Received = 4, Lost = 0 (0% loss),
```

Figure 7.2 ping

7. In the 'Windows Defender firewall' of the control panel, click 'allow applications to pass through the firewall' to add firewall access for the SDK.

### Allow apps to communicate through Windows Firewall

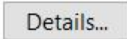
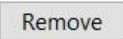
To add, change, or remove allowed apps and ports, click Change settings.

What are the risks of allowing an app to communicate?

 Change settings

Allowed apps and features:

Name	Private	Public
<input checked="" type="checkbox"/> Contact Support	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
<input checked="" type="checkbox"/> Core Networking	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
<input checked="" type="checkbox"/> Delivery Optimization	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
<input checked="" type="checkbox"/> DIAL protocol server	<input checked="" type="checkbox"/>	<input type="checkbox"/>
<input type="checkbox"/> Distributed Transaction Coordinator	<input type="checkbox"/>	<input type="checkbox"/>
<input checked="" type="checkbox"/> Email and accounts	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
<input type="checkbox"/> File and Printer Sharing	<input type="checkbox"/>	<input type="checkbox"/>
<input checked="" type="checkbox"/> frameviewer_dcam800.exe	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
<input checked="" type="checkbox"/> Get Office	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
<input checked="" type="checkbox"/> Get started	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
<input type="checkbox"/> HomeGroup	<input type="checkbox"/>	<input type="checkbox"/>
<input type="checkbox"/> iSCSI Service	<input type="checkbox"/>	<input type="checkbox"/>

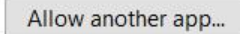


Figure 7.3 firewall setting

Or just turn off the Windows firewall.

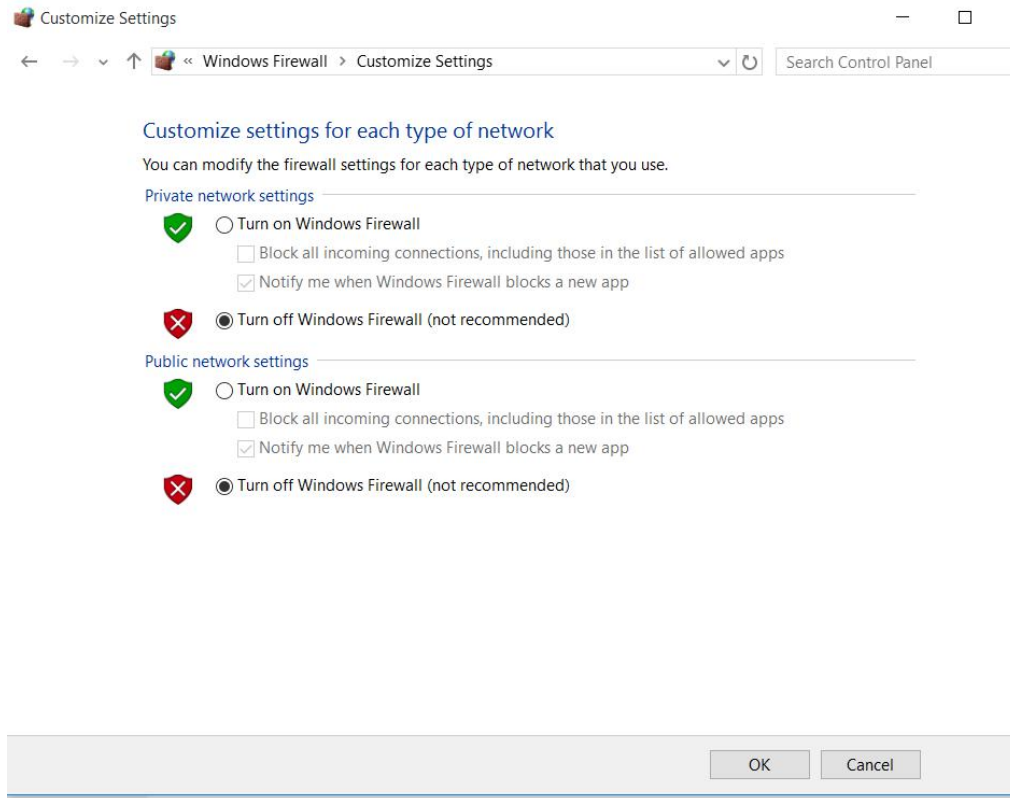


Figure 7.4 close firewall