

Projection

Module `dataset_reader`

Functions

Function `get_bbox`

```
def get_bbox(  
    datasets_folder: str,  
    dataset_name: str,  
    vehicle: str,  
    frame: int,  
    old: bool = True  
) -> bbox.BoundingBox
```

Get the bounding box of a vehicle in a frame

Args

vehicle : str Name of the vehicle (e.g. 'V0')

frame : int Frame to observe

old : bool If True, use the old dataset format

Returns

BoundingBox Bounding box of the vehicle in the frame containing the transformation matrix of the vehicle in the world frame (left handed)

Function `get_camera_matrix`

```
def get_camera_matrix(  
    file_path: str  
) -> numpy.ndarray
```

Get the camera matrix of a camera.

$$k = \begin{pmatrix} 692. & 0. & 692. \\ 0. & 692. & 516. \\ 0. & 0. & 1. \end{pmatrix}$$

Args

file_path : str Path to the camera calibration file

Returns

np.ndarray Camera matrix (3x3)

Function `get_camera_pose`

```
def get_camera_pose(  
    datasets_folder: str,
```

```
    dataset_name: str,  
    vehicle: str,  
    frame: int,  
    old: bool = True  
) -> numpy.ndarray
```

Get the camera pose of a vehicle in a frame

Args

vehicle : str Name of the vehicle (e.g. 'V0')

frame : int Frame to observe

old : bool If True, use the old dataset format

Returns

np.ndarray Transformation matrix from the camera to the vehicle frame (left handed)

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