

Projection

Module `dataset_reader`

Functions

Function `get_bbox`

```
def get_bbox(  
    datasets_folder: str,  
    dataset_name: str,  
    vehicle: str,  
    frame: int  
) -> 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

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  
) -> 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

Returns

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

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