Setting up the Camera

* pipeline = rs.pipeline() 🡪 rs.pipeline
  + Makes a connection with the realsense camera and manages computer vision modules
* pipeline.poll\_for\_frames() 🡪 rs.composite\_frame
  + Checks if a new set of frames is available and retrieve the latest undelivered set
* pipeline.start(config) 🡪 rs.pipeline\_profile
  + starts the pipeline streaming according to the configuration
* pipeline.stop() 🡪 none
  + Stops the pipeline streaming
* pipeline.wait\_for\_frames(timout\_ms) 🡪 rs.composite\_frame
  + Wait until a new set of frames becomes available
* config = rs.config() 🡪 rs.config
  + Configures streams
* config.enable\_stream(rs.stream, width, height, format, frame\_rate) 🡪 None
  + Enables the device stream explicitly and with stated configuration
* config.resolve(rs.pipeline\_wrapper) 🡪 rs.pipeline\_profile
  + Resolve the configuration filters, to find a matching device and streams profiles
* frame = rs.composite\_frame() 🡪rs.composite\_frame()
  + Extends the frame class with additional frameset related attributes and functions
* frame.get\_color\_frame() 🡪 rs.video\_frame
  + Retrieve the first color frame, in no frame is found, search the color frame from IR stream
* frame.get\_depth\_frame() 🡪 rs.depth\_frame
  + Retrieve the first depth frame, if no frame is found, return an empty frame instance
* depth\_frame = rs.depth\_frame() 🡪 rs.depth\_frame
  + Extends the video\_frame class with additional depth related attributes and functions
* depth\_frame.get\_distance(x, y) 🡪 float
  + Provides the depth in meters at the given pixel
* video\_frame = rs.video\_frame() 🡪 rs.video\_frame
  + Extends the frame class with additional video related attributes and functions
* stream = rs.stream() 🡪 rs.stream
  + Streams are different types of data provided by the Realsense devices (ex. color, depth, confidence, fisheye, etc.)
* stream.color
  + Color attribute of stream
* stream.depth
  + Depth attribute of stream