

Recording  
.bag



Velodyne

**ROS**  
Robot Operating System

Import

pointcloudset

Analysis and visualization

**Dataset**  
= multiple point clouds



.las/.laz  
.CSV  
...



Import

**PointCloud**  
= single point cloud

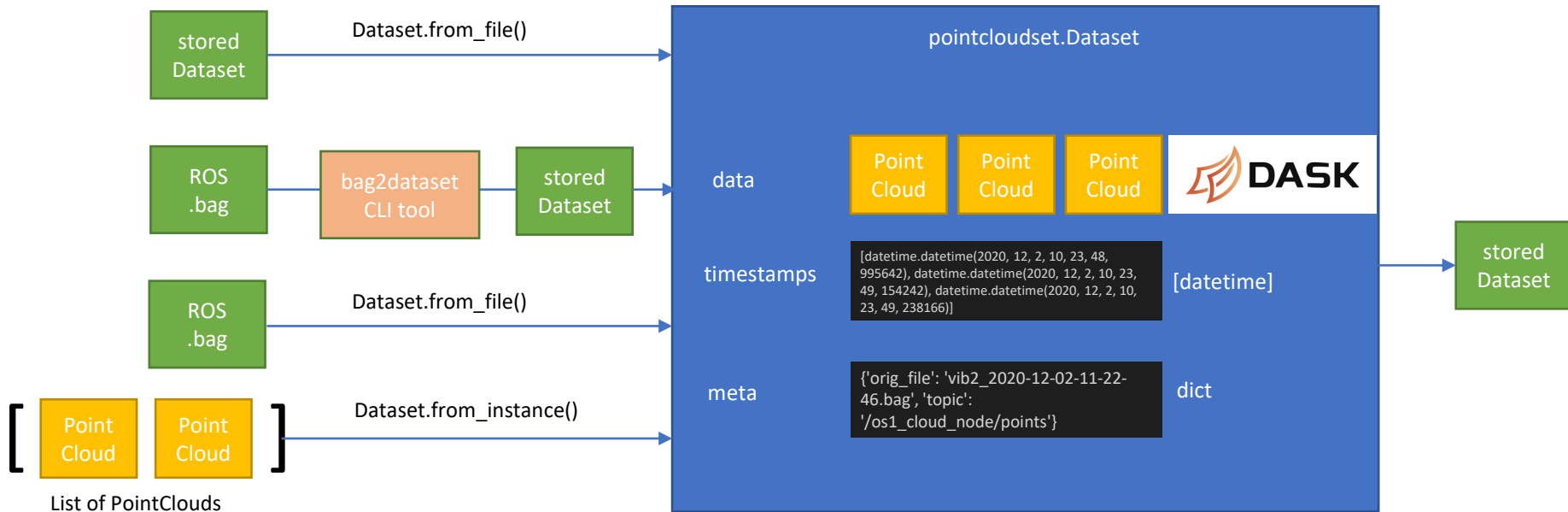
**PointCloud**

**PointCloud**

...

Export


.CSV  
...



.las  
.csv  
And more

PointCloud.from\_file()

pointcloudset.PointCloud

data	 pandas
points	pyntcloud
timestamp	datetime
orig_file	str