



MOILAPP

DISCOVER FISHEYE TECHNOLOGY

Sphinx Documentation

Release 1

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CONTENTS:

1	TEST DOCUMENTATION	1
1.1	Instalataion	1
1.2	Autodock	1
	Python Module Index	3
	Index	4

TEST DOCUMENTATION

1.1 Instalataion

this is how to install

```
(.venv) $ pip install test
```

1.2 Autodock

class test.**AnypointConfig**(*main_ui*)

Bases: object

change_properties_mode_1()

Updates the configuration data for Mode 1 and writes it to the cached file.

This function updates the alpha, beta, and zoom parameters for Mode 1 using the values in the UI double spin boxes. It rounds the zoom value to three decimal places before updating the configuration data. The updated configuration data is then written to the cached file using YAML format.

Returns

None

change_properties_mode_2()

Updates the configuration data for Mode 2 and writes it to the cached file.

This function updates the pitch, yaw, roll, and zoom parameters for Mode 2 using the values in the UI double spin boxes. It creates a list of tuples to store the control names and their corresponding values, and then iterates through the list to update the configuration data for each control. The zoom value is rounded to three decimal places before updating the configuration data. The updated configuration data is then written to the cached file using YAML format.

Returns

None

showing_config_mode_1()

Reads the cached file to load the configuration data for Mode 1.

This function reads the YAML data from the cached file and loads it into the *self.__anypoint_config* attribute. It then sets the values of the zoom, alpha, and beta parameters for Mode 1 in the UI double spin boxes. The function blocks signals while updating the spin box values to prevent recursive updates. Once the values are set, the function unblocks signals.

Returns

None

showing_config_mode_2()

Reads the cached file to load the configuration data for Mode 2.

This function reads the YAML data from the cached file and loads it into the *self.__anypoint_config* attribute. It then sets the values of the pitch, yaw, roll, and zoom parameters for Mode 2 in the UI double spin boxes. The function blocks signals while updating the spin box values to prevent recursive updates. Once the values are set, the function unblocks signals.

Returns

None



Fig. 1: testing

Note: this project is under development.

PYTHON MODULE INDEX

t

test, [1](#)

INDEX

A

`AnypointConfig` (*class in test*), 1

C

`change_properties_mode_1()` (*test.AnypointConfig*
method), 1

`change_properties_mode_2()` (*test.AnypointConfig*
method), 1

M

`module`
`test`, 1

S

`showing_config_mode_1()` (*test.AnypointConfig*
method), 1

`showing_config_mode_2()` (*test.AnypointConfig*
method), 1

T

`test`
`module`, 1