

```

1 '''
2     https://dev.intelrealsense.com/docs/installation (SDK 2.0)
3     conda create -n realsense opencv
4     conda activate realsense
5     pip install pyrealsense2
6     python realsense.py
7 '''
8
9 import cv2
10 import pyrealsense2
11 import numpy as np
12
13 from realsense_depth import *
14
15 def show_distance(event, x, y, args, params):
16     global point
17     point = (x, y)
18
19 dc = DepthCamera()
20 point = (300,200)
21
22 cv2.namedWindow("color frame")
23 cv2.namedWindow("depth frame")
24 #cv2.namedWindow("depth frame normalized")
25 cv2.setMouseCallback("color frame", show_distance)
26
27 ret, depth_frame, color_frame = dc.get_frame()
28 (depth_height, depth_width) = depth_frame.shape
29 print (type(depth_frame), 'height : ', depth_height, ' width : ', depth_width)
30
31 depth_frame_norm = depth_frame.copy()
32
33 #최대 거리값 구하기
34 #max_val = np.amax(depth_frame)
35 #print('max_value : ',max_val)
36
37 while True :
38     ret, depth_frame, color_frame = dc.get_frame()
39
40     '''
41     row = 0
42     while row < depth_height :
43         col = 0
44         while col < depth_width :
45             if depth_frame[row,col] < 1000 :
46                 depth_frame_norm[row,col] = 255
47             else :
48                 depth_frame_norm[row,col] = int(depth_frame[row,col] / 10)
49             #print(depth_frame[row,col])
50             col +=1
51         row +=1
52     '''
53
54     cv2.cvtColor
55     cv2.circle(color_frame, point, 4, (0, 0, 255))
56     distance = depth_frame[point[1], point[0]]
57     cv2.putText(color_frame, "{}mm".format(distance), (point[0], point[1] - 20),
58                 cv2.FONT_HERSHEY_PLAIN, 2, (0, 255, 255), 2)
59
60     cv2.imshow("depth frame", depth_frame)
61     cv2.imshow("color frame", color_frame)
62     #cv2.imshow("depth frame normalized", depth_frame_norm)
63
64     key = cv2.waitKey(1)
65
66     if key == 27 :
67         break

```