

```

1 import pyrealsense2 as rs
2 import numpy as np
3
4 class DepthCamera:
5     def __init__(self):
6         # Configure depth and color streams
7         self.pipeline = rs.pipeline()
8         config = rs.config()
9
10        # Get device product line for setting a supporting resolution
11        pipeline_wrapper = rs.pipeline_wrapper(self.pipeline)
12        pipeline_profile = config.resolve(pipeline_wrapper)
13        device = pipeline_profile.get_device()
14        device_product_line = str(device.get_info(rs.camera_info.product_line))
15
16        config.enable_stream(rs.stream.depth, 640, 480, rs.format.z16, 30)
17        config.enable_stream(rs.stream.color, 640, 480, rs.format.bgr8, 30)
18
19        #config.enable_stream(rs.stream.depth, 480, 270, rs.format.z16, 90)
20        #config.enable_stream(rs.stream.color, 480, 270, rs.format.bgr8, 30)
21
22        # Start streaming
23        self.pipeline.start(config)
24
25    def get_frame(self):
26        frames = self.pipeline.wait_for_frames()
27        depth_frame = frames.get_depth_frame()
28        color_frame = frames.get_color_frame()
29
30        depth_image = np.asanyarray(depth_frame.get_data())
31        color_image = np.asanyarray(color_frame.get_data())
32        if not depth_frame or not color_frame:
33            return False, None, None
34        return True, depth_image, color_image
35
36    def release(self):
37        self.pipeline.stop()

```