
PhotoScan Python Reference

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OVERVIEW

1.1 Introduction to Python scripting in PhotoScan Professional

This API is in development and will be extended in the future PhotoScan releases.

Note: Python scripting is supported only in PhotoScan Professional edition.

PhotoScan Professional uses Python 3.5 as a scripting engine.

Python commands and scripts can be executed in PhotoScan in one of the following ways:

- From PhotoScan “Console” pane using it as standard Python console.
- From the “Tools” menu using “Run script...” command.
- From command line using “-r” argument and passing the path to the script as an argument.

The following PhotoScan functionality can be accessed from Python scripts:

- Open/save/create PhotoScan projects.
- Add/remove chunks, cameras, markers.
- Add/modify camera calibrations, ground control data, assign geographic projections and coordinates.
- Perform processing steps (align photos, build dense cloud, build mesh, texture, decimate model, etc...).
- Export processing results (models, textures, orthophotos, DEMs).
- Access data of generated models, point clouds, images.
- Start and control network processing tasks.

APPLICATION MODULES

PhotoScan module provides access to the core processing functionality, including support for inspection and manipulation with project data.

The main component of the module is a Document class, which represents a PhotoScan project. Multiple Document instances can be created simultaneously if needed. Besides that a currently opened project in the application can be accessed using `PhotoScan.app.document` property.

The following example performs main processing steps on existing project and saves back the results:

```
>>> import PhotoScan
>>> doc = PhotoScan.app.document
>>> doc.open("project.psz")
>>> chunk = doc.chunk
>>> chunk.matchPhotos(accuracy=PhotoScan.HighAccuracy, generic_preselection=True,
↳reference_preselection=False)
>>> chunk.alignCameras()
>>> chunk.buildDepthMaps(quality=PhotoScan.MediumQuality, filter=PhotoScan.
↳AggressiveFiltering)
>>> chunk.buildDenseCloud()
>>> chunk.buildModel(surface=PhotoScan.Arbitrary, interpolation=PhotoScan.
↳EnabledInterpolation)
>>> chunk.buildUV(mapping=PhotoScan.GenericMapping)
>>> chunk.buildTexture(blending=PhotoScan.MosaicBlending, size=4096)
>>> doc.save()
```

class `PhotoScan.Accuracy`
Alignment accuracy in [HighestAccuracy, HighAccuracy, MediumAccuracy, LowAccuracy, LowestAccuracy]

class `PhotoScan.Animation`
Camera animation.

class `Point`
Camera orientation at specified time moment

location
Camera position vector.
Type *Vector*

rotation
Camera rotation quaternion.
Type *Vector*

time
Time.
Type *float*

class `Animation.Track`
Camera animation track

`Animation.field_of_view`
Vertical field of view in degrees.

Type float

`Animation.label`
Animation label.

Type string

`Animation.speed`
Animation speedup factor.

Type float

`Animation.track`
Camera track.

Type `Animation.Track`

class `PhotoScan.Antenna`
GPS antenna position relative to camera.

fixed
Fix antenna flag.

Type bool

location
Antenna coordinates.

Type `Vector`

location_acc
Antenna location accuracy.

Type `Vector`

location_ref
Antenna location reference.

Type `Vector`

rotation
Antenna rotation angles.

Type `Vector`

rotation_acc
Antenna rotation accuracy.

Type `Vector`

rotation_ref
Antenna rotation reference.

Type `Vector`

class `PhotoScan.Application`
Application class provides access to several global application attributes, such as document currently loaded in the user interface, software version and GPU device configuration. It also contains helper routines to prompt the user to input various types of parameters, like displaying a file selection dialog or coordinate system selection dialog among others.

An instance of Application object can be accessed using PhotoScan.app attribute, so there is usually no need to create additional instances in the user code.

The following example prompts the user to select a new coordinate system, applies it to the active chunk and saves the project under the user selected file name:

```
>>> import PhotoScan
>>> doc = PhotoScan.app.document
>>> crs = PhotoScan.app.getCoordinateSystem("Select Coordinate System", doc.chunk.
→crs)
>>> doc.chunk.crs = crs
>>> path = PhotoScan.app.getSaveFileName("Save Project As")
>>> try:
...     doc.save(path)
... except RuntimeError:
...     PhotoScan.app.messageBox("Can't save project")
```

class ConsolePane

ConsolePane class provides access to the console pane

clear()

Clear console pane.

contents

Console pane contents.

Type string

class Application.PhotosPane

PhotosPane class provides access to the photos pane

resetFilter()

Reset photos pane filter.

setFilter(items)

Set photos pane filter.

Parameters *items* (list of *Camera* or *Marker*) – filter to apply.

class Application.Settings

PySettings()

Application settings

load()

Load settings from disk.

log_enable

Enable writing log to file.

Type bool

log_path

Log file path.

Type string

network_enable

Network processing enabled flag.

Type bool

network_host

Network server host name.

Type string

network_path

Network data root path.

Type string

network_port

Network server control port.

Type int

save()

Save settings on disk.

setValue (*key, value*)

Set settings value. :arg key: Key. :type key: string :arg value: Value. :type value: object

value (*key*)

Return settings value. :arg key: Key. :type key: string :return: Settings value. :rtype: object

Application.**activated**

PhotoScan activation status.

Type bool

Application.**addItem** (*label, func* [, *shortcut*] [, *icon*])

Create a new menu entry.

Parameters

- **label** (*string*) – Menu item label.
- **func** (*function*) – Function to be called.
- **shortcut** (*string*) – Keyboard shortcut.
- **icon** (*string*) – Icon.

Application.**addMenuSeparator** (*label*)

Add menu separator.

Parameters **label** (*string*) – Menu label.

Application.**captureModelView** ([*width*] [, *height*] [, *transparent*] [, *hide_items*] [, *source*] [, *mode*])

Capture image from model view.

Parameters

- **width** (*int*) – Image width.
- **height** (*int*) – Image height.
- **transparent** (*bool*) – Sets transparent background.
- **hide_items** (*bool*) – Hides all items.
- **source** (*PhotoScan.DataSource*) – Data source. Note: DataSource.DenseCloudData value is not supported.
- **mode** (*PhotoScan.ModelViewMode*) – Model view mode.

Returns Captured image.

Return type *Image*

Application.**captureOrthoView** ([*width*] [, *height*] [, *transparent*] [, *hide_items*] [, *source*])

Capture image from ortho view.

Parameters

- **width** (*int*) – Image width.
- **height** (*int*) – Image height.
- **transparent** (*bool*) – Sets transparent background.
- **hide_items** (*bool*) – Hides all items.
- **source** (*PhotoScan.DataSource*) – Data source.

Returns Captured image.

Return type *Image*

`Application.console`

Console pane.

Type `ConsolePane`

`Application.cpu_enable`

Use CPU when GPU is active.

Type `bool`

`Application.document`

Main application document object.

Type *Document*

`Application.enumGPUDevices()`

Enumerate installed GPU devices.

Returns A list of devices.

Return type `list`

`Application.getBool(label='')`

Prompt user for the boolean value.

Parameters **label** (*string*) – Optional text label for the dialog.

Returns Boolean value selected by the user.

Return type `bool`

`Application.getCoordinateSystem([label][, value])`

Prompt user for coordinate system.

Parameters

- **label** (*string*) – Optional text label for the dialog.
- **value** (*CoordinateSystem*) – Default value.

Returns Selected coordinate system. If the dialog was cancelled, `None` is returned.

Return type *CoordinateSystem*

`Application.getExistingDirectory([hint])`

Prompt user for the existing folder.

Parameters **hint** (*string*) – Optional text label for the dialog.

Returns Path to the folder selected. If the input was cancelled, empty string is returned.

Return type `string`

`Application.getFloat(label='', value=0)`

Prompt user for the floating point value.

Parameters

- **label** (*string*) – Optional text label for the dialog.
- **value** (*float*) – Default value.

Returns Floating point value entered by the user.

Return type float

`Application.getInt (label='', value=0)`

Prompt user for the integer value.

Parameters

- **label** (*string*) – Optional text label for the dialog.
- **value** (*int*) – Default value.

Returns Integer value entered by the user.

Return type int

`Application.getOpenFileName ([hint][, filter])`

Prompt user for the existing file.

Parameters

- **hint** (*string*) – Optional text label for the dialog.
- **filter** (*string*) – Optional file filter, e.g. “Text file (.txt)” or “.txt”. Multiple filters are separated with “;”.

Returns Path to the file selected. If the input was cancelled, empty string is returned.

Return type string

`Application.getOpenFileNames ([hint][, filter])`

Prompt user for one or more existing files.

Parameters

- **hint** (*string*) – Optional text label for the dialog.
- **filter** (*string*) – Optional file filter, e.g. “Text file (.txt)” or “.txt”. Multiple filters are separated with “;”.

Returns List of file paths selected by the user. If the input was cancelled, empty list is returned.

Return type list

`Application.getSaveFileName ([hint][, filter])`

Prompt user for the file. The file does not have to exist.

Parameters

- **hint** (*string*) – Optional text label for the dialog.
- **filter** (*string*) – Optional file filter, e.g. “Text file (.txt)” or “.txt”. Multiple filters are separated with “;”.

Returns Path to the file selected. If the input was cancelled, empty string is returned.

Return type string

`Application.getString (label='', value='')`

Prompt user for the string value.

Parameters

- **label** (*string*) – Optional text label for the dialog.
- **value** (*string*) – Default value.

Returns String entered by the user.

Return type string

`Application.gpu_mask`

GPU device bit mask: 1 - use device, 0 - do not use (i.e. value 5 enables device number 0 and 2).

Type int

`Application.messageBox` (*message*)

Display message box to the user.

Parameters **message** (*string*) – Text message to be displayed.

`Application.photos_pane`

Photos pane.

Type PhotosPane

`Application.quit` ()

Exit application.

`Application.settings`

Application settings.

Type Settings

`Application.update` ()

Update user interface during long operations.

`Application.version`

PhotoScan version.

Type string

`Application.viewpoint`

Viewpoint in the model view.

Type *Viewpoint*

class PhotoScan.**BlendingMode**

Blending mode in [AverageBlending, MosaicBlending, MinBlending, MaxBlending, DisabledBlending]

class PhotoScan.**Calibration**

Calibration object contains camera calibration information including image size, focal length, principal point coordinates and distortion coefficients.

b1

Affinity.

Type float

b2

Non-orthogonality.

Type float

covariance_matrix

Covariance matrix.

Type *Matrix*

covariance_params

Covariance matrix parameters.

Type list of string

cx

Principal point X coordinate.

Type float

cy

Principal point Y coordinate.

Type float

error (*point*, *proj*)

Returns projection error.

Parameters

- **point** (*Vector*) – Coordinates of the point to be projected.
- **proj** (*Vector*) – Pixel coordinates of the point.

Returns 2D projection error.

Return type *Vector*

f

Focal length.

Type float

height

Image height.

Type int

k1

Radial distortion coefficient K1.

Type float

k2

Radial distortion coefficient K2.

Type float

k3

Radial distortion coefficient K3.

Type float

k4

Radial distortion coefficient K4.

Type float

load (*path*, *format*=*'xml'*)

Loads calibration from file.

Parameters

- **path** (*string*) – path to calibration file
- **format** (*string*) – Calibration format in [*'xml'*, *'australis'*, *'photomodeler'*, *'calibcam'*, *'calcam'*, *'inpho'*, *'usgs'*].

Returns success of operation

Return type bool

p1

Tangential distortion coefficient P1.

Type float

p2

Tangential distortion coefficient P2.

Type float

p3

Tangential distortion coefficient P3.

Type float

p4

Tangential distortion coefficient P4.

Type float

project (*point*)

Returns projected pixel coordinates of the point.

Parameters **point** (*Vector*) – Coordinates of the point to be projected.

Returns 2D projected point coordinates.

Return type *Vector*

save (*path*, *format*='xml', [*pixel_size*][*label*])

Saves calibration to file.

Parameters

- **path** (*string*) – path to calibration file
- **format** (*string*) – Calibration format in ['xml', 'australis', 'photomodeler', 'calibcam', 'calcam', 'inpho', 'usgs'].
- **pixel_size** (*Vector*) – Pixel size in mm used to convert normalized calibration coefficients to Australis and CalibCam coefficients.
- **label** (*string*) – Calibration label used in Australis, CalibCam and CalCam formats.

Returns success of operation

Return type bool

type

Camera model.

Type *Sensor.Type*

unproject (*point*)

Returns direction corresponding to the image point.

Parameters **point** (*Vector*) – Pixel coordinates of the point.

Returns 3D vector in the camera coordinate system.

Return type *Vector*

width

Image width.

Type `int`

class `PhotoScan.Camera`

Camera instance

```
>>> import PhotoScan
>>> chunk = PhotoScan.app.document.addChunk()
>>> chunk.addPhotos(["IMG_0001.jpg", "IMG_0002.jpg"])
>>> camera = chunk.cameras[0]
>>> camera.photo.meta["Exif/FocalLength"]
'18'
```

The following example describes how to create multispectral camera layout:

```
>>> import PhotoScan
>>> doc = PhotoScan.app.document
>>> chunk = doc.chunk
>>> rgb = ["RGB_0001.JPG", "RGB_0002.JPG", "RGB_0003.JPG"]
>>> nir = ["NIR_0001.JPG", "NIR_0002.JPG", "NIR_0003.JPG"]
>>> images = [[rgb[0], nir[0]], [rgb[1], nir[1]], [rgb[2], nir[2]]]
>>> chunk.addPhotos(images, PhotoScan.MultiplaneLayout)
```

class **Reference**

Camera reference data.

accuracy

Camera location accuracy.

Type *Vector*

enabled

Enabled flag.

Type `bool`

location

Camera coordinates.

Type *Vector*

location_accuracy

Camera location accuracy.

Type *Vector*

rotation

Camera rotation angles.

Type *Vector*

rotation_accuracy

Camera rotation accuracy.

Type *Vector*

Camera.**center**

Camera station coordinates for the photo in the chunk coordinate system.

Type *Vector*

Camera.**chunk**

Chunk the camera belongs to.

Type *Chunk*

Camera.**enabled**

Enables/disables the photo.

Type bool

Camera.**error** (*point*, *proj*)

Returns projection error.

Parameters

- **point** (*Vector*) – Coordinates of the point to be projected.
- **proj** (*Vector*) – Pixel coordinates of the point.

Returns 2D projection error.

Return type *Vector*

Camera.**frames**

Camera frames.

Type list of *Camera*

Camera.**group**

Camera group.

Type *CameraGroup*

Camera.**image** ()

Returns image data.

Returns Image data.

Return type *Image*

Camera.**key**

Camera identifier.

Type int

Camera.**label**

Camera label.

Type string

Camera.**layer_index**

Camera layer index.

Type int

Camera.**mask**

Camera mask.

Type *Mask*

Camera.**master**

Master camera.

Type *Camera*

Camera.**meta**

Camera meta data.

Type *MetaData*

Camera.**open** (*path*[, *layer*])

Loads specified image file.

Parameters

- **path** (*string*) – Path to the image file to be loaded.

- **layer** (*int*) – Optional layer index in case of multipage files.

Camera.**orientation**

Image orientation (1 - normal, 6 - 90 degree, 3 - 180 degree, 8 - 270 degree).

Type *int*

Camera.**photo**

Camera photo.

Type *Photo*

Camera.**planes**

Camera planes.

Type list of *Camera*

Camera.**project** (*point*)

Returns coordinates of the point projection on the photo.

Parameters **point** (*Vector*) – Coordinates of the point to be projected.

Returns 2D point coordinates.

Return type *Vector*

Camera.**reference**

Camera reference data.

Type *CameraReference*

Camera.**selected**

Selects/deselects the photo.

Type *bool*

Camera.**sensor**

Camera sensor.

Type *Sensor*

Camera.**shutter**

Camera shutter.

Type *Shutter*

Camera.**thumbnail**

Camera thumbnail.

Type *Thumbnail*

Camera.**transform**

4x4 matrix describing photo location in the chunk coordinate system.

Type *Matrix*

Camera.**unproject** (*point*)

Returns coordinates of the point which will have specified projected coordinates.

Parameters **point** (*Vector*) – Projection coordinates.

Returns 3D point coordinates.

Return type *Vector*

Camera.**vignetting**

Vignetting for each band.

Type list of *Vignetting*

class PhotoScan.**CameraGroup**

CameraGroup objects define groups of multiple cameras. The grouping is established by assignment of a CameraGroup instance to the Camera.group attribute of participating cameras.

The type attribute of CameraGroup instances defines the effect of such grouping on processing results and can be set to Folder (no effect) or Station (coincident projection centers).

class **Type**

Camera group type in [Folder, Station]

CameraGroup.**label**

Camera group label.

Type string

CameraGroup.**selected**

Current selection state.

Type bool

CameraGroup.**type**

Camera group type.

Type *CameraGroup.Type*

class PhotoScan.**CamerasFormat**

Camera orientation format in [CamerasFormatXML, CamerasFormatCHAN, CamerasFormatBoujou, CamerasFormatBundler, CamerasFormatOPK, CamerasFormatPATB, CamerasFormatBINGO, CamerasFormatORIMA, CamerasFormatAeroSys, CamerasFormatInpho, CamerasFormatSummit, CamerasFormatBlocksExchange, CamerasFormatRZML, CamerasFormatVisionMap, CamerasFormatABC, CamerasFormatFBX]

class PhotoScan.**Chunk**

A Chunk object:

- provides access to all chunk components (sensors, cameras, camera groups, markers, scale bars)
- contains data inherent to individual frames (point cloud, model, etc)
- implements processing methods (matchPhotos, alignCameras, buildDenseCloud, buildModel, etc)
- provides access to other chunk attributes (transformation matrix, coordinate system, meta-data, etc..)

New components can be created using corresponding addXXX methods (addSensor, addCamera, addCameraGroup, addMarker, addScalebar, addFrame). Removal of components is supported by a single remove method, which can accept lists of various component types.

In case of multi-frame chunks the Chunk object contains an additional reference to the particular chunk frame, initialized to the current frame by default. Various methods that work on a per frame basis (matchPhotos, buildModel, etc) are applied to this particular frame. A frames attribute can be used to obtain a list of Chunk objects that reference all available frames.

The following example performs image matching and alignment for the active chunk:

```
>>> import PhotoScan
>>> chunk = PhotoScan.app.document.chunk
>>> for frame in chunk.frames:
...     frame.matchPhotos(accuracy=PhotoScan.HighAccuracy)
>>> chunk.alignCameras()
```

addCamera ([*sensor*])

Add new camera to the chunk.

Parameters **sensor** (*Sensor*) – Sensor to be assigned to this camera.

Returns Created camera.

Return type *Camera*

addCameraGroup ()

Add new camera group to the chunk.

Returns Created camera group.

Return type *CameraGroup*

addDenseCloud ()

Add new dense cloud to the chunk.

Returns Created dense cloud.

Return type *DenseCloud*

addDepthMaps ()

Add new depth maps set to the chunk.

Returns Created depth maps set.

Return type *DepthMaps*

addElevation ()

Add new elevation model to the chunk.

Returns Created elevation model.

Return type *Elevation*

addFrame ()

Add new frame to the chunk.

Returns Created frame.

Return type *Frame*

addFrames (*chunk* [, *frames*] [, *items*] [, *progress*])

Add frames from specified chunk.

Parameters

- **chunk** (*PhotoScan.Chunk*) – Chunk to copy frames from.
- **frames** (list of *Frame*) – Optional list of frames to be copied.
- **items** (list of *PhotoScan.DataSource*) – A list of items to copy.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

addMarker ([*point*], *visibility=False*)

Add new marker to the chunk.

Parameters

- **point** (*PhotoScan.Vector*) – Point to initialize marker projections.
- **visibility** (*bool*) – Enables visibility check during projection assignment.

Returns Created marker.

Return type *Marker*

addMarkerGroup ()

Add new marker group to the chunk.

Returns Created marker group.

Return type *MarkerGroup*

addModel ()

Add new model to the chunk.

Returns Created model.

Return type *Model*

addOrthomosaic ()

Add new orthomosaic to the chunk.

Returns Created orthomosaic.

Return type *Orthomosaic*

addPhotos (*filenames* [, *layout*], *strip_extensions=True* [, *progress*])

Add a list of photos to the chunk.

Parameters

- **filenames** (*list of string*) – A list of file paths.
- **layout** (*PhotoScan.ImageLayout*) – Image layout in the chunk.
- **strip_extensions** (*bool*) – Strip file extensions from camera labels.
- **progress** (*Callable[[float], None]*) – Progress callback.

addScalebar (*point1*, *point2*)

Add new scale bar to the chunk.

Parameters

- **point1** (*Marker* or *Camera*) – First endpoint.
- **point2** – Second endpoint.

Returns Created scale bar.

Return type *Scalebar*

addScalebarGroup ()

Add new scale bar group to the chunk.

Returns Created scale bar group.

Return type *ScalebarGroup*

addSensor ()

Add new sensor to the chunk.

Returns Created sensor.

Return type *Sensor*

addTiledModel ()

Add new tiled model to the chunk.

Returns Created tiled model.

Return type *TiledModel*

alignCameras ([*cameras*] [, *min_image*], *adaptive_fitting=False* [, *progress*])

Perform photo alignment for the chunk.

Parameters

- **cameras** (list of *Camera*) – A list of cameras to be aligned to the existing cameras.
- **min_image** (*int*) – Minimum number of point projections.
- **adaptive_fitting** (*bool*) – Enables adaptive fitting of distortion coefficients.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

animation

Camera animation.

Type *Animation*

buildContours (*source_data*=*ElevationData*, *interval*=1[, *min_value*][, *max_value*][, *progress*])
Build contours for the chunk.

Parameters

- **source_data** (*PhotoScan.DataSource*) – Source data for contour generation.
- **interval** (*float*) – Contour interval.
- **min_value** (*float*) – Minimum value of contour range.
- **max_value** (*float*) – Maximum value of contour range.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

buildDem (*source*=*DenseCloudData*, *interpolation*=*EnabledInterpolation*[, *projection*][, *region*][, *classes*], *flip_x*=*False*, *flip_y*=*False*, *flip_z*=*False*[, *progress*])
Build elevation model for the chunk.

Parameters

- **source** (*PhotoScan.DataSource*) – Selects between dense point cloud and sparse point cloud. If not specified, uses dense cloud if available.
- **interpolation** (*PhotoScan.Interpolation*) – Interpolation mode.
- **projection** (*OrthoProjection* or *CoordinateSystem* or *Matrix*) – Sets output projection.
- **region** (*tuple of 4 floats*) – Region to be exported in the (x0, y0, x1, y1) format.
- **classes** (list of *PhotoScan.PointClass*) – List of dense point classes to be used for surface extraction.
- **flip_x** (*bool*) – Flip X axis direction.
- **flip_y** (*bool*) – Flip X axis direction.
- **flip_z** (*bool*) – Flip X axis direction.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

buildDenseCloud (*point_colors*=*True*, *keep_depth*=*False*[, *max_neighbors*][, *progress*])
Generate dense cloud for the chunk.

Parameters

- **point_colors** (*bool*) – Enables/disables point colors calculation.
- **keep_depth** (*bool*) – Enables keep depth maps option.
- **max_neighbors** (*int*) – Maximum number of neighbor images to use for depth map filtering.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

buildDepthMaps (*quality=MediumQuality*, *filter=AggressiveFiltering* [, *cameras*],
reuse_depth=True [, *max_neighbors*] [, *progress*])
 Generate depth maps for the chunk.

Parameters

- **quality** (*PhotoScan.Quality*) – Depth map quality.
- **filter** (*PhotoScan.FilterMode*) – Depth map filtering level.
- **cameras** (list of *Camera*) – A list of cameras to be processed.
- **reuse_depth** (*bool*) – Enables reuse depth maps option.
- **max_neighbors** (*int*) – Maximum number of neighbor images to use for depth map generation.
- **progress** (*Callable[[float], None]*) – Progress callback.

buildModel (*surface=Arbitrary*, *interpolation=EnabledInterpolation*,
face_count=MediumFaceCount [, *source*] [, *classes*], *vertex_colors=True*, *qual-*
ity=MediumQuality, *volumetric_masks=False*, *keep_depth=False*, *reuse_depth=False* [,
progress])
 Generate model for the chunk frame.

Parameters

- **surface** (*PhotoScan.SurfaceType*) – Type of object to be reconstructed.
- **interpolation** (*PhotoScan.Interpolation*) – Interpolation mode.
- **face_count** (*PhotoScan.FaceCount* or *int*) – Target face count.
- **source** (*PhotoScan.DataSource*) – Selects between dense point cloud, sparse point cloud and depth maps. If not specified, uses dense cloud if available.
- **classes** (list of *PhotoScan.PointClass*) – List of dense point classes to be used for surface extraction.
- **vertex_colors** (*bool*) – Enables/disables vertex colors calculation.
- **quality** (*PhotoScan.Quality*) – Depth map quality. Ignored if source is not *DepthMapsData*.
- **volumetric_masks** (*bool*) – Enables/disables strict volumetric masking.
- **keep_depth** (*bool*) – Enables keep depth maps option.
- **reuse_depth** (*bool*) – Enables reuse depth maps option.
- **progress** (*Callable[[float], None]*) – Progress callback.

buildOrthomosaic (*surface=ElevationData*, *blending=MosaicBlending*, *fill_holes=True*,
cull_faces=False [, *projection*] [, *region*] [, *dx*] [, *dy*], *flip_x=False*,
flip_y=False, *flip_z=False* [, *progress*])
 Build orthomosaic for the chunk.

Parameters

- **surface** (*PhotoScan.DataSource*) – Orthorectification surface.
- **blending** (*PhotoScan.BlendingMode*) – Orthophoto blending mode.
- **fill_holes** (*bool*) – Enable hole filling.
- **cull_faces** (*bool*) – Enable back-face culling.

- **projection** (*OrthoProjection* or *CoordinateSystem* or *Matrix*) – Sets output projection.
- **region** (*tuple of 4 floats*) – Region to be exported in the (x0, y0, x1, y1) format.
- **dx** (*float*) – Pixel size in the X dimension in projected units.
- **dy** (*float*) – Pixel size in the Y dimension in projected units.
- **flip_x** (*bool*) – Flip X axis direction.
- **flip_y** (*bool*) – Flip X axis direction.
- **flip_z** (*bool*) – Flip X axis direction.
- **progress** (*Callable[[float], None]*) – Progress callback.

buildPoints (*error=10*[, *min_image*][, *progress*])
 Rebuild point cloud for the chunk.

Parameters

- **error** (*float*) – Reprojection error threshold.
- **min_image** (*int*) – Minimum number of point projections.
- **progress** (*Callable[[float], None]*) – Progress callback.

buildSeamlines (*epsilon=1.5*[, *progress*])
 Generate shapes for orthomosaic seamlines.

Parameters

- **epsilon** (*float*) – Contour simplification threshold.
- **progress** (*Callable[[float], None]*) – Progress callback.

buildTexture (*blending=MosaicBlending*, *size=2048*, *fill_holes=True*, *ghosting_filter=True*[, *cameras*][, *progress*])
 Generate texture for the chunk.

Parameters

- **blending** (*PhotoScan.BlendingMode*) – Texture blending mode.
- **size** (*int*) – Texture size.
- **fill_holes** (*bool*) – Enables hole filling.
- **ghosting_filter** (*bool*) – Enables ghosting filter.
- **cameras** (list of *Camera*) – A list of cameras to be used for texturing.
- **progress** (*Callable[[float], None]*) – Progress callback.

buildTiledModel ([*pixel_size*], *tile_size=256*[, *source*], *reuse_depth=False*, *ghosting_filter=True*[, *progress*])
 Build tiled model for the chunk.

Parameters

- **pixel_size** (*float*) – Target model resolution in meters.
- **tile_size** (*int*) – Size of tiles in pixels.
- **source** (*PhotoScan.DataSource*) – Selects between depth maps, dense point cloud and mesh. If not specified, uses dense cloud if available.

- **reuse_depth** (*bool*) – Enables reuse depth maps option. Applicable if depth maps are the source.
- **ghosting_filter** (*bool*) – Enables ghosting filter.
- **progress** (*Callable[[float], None]*) – Progress callback.

buildUV (*mapping=GenericMapping, count=1, adaptive_resolution=False* [, *camera*] [, *progress*])
Generate uv mapping for the model.

Parameters

- **mapping** (*PhotoScan.MappingMode*) – Texture mapping mode.
- **count** (*int*) – Texture count.
- **adaptive_resolution** (*bool*) – Enable adaptive face detalization.
- **camera** (*Camera*) – Camera to be used for texturing in MappingCamera mode.
- **progress** (*Callable[[float], None]*) – Progress callback.

calibrateColors (*source_data=ModelData, color_balance=False* [, *cameras*] [, *frames*] [, *progress*])
Perform radiometric calibration.

Parameters

- **source_data** (*PhotoScan.DataSource*) – Source data for calibration.
- **color_balance** (*bool*) – Turn color balance compensation on/off.
- **cameras** (list of *Camera*) – List of cameras to process.
- **frames** (list of *Frame*) – List of frames to process.
- **progress** (*Callable[[float], None]*) – Progress callback.

calibrateReflectance (*use_reflectance_panels=True, use_sun_sensor=False* [, *progress*])
Calibrate reflectance factors based on calibration panels and/or sun sensor.

Parameters

- **use_reflectance_panels** (*bool*) – Use calibrated reflectance panels.
- **use_sun_sensor** (*bool*) – Apply irradiance sensor measurements.
- **progress** (*Callable[[float], None]*) – Progress callback.

camera_crs

Coordinate system used for camera reference data.

Type *CoordinateSystem*

camera_groups

List of camera groups in the chunk.

Type list of *CameraGroup*

camera_location_accuracy

Expected accuracy of camera coordinates in meters.

Type *Vector*

camera_rotation_accuracy

Expected accuracy of camera orientation angles in degrees.

Type *Vector*

cameras

List of cameras in the chunk.

Type list of *Camera*

cir_transform

CIR calibration matrix.

Type *CirTransform*

copy (*[frames]* [, *items*] [, *progress*])

Make a copy of the chunk.

Parameters

- **frames** (list of *Frame*) – Optional list of frames to be copied.
- **items** (list of *PhotoScan.DataSource*) – A list of items to copy.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

Returns Copy of the chunk.

Return type *Chunk*

crs

Coordinate system used for reference data.

Type *CoordinateSystem*

decimateModel (*face_count* [, *progress*])

Decimate the model to the specified face count.

Parameters

- **face_count** (*int*) – Target face count.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

dense_cloud

Default dense point cloud for the current frame.

Type *DenseCloud*

dense_clouds

List of dense clouds for the current frame.

Type list of *DenseCloud*

depth_maps

Default depth maps set for the current frame.

Type *DepthMaps*

depth_maps_sets

List of depth maps sets for the current frame.

Type list of *DepthMaps*

detectFiducials ([*progress*])

Detect fiducial marks on film cameras.

Parameters **progress** (*Callable*[[*float*], *None*]) – Progress callback.

detectMarkers (*type=TargetCircular12bit*, *tolerance=50*, *inverted=False*, *noparity=False* [, *minimum_size*] [, *minimum_dist*] [, *progress*])

Create markers from coded targets.

Parameters

- **type** (*PhotoScan.TargetType*) – Type of targets.
- **tolerance** (*int*) – Detector tolerance (0 - 100).
- **inverted** (*bool*) – Detect markers on black background.
- **noparity** (*bool*) – Disable parity checking.
- **minimum_size** (*int*) – Minimum target radius in pixels to be detected (CrossTarget type only).
- **minimum_dist** (*int*) – Minimum distance between targets in pixels (CrossTarget type only).
- **progress** (*Callable[[float], None]*) – Progress callback.

elevation

Default elevation model for the current frame.

Type *Elevation*

elevations

List of elevation models for the current frame.

Type list of *Elevation*

enabled

Enables/disables the chunk.

Type bool

estimateImageQuality (*[cameras]*, *filter_mask=False*, *[progress]*)

Estimate image quality.

Parameters

- **cameras** (list of *Camera*) – Optional list of cameras to be processed.
- **filter_mask** (*bool*) – Constrain analyzed image region by mask.
- **progress** (*Callable[[float], None]*) – Progress callback.

euler_angles

Euler angles triplet used for rotation reference.

Type *EulerAngles*

exportCameras (*path*, *format=CamerasFormatXML*, *[projection]*, *export_points=True*, *export_markers=False*, *use_labels=False*, *rotation_order=RotationOrderXYZ*, *[progress]*)

Export point cloud and/or camera positions.

Parameters

- **path** (*string*) – Path to output file.
- **format** (*PhotoScan.CamerasFormat*) – Export format.
- **projection** (*CoordinateSystem*) – Output coordinate system.
- **export_points** (*bool*) – Enables/disables export of automatic tie points.
- **export_markers** (*bool*) – Enables/disables export of manual matching points.
- **use_labels** (*bool*) – Enables/disables label based item identifiers.

- **rotation_order** (*PhotoScan.RotationOrder*) – Rotation order (CHAN format only)
- **progress** (*Callable[[float], None]*) – Progress callback.

```
exportDem(path[, format][, image_format], raster_transform=RasterTransformNone[, projection
][, region][, dx][, dy][, blockw][, blockh][, width][, height][, world_transform
], nodata=-32767, write_kml=False, write_world=False, write_scheme=False[,
image_description], tiff_big=False, tiff_overviews=True, network_links=True[,
min_zoom_level][, max_zoom_level][, progress])
```

Export digital elevation model.

Parameters

- **path** (*string*) – Path to output DEM.
- **format** (*PhotoScan.RasterFormat*) – Export format.
- **image_format** (*PhotoScan.ImageFormat*) – Tile format.
- **raster_transform** (*PhotoScan.RasterTransformType*) – Raster transformation. Can be *RasterTransformNone* or *RasterTransformPalette*.
- **projection** (*OrthoProjection* or *CoordinateSystem*) – Output coordinate system.
- **region** (*tuple of 4 floats*) – Region to be exported in the (x0, y0, x1, y1) format.
- **dx** (*float*) – Pixel size in the X dimension in projected units.
- **dy** (*float*) – Pixel size in the Y dimension in projected units.
- **blockw** (*int*) – Specifies block width of the DEM mosaic in pixels.
- **blockh** (*int*) – Specifies block height of the DEM mosaic in pixels.
- **width** (*int*) – Total width of the orthomosaic in pixels.
- **height** (*int*) – Total height of the orthomosaic in pixels.
- **world_transform** (*PhotoScan.Matrix*) – 2x3 raster-to-world transformation matrix.
- **nodata** (*float*) – No-data value.
- **write_kml** (*bool*) – Enables/disables kml file generation.
- **write_world** (*bool*) – Enables/disables world file generation.
- **write_scheme** (*bool*) – Enables/disables tile scheme files generation.
- **image_description** (*string*) – Optional description to be added to image files.
- **tiff_big** (*bool*) – Enables/disables BigTIFF compression for TIFF files.
- **tiff_overviews** (*bool*) – Enables/disables image pyramid deneration for TIFF files.
- **network_links** (*bool*) – Enables/disables network links generation for KMZ format.
- **min_zoom_level** (*int*) – Minimum zoom level (Google Map Tiles, MBTiles and World Wind Tiles formats only).
- **max_zoom_level** (*int*) – Maximum zoom level (Google Map Tiles, MBTiles and World Wind Tiles formats only).
- **progress** (*Callable[[float], None]*) – Progress callback.

exportMarkers (*path* [, *projection*])

Export markers.

Parameters

- **path** (*string*) – Path to output file.
- **projection** (*CoordinateSystem*) – Output coordinate system.

exportModel (*path*, *binary*=True, *precision*=6, *texture_format*=ImageFormat.JPEG, *texture*=True, *normals*=True, *colors*=True, *cameras*=True, *markers*=True, *udim*=False, *alpha*=False, *strip_extensions*=False, *raster_transform*=RasterTransformNone [, *comment*] [, *format*] [, *projection*] [, *shift*] [, *progress*])

Export generated model for the chunk.

Parameters

- **path** (*string*) – Path to output model.
- **binary** (*bool*) – Enables/disables binary encoding (if supported by format).
- **precision** (*int*) – Number of digits after the decimal point (for text formats).
- **texture_format** (*PhotoScan.ImageFormat*) – Texture format.
- **texture** (*bool*) – Enables/disables texture export.
- **normals** (*bool*) – Enables/disables export of vertex normals.
- **colors** (*bool*) – Enables/disables export of vertex colors.
- **cameras** (*bool*) – Enables/disables camera export.
- **markers** (*bool*) – Enables/disables marker export.
- **udim** (*bool*) – Enables/disables UDIM texture layout.
- **alpha** (*bool*) – Enables/disables alpha channel export.
- **strip_extensions** (*bool*) – Strips camera label extensions during export.
- **raster_transform** (*PhotoScan.RasterTransformType*) – Raster band transformation.
- **comment** (*string*) – Optional comment (if supported by selected format).
- **format** (*PhotoScan.ModelFormat*) – Export format.
- **projection** (*CoordinateSystem*) – Output coordinate system.
- **shift** (*3-element vector*) – Optional shift to be applied to vertex coordinates.
- **progress** (*Callable[[float], None]*) – Progress callback.

exportOrthomosaic (*path* [, *format*] [, *image_format*], *raster_transform*=RasterTransformNone [, *projection*] [, *region*] [, *dx*] [, *dy*] [, *blockw*] [, *blockh*] [, *width*] [, *height*] [, *world_transform*], *write_kml*=False, *write_world*=False, *write_scheme*=False, *write_alpha*=True [, *image_description*], *tiff_compression*=TiffCompressionLZW, *tiff_big*=False, *tiff_overviews*=True, *jpeg_quality*=90, *network_links*=True [, *min_zoom_level*] [, *max_zoom_level*], *white_background*=True [, *progress*])

Export orthomosaic for the chunk.

Parameters

- **path** (*string*) – Path to output orthomosaic.
- **format** (*PhotoScan.RasterFormat*) – Export format.

- **image_format** (*PhotoScan.ImageFormat*) – Tile format.
- **raster_transform** (*PhotoScan.RasterTransformType*) – Raster band transformation.
- **projection** (*OrthoProjection* or *CoordinateSystem*) – Output coordinate system.
- **region** (*tuple of 4 floats*) – Region to be exported in the (x0, y0, x1, y1) format.
- **dx** (*float*) – Pixel size in the X dimension in projected units.
- **dy** (*float*) – Pixel size in the Y dimension in projected units.
- **blockw** (*int*) – Specifies block width of the orthomosaic in pixels.
- **blockh** (*int*) – Specifies block height of the orthomosaic in pixels.
- **width** (*int*) – Total width of the orthomosaic in pixels.
- **height** (*int*) – Total height of the orthomosaic in pixels.
- **world_transform** (*PhotoScan.Matrix*) – 2x3 raster-to-world transformation matrix.
- **write_kml** (*bool*) – Enables/disables kml file generation.
- **write_world** (*bool*) – Enables/disables world file generation.
- **write_scheme** (*bool*) – Enables/disables tile scheme files generation.
- **write_alpha** (*bool*) – Enables/disables alpha channel generation.
- **image_description** (*string*) – Optional description to be added to image files.
- **tiff_compression** (*PhotoScan.TiffCompression*) – Tiff compression.
- **tiff_big** (*bool*) – Enables/disables BigTIFF compression for TIFF files.
- **tiff_overviews** (*bool*) – Enables/disables image pyramid deneration for TIFF files.
- **jpeg_quality** (*int*) – JPEG quality.
- **network_links** (*bool*) – Enables/disables network links generation for KMZ format.
- **min_zoom_level** (*int*) – Minimum zoom level (Google Map Tiles, MBTiles and World Wind Tiles formats only).
- **max_zoom_level** (*int*) – Maximum zoom level (Google Map Tiles, MBTiles and World Wind Tiles formats only).
- **white_background** (*bool*) – Enables/disables white background.
- **progress** (*Callable[[float], None]*) – Progress callback.

exportOrthophotos (*path, cameras, raster_transform=RasterTransformNone* [, *projection*] [, *region*] [, *dx*] [, *dy*] [, *write_kml=False, write_world=False, write_alpha=True, tiff_compression=TiffCompressionLZW, tiff_big=False, tiff_overviews=True, jpeg_quality=90, white_background=True*] [, *progress*])

Export orthophoto for the chunk.

Parameters

- **path** (*string*) – Path to output orthophoto.
- **cameras** (list of *Camera*) – A list of cameras. If not specified or empty, all enabled cameras will be used.

- **raster_transform** (*PhotoScan.RasterTransformType*) – Raster band transformation.
- **projection** (*OrthoProjection* or *CoordinateSystem*) – Output coordinate system.
- **region** (*tuple of 4 floats*) – Region to be exported in the (x0, y0, x1, y1) format.
- **dx** (*float*) – Pixel size in the X dimension in projected units.
- **dy** (*float*) – Pixel size in the Y dimension in projected units.
- **write_kml** (*bool*) – Enables/disables kml file generation.
- **write_world** (*bool*) – Enables/disables world file generation.
- **write_alpha** (*bool*) – Enables/disables alpha channel generation.
- **tiff_compression** (*PhotoScan.TiffCompression*) – Tiff compression.
- **tiff_big** (*bool*) – Enables/disables BigTIFF compression for TIFF files.
- **tiff_overviews** (*bool*) – Enables/disables image pyramid deneration for TIFF files.
- **jpeg_quality** (*int*) – JPEG quality.
- **white_background** (*bool*) – Enables/disables white background.
- **progress** (*Callable[[float], None]*) – Progress callback.

exportPoints (*path* [, *source*], *binary=True*, *precision=6*, *normals=True*, *colors=True*, *raster_transform=RasterTransformNone* [, *comment*] [, *format*] [, *image_format*] [, *projection*] [, *shift*] [, *blockw*] [, *blockh*] [, *classes*] [, *progress*])

Export point cloud.

Parameters

- **path** (*string*) – Path to output file.
- **source** (*PhotoScan.DataSource*) – Selects between dense point cloud and sparse point cloud. If not specified, uses dense cloud if available.
- **binary** (*bool*) – Enables/disables binary encoding for selected format (if applicable).
- **precision** (*int*) – Number of digits after the decimal point (for text formats).
- **normals** (*bool*) – Enables/disables export of point normals.
- **colors** (*bool*) – Enables/disables export of point colors.
- **raster_transform** (*PhotoScan.RasterTransformType*) – Raster band transformation.
- **comment** (*string*) – Optional comment (if supported by selected format).
- **format** (*PhotoScan.PointsFormat*) – Export format.
- **image_format** (*PhotoScan.ImageFormat*) – Image data format.
- **projection** (*CoordinateSystem*) – Output coordinate system.
- **shift** (*3-element vector*) – Optional shift to be applied to vertex coordinates.
- **blockw** (*float*) – Tile width in meters.
- **blockh** (*float*) – Tile height in meters.

- **classes** (list of *PhotoScan.PointClass*) – List of dense point classes to be exported.
- **progress** (*Callable[[float], None]*) – Progress callback.

exportReport (*path* [, *title*] [, *description*] [, *settings*] [, *page_numbers*] [, *progress*])
 Export processing report in PDF format.

Parameters

- **path** (*string*) – Path to output report.
- **title** (*string*) – Report title.
- **description** (*string*) – Report description.
- **settings** (list of (*string*, *string*) tuples) – A list of user defined settings to include on the Processing Parameters page.
- **page_numbers** (*bool*) – Enable page numbers.
- **progress** (*Callable[[float], None]*) – Progress callback.

exportShapes (*path*, *items=Shape.Polygon* [, *groups*] [, *format*] [, *projection*] [, *shift*], *polygons_as_polylines=False*, *export_labels=True*, *export_attributes=True* [, *progress*])
 Export shapes layer to file.

Parameters

- **path** (*string*) – Path to shape file.
- **items** (*PhotoScan.Shape.Type*) – Items to export.
- **groups** (list of *ShapeGroup*) – A list of shape groups to export.
- **format** (*PhotoScan.ShapesFormat*) – Export format.
- **projection** (*CoordinateSystem*) – Output coordinate system.
- **shift** (*3-element vector*) – Optional shift to be applied to vertex coordinates.
- **polygons_as_polylines** (*bool*) – Save polygons as polylines.
- **export_labels** (*bool*) – Export labels.
- **export_attributes** (*bool*) – Export attributes.
- **progress** (*Callable[[float], None]*) – Progress callback.

exportTiledModel (*path*, *format=TiledModelFormatTLS*, *mesh_format=ModelFormatCOLLADA*, *raster_transform=RasterTransformNone* [, *progress*])
 Export generated tiled model for the chunk.

Parameters

- **path** (*string*) – Path to output model.
- **format** (*PhotoScan.TiledModelFormat*) – Export format.
- **mesh_format** (*PhotoScan.ModelFormat*) – Mesh format for zip export.
- **raster_transform** (*PhotoScan.RasterTransformType*) – Raster band transformation.
- **progress** (*Callable[[float], None]*) – Progress callback.

frame

Current frame index.

Type int

frames

List of frames in the chunk.

Type list of `Frame`

image_brightness

Image brightness as percentage.

Type float

importCameras (*path*, *format=CamerasFormatXML*)

Import camera positions.

Parameters

- **path** (*string*) – Path to the file.
- **format** (*PhotoScan.CamerasFormat*) – File format.

importDem (*path* [, *projection*] [, *progress*])

Import elevation model from file.

Parameters

- **path** (*string*) – Path to elevation model in GeoTIFF format.
- **projection** (*CoordinateSystem*) – Default coordinate system if not specified in GeoTIFF file.
- **progress** (*Callable[[float], None]*) – Progress callback.

importMarkers (*path*)

Import markers.

Parameters **path** (*string*) – Path to the file.

importMasks (*path*='', *source=MaskSourceAlpha*, *operation=MaskOperationReplacement*, *tolerance=10* [, *cameras*] [, *progress*])

Import masks for multiple cameras.

Parameters

- **path** (*string*) – Mask file name template.
- **source** (*PhotoScan.MaskSource*) – Mask source.
- **operation** (*PhotoScan.MaskOperation*) – Mask operation.
- **tolerance** (*int*) – Background masking tolerance.
- **cameras** (list of *Camera*) – Optional list of cameras to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

importModel (*path* [, *format*] [, *projection*] [, *shift*] [, *progress*])

Import model from file.

Parameters

- **path** (*string*) – Path to model.
- **format** (*PhotoScan.ModelFormat*) – Model format.
- **projection** (*CoordinateSystem*) – Model coordinate system.
- **shift** (*3-element vector*) – Optional shift to be applied to vertex coordinates.

- **progress** (*Callable*[[float], None]) – Progress callback.

importPoints (*path*[, *format*][, *projection*][, *shift*][, *progress*])
 Import point cloud from file.

Parameters

- **path** (*string*) – Path to point cloud.
- **format** (*PhotoScan.PointsFormat*) – Point cloud format.
- **projection** (*CoordinateSystem*) – Point cloud coordinate system.
- **shift** (*3-element vector*) – Optional shift to be applied to point coordinates.
- **progress** (*Callable*[[float], None]) – Progress callback.

importShapes (*path*='', *replace*=False, *boundary*=*Shape.NoBoundary*[, *format*])
 Import shapes layer from file.

Parameters

- **path** (*string*) – Path to shape file.
- **replace** (*bool*) – Replace current shapes with new data.
- **boundary** (*Shape.BoundaryType*) – Boundary type to be applied to imported shapes.
- **format** (*PhotoScan.ShapesFormat*) – Shapes format.

key

Chunk identifier.

Type int

label

Chunk label.

Type string

loadReference (*path*[, *format*], *columns*='nxyzabc', *delimiter*=' ', *group_delimiters*=False, *skip_rows*=0[, *items*][, *crs*], *ignore_labels*=False, *create_markers*=False, *threshold*=0.1[, *progress*])
 Import reference data from the specified file.

Parameters

- **path** (*string or stream object*) – Path to the file with reference data.
- **format** (*PhotoScan.ReferenceFormat*) – File format.
- **columns** (*string*) – column order in csv format (n - label, o - enabled flag, x/y/z - coordinates, X/Y/Z - coordinate accuracy, a/b/c - rotation angles, A/B/C - rotation angle accuracy, [] - group of multiple values, | - column separator within group).
- **delimiter** (*string*) – column delimiter in csv format.
- **group_delimiters** (*bool*) – combine consecutive delimiters in csv format.
- **skip_rows** (*int*) – number of rows to skip in (csv format only).
- **items** (list of *PhotoScan.ReferenceItems*) – list of items to load reference for (csv format only).
- **crs** (*CoordinateSystem*) – reference data coordinate system (csv format only).

- **ignore_labels** (*bool*) – matches reference data based on coordinates alone (csv format only).
- **create_markers** (*bool*) – create markers for missing entries (csv format only).
- **threshold** (*float*) – error threshold in meters used when ignore_labels is set (csv format only).
- **progress** (*Callable[[float], None]*) – Progress callback.

Example

```
>>> loadReference('reference.csv', 'nxyz[XYZ]abc[ABC]')
>>> loadReference('reference.csv', '[n|x|y|z|XYZ|a|b|c|ABC]')
```

loadReferenceExif (*load_rotation=False, load_accuracy=False*)

Import camera locations from EXIF meta data.

Parameters

- **load_rotation** (*bool*) – load yaw, pitch and roll orientation angles.
- **load_accuracy** (*bool*) – load camera location accuracy.

loadReflectancePanelCalibration (*path[, cameras]*)

Load reflectance panel calibration from CSV file.

Parameters

- **path** (*string*) – Path to calibration file.
- **cameras** (list of *Camera*) – List of cameras to process.

locateReflectancePanels (*[progress]*)

Locate reflectance panels based on QR-codes.

Parameters **progress** (*Callable[[float], None]*) – Progress callback.

marker_crs

Coordinate system used for marker reference data.

Type *CoordinateSystem*

marker_groups

List of marker groups in the chunk.

Type list of *MarkerGroup*

marker_location_accuracy

Expected accuracy of marker coordinates in meters.

Type *Vector*

marker_projection_accuracy

Expected accuracy of marker projections in pixels.

Type float

markers

List of markers in the chunk.

Type list of *Marker*

masks

Image masks.

Type *Masks*

matchPhotos (*accuracy=HighAccuracy*, *preselection=ReferencePreselection*,
generic_preselection=True, *reference_preselection=True*, *filter_mask=False*,
mask_tiepoints=False, *keypoint_limit=40000*, *tiepoint_limit=4000*,
keep_keypoints=True, *pairs* [, *progress*])

Perform image matching for the chunk frame.

Parameters

- **accuracy** (*PhotoScan.Accuracy*) – Alignment accuracy.
- **preselection** (*PhotoScan.Preselection*) – Image pair preselection method (obsolete).
- **generic_preselection** (*bool*) – Enables generic image pair preselection.
- **reference_preselection** (*bool*) – Enables reference image pair preselection.
- **filter_mask** (*bool*) – Filter points by mask.
- **mask_tiepoints** (*bool*) – Apply mask filter to tie points.
- **keypoint_limit** (*int*) – Maximum number of key points to look for in each photo.
- **tiepoint_limit** (*int*) – Maximum number of tie points to generate for each photo.
- **keep_keypoints** (*bool*) – Store keypoints in the project.
- **pairs** (list of *PhotoScan.Camera* tuples) – User defined list of camera pairs to match.
- **progress** (*Callable[[float], None]*) – Progress callback.

meta

Chunk meta data.

Type *MetaData*

model

Default model for the current frame.

Type *Model*

models

List of models for the current frame.

Type list of *Model*

modified

Modified flag.

Type *bool*

optimizeCameras (*fit_f=True*, *fit_cx=True*, *fit_cy=True*, *fit_b1=True*, *fit_b2=True*, *fit_k1=True*,
fit_k2=True, *fit_k3=True*, *fit_k4=False*, *fit_p1=True*, *fit_p2=True*, *fit_p3=False*,
fit_p4=False, *adaptive_fitting=False*, *progress*])

Perform optimization of point cloud / camera parameters.

Parameters

- **fit_f** (*bool*) – Enables optimization of focal length coefficient.
- **fit_cx** (*bool*) – Enables optimization of X principal point coordinates.
- **fit_cy** (*bool*) – Enables optimization of Y principal point coordinates.
- **fit_b1** (*bool*) – Enables optimization of aspect ratio.
- **fit_b2** (*bool*) – Enables optimization of skew coefficient.

- **fit_k1** (*bool*) – Enables optimization of k1 radial distortion coefficient.
- **fit_k2** (*bool*) – Enables optimization of k2 radial distortion coefficient.
- **fit_k3** (*bool*) – Enables optimization of k3 radial distortion coefficient.
- **fit_k4** (*bool*) – Enables optimization of k4 radial distortion coefficient.
- **fit_p1** (*bool*) – Enables optimization of p1 tangential distortion coefficient.
- **fit_p2** (*bool*) – Enables optimization of p2 tangential distortion coefficient.
- **fit_p3** (*bool*) – Enables optimization of p3 tangential distortion coefficient.
- **fit_p4** (*bool*) – Enables optimization of p4 tangential distortion coefficient.
- **adaptive_fitting** (*bool*) – Enables adaptive fitting of calibration coefficients.
- **progress** (*Callable[[float], None]*) – Progress callback.

orthomosaic

Default orthomosaic for the current frame.

Type *Orthomosaic*

orthomosaics

List of orthomosaics for the current frame.

Type list of *Orthomosaic*

point_cloud

Generated sparse point cloud.

Type *PointCloud*

primary_channel

Primary channel index (-1 for default).

Type *int*

raster_transform

Raster transform.

Type *RasterTransform*

refineMarkers (*[markers][, progress]*)

Refine markers based on images content.

Parameters

- **markers** (list of *Marker*) – Optional list of markers to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

refineModel (*quality=MediumQuality, iterations=10, smoothness=0.5[, progress]*)

Generate model for the chunk frame.

Parameters

- **quality** (*PhotoScan.Quality*) – Quality of refinement.
- **iterations** (*int*) – Number of refinement iterations.
- **smoothness** (*float*) – Smoothing strength. Should be in range [0, 1].
- **progress** (*Callable[[float], None]*) – Progress callback.

region

Reconstruction volume selection.

Type *Region*

remove (*items*)

Remove items from the chunk.

Parameters *items* (list of *Frame*, *Sensor*, *CameraGroup*, *MarkerGroup*, *ScalebarGroup*, *Camera*, *Marker* or *Scalebar*) – A list of items to be removed.

removeLighting (*color_mode=SingleColor*, *internal_blur=1.0*, *mesh_noise_suppression=1.5*, *ambient_occlusion_path=''*, *ambient_occlusion_multiplier=1.0* [, *progress*])

Generate model for the chunk frame.

Parameters

- **color_mode** (*PhotoScan.DelightingColorMode*) – Color mode of model to be delighted.
- **internal_blur** (*float*) – Internal blur. Should be in range [0, 4].
- **mesh_noise_suppression** (*float*) – Mesh normals noise suppression strength. Should be in range [0, 4].
- **ambient_occlusion_path** (*string*) – Path to ambient occlusion texture atlas. Can be empty.
- **ambient_occlusion_multiplier** (*float*) – Ambient occlusion multiplier. Should be in range [0.25, 4].
- **progress** (*Callable[[float], None]*) – Progress callback.

resetRegion ()

Reset reconstruction volume selector to default position.

saveReference (*path* [, *format*], *items=ReferenceItemsCameras* [, *columns*], *delimiter=''* [, *progress*])

Export reference data to the specified file.

Parameters

- **path** (*string*) – Path to the output file.
- **format** (*PhotoScan.ReferenceFormat*) – Export format.
- **items** (*PhotoScan.ReferenceItems*) – Items to export in CSV format.
- **columns** (*string*) – column order in csv format (n - label, o - enabled flag, x/y/z - coordinates, X/Y/Z - coordinate accuracy, a/b/c - rotation angles, A/B/C - rotation angle accuracy, u/v/w - estimated coordinates, U/V/W - coordinate errors, d/e/f - estimated orientation angles, D/E/F - orientation errors, [] - group of multiple values, | - column separator within group)
- **delimiter** (*string*) – column delimiter in csv format
- **progress** (*Callable[[float], None]*) – Progress callback.

scalebar_accuracy

Expected scale bar accuracy in meters.

Type *float*

scalebar_groups

List of scale bar groups in the chunk.

Type list of *ScalebarGroup*

scalebars

List of scale bars in the chunk.

Type list of *Scalebar*

selected

Selects/deselects the chunk.

Type bool

sensors

List of sensors in the chunk.

Type list of *Sensor*

shapes

Shapes for the current frame.

Type *Shapes*

smoothModel (*strength = 3, selected_faces = False, fix_borders = True*, *progress*)

Smooth mesh using Laplacian smoothing algorithm.

Parameters

- **strength** (*float*) – Smoothing strength.
- **selected_faces** (*bool*) – Smooth only selected faces.
- **fix_borders** (*bool*) – Fix vertices on borders.
- **progress** (*Callable[[float], None]*) – Progress callback.

sortCameras ()

Sorts cameras by their labels.

sortMarkers ()

Sorts markers by their labels.

sortScalebars ()

Sorts scalebars by their labels.

thinPointCloud (*point_limit=1000*)

Remove excessive tracks from the point cloud.

Parameters **point_limit** (*int*) – Maximum number of points for each photo.

thumbnails

Image thumbnails.

Type *Thumbnails*

tiepoint_accuracy

Expected tie point accuracy in pixels.

Type float

tiled_model

Default tiled model for the current frame.

Type *TiledModel*

tiled_models

List of tiled models for the current frame.

Type list of *TiledModel*

trackMarkers (*start* [, *end*] [, *progress*])
Track marker projections through the frame sequence.

Parameters

- **start** (*int*) – Starting frame index.
- **end** (*int*) – Ending frame index.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

transform
4x4 matrix specifying chunk location in the world coordinate system.

Type *ChunkTransform*

updateTransform ()
Update chunk transformation based on reference data.

world_crs
Coordinate system used as world coordinate system.

Type *CoordinateSystem*

class *PhotoScan*.**ChunkTransform**
Transformation between chunk and world coordinates systems.

matrix
Transformation matrix.

Type *Matrix*

rotation
Rotation component.

Type *Matrix*

scale
Scale component.

Type *float*

translation
Translation component.

Type *Vector*

class *PhotoScan*.**CirTransform**
CIR calibration matrix.

calibrate ()
Calibrate CIR matrix based on orthomosaic histogram.

coeffs
Color matrix.

Type *Matrix*

reset ()
Reset CIR calibration matrix.

class *PhotoScan*.**CoordinateSystem**
Coordinate reference system (local, geographic or projected).

The following example changes chunk coordinate system to WGS 84 / UTM zone 41N and loads reference data from file:

```

>>> import PhotoScan
>>> chunk = PhotoScan.app.document.chunk
>>> chunk.crs = PhotoScan.CoordinateSystem("EPSG::32641")
>>> chunk.loadReference("gcp.txt", PhotoScan.ReferenceFormatCSV)
>>> chunk.updateTransform()

```

addGeoid (*path*)

Register geoid model.

Parameters **path** (*string*) – Path to geoid file.

authority

Authority identifier of the coordinate system.

Type *string*

geoccs

Base geocentric coordinate system.

Type *CoordinateSystem*

geogcs

Base geographic coordinate system.

Type *CoordinateSystem*

geoid_height

Fixed geoid height to be used instead of interpolated values.

Type *float*

init (*crs*)

Initialize projection based on specified WKT definition or authority identifier.

Parameters **crs** (*string*) – WKT definition of coordinate system or authority identifier.

listBuiltinCRS ()

Returns a list of builtin coordinate systems.

localframe (*point*)

Returns 4x4 transformation matrix to LSE coordinates at the given point.

Parameters **point** (*Vector*) – Coordinates of the origin in the geocentric coordinates.

Returns Transformation from geocentric coordinates to local coordinates.

Return type *Matrix*

name

Name of the coordinate system.

Type *string*

proj4

Coordinate system definition in PROJ.4 format.

Type *string*

project (*point*)

Projects point from geocentric coordinates to projected geographic coordinate system.

Parameters **point** (*Vector*) – 3D point in geocentric coordinates.

Returns 3D point in projected coordinates.

Return type *Vector*

ttransform (*point*, *source*, *target*)

Transform point coordinates between coordinate systems.

Parameters

- **point** (2 or 3 component *Vector*) – Point coordinates.
- **source** (*CoordinateSystem*) – Source coordinate system.
- **target** (*CoordinateSystem*) – Target coordinate system.

Returns Transformed point coordinates.

Return type *Vector*

transformationMatrix (*point*, *source*, *target*)

Local approximation of coordinate transformation from source to target coordinate system at the given point.

Parameters

- **point** (3 component *Vector*) – Point coordinates.
- **source** (*CoordinateSystem*) – Source coordinate system.
- **target** (*CoordinateSystem*) – Target coordinate system.

Returns 4x4 transformation matrix.

Return type *Matrix*

unproject (*point*)

Unprojects point from projected coordinates to geocentric coordinates.

Parameters **point** (*Vector*) – 3D point in projected coordinate system.

Returns 3D point in geocentric coordinates.

Return type *Vector*

wkt

Coordinate system definition in WKT format.

Type string

wkt2

Coordinate system definition in WKT format, version 2.

Type string

class `PhotoScan.DataSource`

Data source in [PointCloudData, DenseCloudData, DepthMapsData, ModelData, TiledModelData, ElevationData, OrthomosaicData, ImagesData]

class `PhotoScan.DenseCloud`

Dense point cloud data.

assignClass (*target=0* [, *source*] [, *progress*])

Assign class to points.

Parameters

- **target** (`PhotoScan.PointClass`) – Target class.
- **source** (`PhotoScan.PointClass` or list of `PhotoScan.PointClass`) – Classes of points to be replaced.
- **progress** (`Callable[[float], None]`) – Progress callback.

assignClassToSelection (*target=0*[, *source*][, *progress*])

Assign class to selected points.

Parameters

- **target** (*PhotoScan.PointClass*) – Target class.
- **source** (*PhotoScan.PointClass* or list of *PhotoScan.PointClass*) – Classes of points to be replaced.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

classifyGroundPoints (*max_angle=15.0*, *max_distance=1.0*, *cell_size=50.0*[, *source*][, *progress*])

Classify points into ground and non ground classes.

Parameters

- **max_angle** (*float*) – Maximum angle (degrees).
- **max_distance** (*float*) – Maximum distance (meters).
- **cell_size** (*float*) – Cell size (meters).
- **source** (*PhotoScan.PointClass*) – Class of points to be re-classified.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

clear ()

Clears dense cloud data.

compactPoints ([*progress*])

Permanently removes deleted points from dense cloud.

Parameters **progress** (*Callable*[[*float*], *None*]) – Progress callback.

copy ()

Create a copy of the dense cloud.

Returns Copy of the dense cloud.

Return type *DenseCloud*

cropSelectedPoints ([*point_classes*][, *progress*])

Crop selected points.

Parameters

- **point_classes** (*PhotoScan.PointClass* or list of *PhotoScan.PointClass*) – Classes of points to be removed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

crs

Reference coordinate system.

Type *CoordinateSystem* or *None*

key

Dense cloud identifier.

Type *int*

label

Dense cloud label.

Type *string*

meta

Dense cloud meta data.

Type *MetaData*

modified

Modified flag.

Type `bool`

pickPoint (*origin, target*)

Returns ray intersection with the point cloud (point on the ray nearest to some point).

Parameters

- **origin** (*PhotoScan.Vector*) – Ray origin.
- **target** (*PhotoScan.Vector*) – Point on the ray.

Returns Coordinates of the intersection point.

Return type *PhotoScan.Vector*

point_count

Number of points in dense cloud.

Type `int`

removePoints (*point_classes* [, *progress*])

Remove points.

Parameters

- **point_classes** (*PhotoScan.PointClass* or list of *PhotoScan.PointClass*) – Classes of points to be removed.
- **progress** (*Callable[[float], None]*) – Progress callback.

removeSelectedPoints ([*point_classes*] [, *progress*])

Remove selected points.

Parameters

- **point_classes** (*PhotoScan.PointClass* or list of *PhotoScan.PointClass*) – Classes of points to be removed.
- **progress** (*Callable[[float], None]*) – Progress callback.

restorePoints ([*point_classes*] [, *progress*])

Restore deleted points.

Parameters

- **point_classes** (*PhotoScan.PointClass* or list of *PhotoScan.PointClass*) – Classes of points to be restored.
- **progress** (*Callable[[float], None]*) – Progress callback.

selectMaskedPoints (*cameras, softness=4* [, *progress*])

Select dense points based on image masks.

Parameters

- **cameras** (list of *Camera*) – A list of cameras to use for selection.
- **softness** (*float*) – Mask edge softness.
- **progress** (*Callable[[float], None]*) – Progress callback.

selectPointsByColor (*color*, *tolerance=10*, *channels='RGB'*, [*progress*])
 Select dense points based on point colors.

Parameters

- **color** (*list of int*) – Color to select.
- **tolerance** (*int*) – Color tolerance.
- **channels** (*string*) – Combination of color channels to compare in ['R', 'G', 'B', 'H', 'S', 'V'].
- **progress** (*Callable[[float], None]*) – Progress callback.

transform

4x4 dense cloud transformation matrix.

Type *Matrix*

updateStatistics ([*progress*])
 Updates dense cloud statistics.

Parameters **progress** (*Callable[[float], None]*) – Progress callback.

class PhotoScan.**DepthMap**

Depth map data.

calibration

Depth map calibration.

Type *Calibration*

copy ()

Returns a copy of the depth map.

Returns Copy of the depth map.

Return type *DepthMap*

image ()

Returns image data.

Returns Image data.

Return type *Image*

setImage (*image*)

Parameters **image** (*Image*) – Image object with depth map data.

class PhotoScan.**DepthMaps**

A set of depth maps generated for a chunk frame.

clear ()

Clears depth maps data.

copy ()

Create a copy of the depth maps.

Returns Copy of the depth maps.

Return type *DepthMaps*

items ()

List of items.

key
Depth maps identifier.

Type int

keys ()
List of item keys.

label
Depth maps label.

Type string

meta
Depth maps meta data.

Type *MetaData*

modified
Modified flag.

Type bool

values ()
List of item values.

class `PhotoScan.Document`
PhotoScan project.

Contains list of chunks available in the project. Implements processing operations that work with multiple chunks. Supports saving/loading project files.

The project currently opened in PhotoScan window can be accessed using `PhotoScan.app.document` attribute. Additional Document objects can be created as needed.

The following example saves active chunk from the opened project in a separate project:

```
>>> import PhotoScan
>>> doc = PhotoScan.app.document
>>> doc.save(path = "project.psz", chunks = [doc.chunk])
```

addChunk ()
Add new chunk to the document.

Returns Created chunk.

Return type *Chunk*

alignChunks (*chunks*, *reference*, *method*='points', *fix_scale*=False, *accuracy*=HighAccuracy, *preselection*=False, *filter_mask*=False, *point_limit*=40000[, *progress*])
Align specified set of chunks.

Parameters

- **chunks** (*list*) – List of chunks to be aligned.
- **reference** (*Chunk*) – Chunk to be used as a reference.
- **method** (*string*) – Alignment method in ['points', 'markers', 'cameras'].
- **fix_scale** (*bool*) – Fixes chunk scale during alignment.
- **accuracy** (*PhotoScan.Accuracy*) – Alignment accuracy.
- **preselection** (*bool*) – Enables image pair preselection.

- **filter_mask** (*bool*) – Filter points by mask.
- **point_limit** (*int*) – Maximum number of points for each photo.
- **progress** (*Callable[[float], None]*) – Progress callback.

append (*document* [, *chunks*] [, *progress*])

Append the specified Document object to the current document.

Parameters

- **document** (*Document*) – Document object to be appended.
- **chunks** (list of *Chunk*) – List of chunks to append.
- **progress** (*Callable[[float], None]*) – Progress callback.

chunk

Active chunk.

Type *Chunk*

chunks

List of chunks in the document.

Type Chunks

clear ()

Clear the contents of the Document object.

mergeChunks (*chunks*, *merge_dense_clouds*=*False*, *merge_models*=*False*, *merge_markers*=*False* [, *progress*])

Merge specified set of chunks.

Parameters

- **chunks** (*list*) – List of chunks to be merged.
- **merge_dense_clouds** (*bool*) – Enables/disables merging of dense clouds.
- **merge_models** (*bool*) – Enables/disables merging of polygonal models.
- **merge_markers** (*bool*) – Enables/disables merging of corresponding marker across the chunks.
- **progress** (*Callable[[float], None]*) – Progress callback.

meta

Document meta data.

Type *MetaData*

modified

Modified flag.

Type bool

open (*path*, *read_only*=*False*)

Load document from the specified file.

Parameters

- **path** (*string*) – Path to the file.
- **read_only** (*bool*) – Open document in read-only mode.

path

Path to the document file.

Type string

read_only

Read only status.

Type bool

remove (*items*)

Remove a set of items from the document.

Parameters *items* (list of *Chunk*) – A list of items to be removed.

save ([*path*] [, *chunks*], *compression* = 6, *absolute_paths* = *False* [, *version*])

Save document to the specified file.

Parameters

- **path** (*string*) – Optional path to the file.
- **chunks** (list of *Chunk*) – List of chunks to be saved.
- **compression** (*int*) – Project compression level.
- **absolute_paths** (*bool*) – Store absolute image paths.
- **version** (*string*) – Project version to save.

class PhotoScan.**Elevation**

Digital elevation model.

altitude (*point*)

Return elevation value at the specified point.

Parameters *point* (*PhotoScan.Vector*) – Point coordinates in the levation coordinate system.

Returns Elevation value.

Return type float

bottom

Y coordinate of the bottom side.

Type float

clear ()

Clears elevation model data.

copy ()

Create a copy of the elevation model.

Returns Copy of the elevation model.

Return type *Elevation*

crs

Coordinate system of elevation model.

Type *CoordinateSystem*

height

Elevation model height.

Type int

key

Elevation model identifier.

Type int

label

Elevation model label.

Type string

left

X coordinate of the left side.

Type float

max

Maximum elevation value.

Type float

meta

Elevation model meta data.

Type *MetaData*

min

Minimum elevation value.

Type float

modified

Modified flag.

Type bool

projection

Projection of elevation model.

Type *OrthoProjection*

resolution

DEM resolution in meters.

Type float

right

X coordinate of the right side.

Type float

top

Y coordinate of the top side.

Type float

width

Elevation model width.

Type int

class PhotoScan.**EulerAngles**

Euler angles in [EulerAnglesYPR, EulerAnglesOPK]

class PhotoScan.**FaceCount**

Face count in [LowFaceCount, MediumFaceCount, HighFaceCount]

class PhotoScan.**FilterMode**

Depth filtering mode in [NoFiltering, MildFiltering, ModerateFiltering, AggressiveFiltering]

class PhotoScan.**Image** (*width, height, channels, datatype='U8'*)
n-channel image

Parameters

- **width** (*int*) – image width
- **height** (*int*) – image height
- **channels** (*string*) – color channel layout, e.g. 'RGB', 'RGBA', etc.
- **datatype** (*string*) – pixel data type in ['U8', 'U16', 'U32', 'F16', 'F32', 'F64']

channels

Channel mapping for the image.

Type string

cn

Number of color channels.

Type int

convert (*channels[, datatype]*)

Convert image to specified data type and channel layout.

Parameters

- **channels** (*string*) – color channels to be loaded, e.g. 'RGB', 'RGBA', etc.
- **datatype** (*string*) – pixel data type in ['U8', 'U16', 'U32', 'F16', 'F32', 'F64']

Returns Converted image.

Return type *Image*

copy ()

Return a copy of the image.

Returns copy of the image

Return type *Image*

data_type

Data type used to store pixel values.

Type string

fromstring (*data, width, height, channels, datatype='U8'*)

Create image from byte array.

Parameters

- **data** (*string*) – raw image data
- **width** (*int*) – image width
- **height** (*int*) – image height
- **channels** (*string*) – color channel layout, e.g. 'RGB', 'RGBA', etc.
- **datatype** (*string*) – pixel data type in ['U8', 'U16', 'U32', 'F16', 'F32', 'F64']

Returns Created image.

Return type *Image*

gaussianBlur (*radius*)

Smooth image with a gaussian filter.

Parameters **radius** (*float*) – smoothing radius.

Returns Smoothed image.

Return type *Image*

height

Image height.

Type *int*

open (*path*, *layer=0*, *datatype='U8'* [, *channels*])

Load image from file.

Parameters

- **path** (*string*) – path to the image file
- **layer** (*int*) – image layer in case of multipage file
- **datatype** (*string*) – pixel data type in ['U8', 'U16', 'U32', 'F16', 'F32', 'F64']
- **channels** (*string*) – color channels to be loaded, e.g. 'RGB', 'RGBA', etc.

Returns Loaded image.

Return type *Image*

resize (*width*, *height*)

Resize image to specified dimensions.

Parameters

- **width** (*int*) – new image width
- **height** (*int*) – new image height

Returns resized image

Return type *Image*

save (*path*)

Save image to the file.

Parameters **path** (*string*) – path to the image file

tostring ()

Convert image to byte array.

Returns Raw image data.

Return type *string*

undistort (*calib*, *center_principal_point = True*, *square_pixels = True*)

Undistort image using provided calibration.

Parameters

- **calib** (*Calibration*) – lens calibration
- **center_principal_point** (*bool*) – moves principal point to the image center
- **square_pixels** (*bool*) – create image with square pixels

Returns undistorted image

Return type *Image*

uniformNoise (*amplitude*)

Add uniform noise with specified amplitude.

Parameters **amplitude** (*float*) – noise amplitude.

Returns Image with added noise.

Return type *Image*

warp (*calib0, trans0, calib1, trans1*)

Warp image by rotating virtual viewpoint.

Parameters

- **calib0** (*Calibration*) – initial calibration
- **trans0** (*Matrix*) – initial camera orientation as 4x4 matrix
- **calib1** (*Calibration*) – final calibration
- **trans1** (*Matrix*) – final camera orientation as 4x4 matrix

Returns warped image

Return type *Image*

width

Image width.

Type int

class PhotoScan.**ImageFormat**

Image format in [ImageFormatNone, ImageFormatJPEG, ImageFormatTIFF, ImageFormatPNG, ImageFormatBMP, ImageFormatEXR, ImageFormatPNM, ImageFormatSGI, ImageFormatCR2, ImageFormatSEQ, ImageFormatARA, ImageFormatTGA, ImageFormatJP2]

class PhotoScan.**ImageLayout**

Image layout in [UndefinedLayout, FlatLayout, MultiframeLayout, MultiplaneLayout]

class PhotoScan.**Interpolation**

Interpolation mode in [DisabledInterpolation, EnabledInterpolation, Extrapolated]

class PhotoScan.**MappingMode**

UV mapping mode in [LegacyMapping, GenericMapping, OrthophotoMapping, AdaptiveOrthophotoMapping, SphericalMapping, CameraMapping]

class PhotoScan.**Marker**

Marker instance

class **Projection**

Marker data().

coord

Point coordinates in pixels.

Type *Vector*

pinned

Pinned flag.

Type bool

valid

Valid flag.

Type bool

class `Marker.Projections`
Collection of projections specified for the marker

- items** ()
List of items.
- keys** ()
List of item keys.
- values** ()
List of item values.

class `Marker.Reference`
Marker reference data.

- accuracy**
Marker location accuracy.
Type *Vector*
- enabled**
Enabled flag.
Type `bool`
- location**
Marker coordinates.
Type *Vector*

class `Marker.Type`
Marker type in [Regular, Vertex, Fiducial]

`Marker.chunk`
Chunk the marker belongs to.
Type *Chunk*

`Marker.frames`
Marker frames.
Type list of *Marker*

`Marker.group`
Marker group.
Type *MarkerGroup*

`Marker.key`
Marker identifier.
Type `int`

`Marker.label`
Marker label.
Type `string`

`Marker.meta`
Marker meta data.
Type *MetaData*

`Marker.position`
Marker position in the current frame.
Type *Vector*

`Marker.projections`

List of marker projections.

Type `MarkerProjections`

`Marker.reference`

Marker reference data.

Type `MarkerReference`

`Marker.selected`

Selects/deselects the marker.

Type `bool`

`Marker.sensor`

Fiducial mark sensor.

Type `Sensor`

`Marker.type`

Marker type.

Type `Marker.Type`

class `PhotoScan.MarkerGroup`

`MarkerGroup` objects define groups of multiple markers. The grouping is established by assignment of a `MarkerGroup` instance to the `Marker.group` attribute of participating markers.

label

Marker group label.

Type `string`

selected

Current selection state.

Type `bool`

class `PhotoScan.Mask`

Mask instance

copy ()

Returns a copy of the mask.

Returns Copy of the mask.

Return type `Mask`

image ()

Returns image data.

Returns Image data.

Return type `Image`

invert ()

Create inverted copy of the mask.

Returns Inverted copy of the mask.

Return type `Mask`

load (*path* [, *layer*])

Loads mask from file.

Parameters

- **path** (*string*) – Path to the image file to be loaded.
- **layer** (*int*) – Optional layer index in case of multipage files.

setImage (*image*)

Parameters **image** (*Image*) – Image object with mask data.

class PhotoScan.**MaskOperation**

Mask operation in [MaskOperationReplacement, MaskOperationUnion, MaskOperationIntersection, MaskOperationDifference]

class PhotoScan.**MaskSource**

Mask source in [MaskSourceAlpha, MaskSourceFile, MaskSourceBackground, MaskSourceModel]

class PhotoScan.**Masks**

A set of masks for a chunk frame.

items ()

List of items.

keys ()

List of item keys.

meta

Thumbnails meta data.

Type *MetaData*

modified

Modified flag.

Type bool

values ()

List of item values.

class PhotoScan.**Matrix**

m-by-n matrix

```
>>> import PhotoScan
>>> m1 = PhotoScan.Matrix.Diag( (1,2,3,4) )
>>> m3 = PhotoScan.Matrix( [[1,2,3,4], [1,2,3,4], [1,2,3,4], [1,2,3,4]] )
>>> m2 = m1.inv()
>>> m3 = m1 * m2
>>> x = m3.det()
>>> if x == 1:
...     PhotoScan.app.messageBox("Diagonal matrix dimensions: " + str(m3.size))
```

Diag (*vector*)

Create a diagonal matrix.

Parameters **vector** (*Vector* or list of floats) – The vector of diagonal entries.

Returns A diagonal matrix.

Return type *Matrix*

Rotation (*matrix*)

Create a rotation matrix.

Parameters **matrix** (*Matrix*) – The 3x3 rotation matrix.

Returns 4x4 matrix representing rotation.

Return type *Matrix*

Scale (*scale*)

Create a scale matrix.

Parameters **scale** (*Vector*) – The scale vector.

Returns A matrix representing scale.

Return type *Matrix*

Translation (*vector*)

Create a translation matrix.

Parameters **vector** (*Vector*) – The translation vector.

Returns A matrix representing translation.

Return type *Matrix*

col (*index*)

Returns column of the matrix.

Returns matrix column.

Return type *Vector*

copy ()

Returns a copy of this matrix.

Returns an instance of itself

Return type *Matrix*

det ()

Return the determinant of a matrix.

Returns Return a the determinant of a matrix.

Return type float

inv ()

Returns an inverted copy of the matrix.

Returns inverted matrix.

Return type *Matrix*

mulp (*point*)

Transforms a point in homogeneous coordinates.

Parameters **point** (*Vector*) – The point to be transformed.

Returns transformed point.

Return type *Vector*

mulv (*vector*)

Transforms vector in homogeneous coordinates.

Parameters **vector** (*Vector*) – The vector to be transformed.

Returns transformed vector.

Return type *Vector*

rotation ()

Returns rotation component of the 4x4 matrix.

Returns rotation component

Return type *Matrix*

row (*index*)

Returns row of the matrix.

Returns matrix row.

Return type *Vector*

scale ()

Returns scale component of the 4x4 matrix.

Returns scale component

Return type float

size

Matrix dimensions.

Type tuple

svd ()

Returns singular value decomposition of the matrix.

Returns u, s, v tuple where $a = u * \text{diag}(s) * v$

Return type *PhotoScan.Matrix PhotoScan.Vector PhotoScan.Matrix* tuple

t ()

Return a new, transposed matrix.

Returns a transposed matrix

Return type *Matrix*

translation ()

Returns translation component of the 4x4 matrix.

Returns translation component

Return type *Vector*

zero ()

Set all matrix elements to zero.

class *PhotoScan*.**MetaData** (*object*)

Collection of object properties

items ()

List of items.

keys ()

List of item keys.

values ()

List of item values.

class *PhotoScan*.**Model**

Triangular mesh model instance

class **Face**

Triangular face of the model

hidden

Face visibility flag.

Type bool

selected
Face selection flag.
Type bool

tex_vertices
Texture vertex indices.
Type tuple of 3 int

vertices
Vertex indices.
Type tuple of 3 int

class `Model.Faces`
Collection of model faces

class `Model.Statistics`
Mesh statistics

components
Number of connected components.
Type int

degenerate_faces
Number of degenerate faces.
Type int

duplicate_faces
Number of duplicate faces.
Type int

faces
Total number of faces.
Type int

flipped_normals
Number of edges with flipped normals.
Type int

free_vertices
Number of free vertices.
Type int

multiple_edges
Number of edges connecting more than 2 faces.
Type int

open_edges
Number of open edges.
Type int

out_of_range_indices
Number of out of range indices.
Type int

similar_vertices
Number of similar vertices.
Type int

vertices
Total number of vertices.

Type int

zero_faces
Number of zero faces.

Type int

class `Model.TexVertex`
Texture vertex of the model

coord
Vertex coordinates.
Type tuple of 2 float

class `Model.TexVertices`
Collection of model texture vertices

class `Model.Vertex`
Vertex of the model

color
Vertex color.
Type tuple of 3 int

coord
Vertex coordinates.
Type *Vector*

class `Model.Vertices`
Collection of model vertices

`Model.area()`
Return area of the model surface.
Returns Model area.
Return type float

`Model.clear()`
Clears model data.

`Model.closeHoles(level = 30)`
Fill holes in the model surface.
Parameters `level` (*int*) – Hole size threshold in percents.

`Model.copy()`
Create a copy of the model.
Returns Copy of the model.
Return type *Model*

`Model.cropSelection()`
Crop selected faces and free vertices from the mesh.

`Model.faces`
Collection of mesh faces.
Type *MeshFaces*

`Model.fixTopology()`
Remove polygons causing topological problems.

`Model.key`
Model identifier.

Type int

`Model.label`

Model label.

Type string

`Model.loadTexture` (*path*)

Load texture from the specified file.

Parameters `path` (*string*) – Path to the image file.

`Model.meta`

Model meta data.

Type *MetaData*

`Model.modified`

Modified flag.

Type bool

`Model.pickPoint` (*origin, target*)

Return ray intersection with mesh.

Parameters

- **origin** (*PhotoScan.Vector*) – Ray origin.
- **target** (*PhotoScan.Vector*) – Point on the ray.

Returns Coordinates of the intersection point.

Return type *PhotoScan.Vector*

`Model.removeComponents` (*size*)

Remove small connected components.

Parameters `size` (*int*) – Threshold on the polygon count of the components to be removed.

`Model.removeSelection` ()

Remove selected faces and free vertices from the mesh.

`Model.renderDepth` (*transform, calibration*)

Render model depth image for specified viewpoint.

Parameters

- **transform** (*Matrix*) – Camera location.
- **calibration** (*Calibration*) – Camera calibration.

Returns Rendered image.

Return type *Image*

`Model.renderImage` (*transform, calibration*)

Render model image for specified viewpoint.

Parameters

- **transform** (*Matrix*) – Camera location.
- **calibration** (*Calibration*) – Camera calibration.

Returns Rendered image.

Return type *Image*

`Model.renderMask` (*transform*, *calibration*)

Render model mask image for specified viewpoint.

Parameters

- **transform** (*Matrix*) – Camera location.
- **calibration** (*Calibration*) – Camera calibration.

Returns Rendered image.

Return type *Image*

`Model.renderNormalMap` (*transform*, *calibration*)

Render image with model normals for specified viewpoint.

Parameters

- **transform** (*Matrix*) – Camera location.
- **calibration** (*Calibration*) – Camera calibration.

Returns Rendered image.

Return type *Image*

`Model.saveTexture` (*path*)

Save texture to the specified file.

Parameters **path** (*string*) – Path to the image file.

`Model.setTexture` (*image*, *page=0*)

Initialize texture from image data.

Parameters

- **image** (*Image*) – Texture image.
- **page** (*int*) – Texture index for multitextured models.

`Model.statistics` (*[progress]*)

Return mesh statistics.

Parameters **progress** (*Callable[[float], None]*) – Progress callback.

Returns Mesh statistics.

Return type *Model.Statistics*

`Model.tex_vertices`

Collection of mesh texture vertices.

Type *MeshTexVertices*

`Model.texture` (*page=0*)

Return texture image.

Parameters **page** (*int*) – Texture index for multitextured models.

Returns Texture image.

Return type *Image*

`Model.vertices`

Collection of mesh vertices.

Type *MeshVertices*

`Model.volume()`

Return volume of the closed model surface.

Returns Model volume.

Return type float

class `PhotoScan.ModelFormat`

Model format in [`ModelFormatNone`, `ModelFormatOBJ`, `ModelFormat3DS`, `ModelFormatVRML`, `ModelFormatPLY`, `ModelFormatCOLLADA`, `ModelFormatU3D`, `ModelFormatPDF`, `ModelFormatDXF`, `ModelFormatFBX`, `ModelFormatKMZ`, `ModelFormatCTM`, `ModelFormatSTL`, `ModelFormatDXF_3DF`, `ModelFormat-TLS`, `ModelFormatABC`, `ModelFormatOSGB`]

class `PhotoScan.ModelViewMode`

Model view mode in [`ShadedModelView`, `SolidModelView`, `WireframeModelView`, `TexturedModelView`]

class `PhotoScan.NetworkClient`

`NetworkClient` class provides access to the network processing server and allows to create and manage tasks.

The following example connects to the server and lists active tasks:

```
>>> import PhotoScan
>>> client = PhotoScan.NetworkClient()
>>> client.connect('127.0.0.1')
>>> client.batchList()
```

abortBatch (*batch_id*)

Abort batch.

Parameters `batch_id` (*int*) – Batch id.

abortNode (*node_id*)

Abort node.

Parameters `node_id` (*int*) – Node id.

batchList (*revision=0*)

Get list of batches.

Parameters `revision` (*int*) – First revision to get.

Returns List of batches.

Return type dict

batchStatus (*batch_id*, *revision=0*)

Get batch status.

Parameters

- `batch_id` (*int*) – Batch id.
- `revision` (*int*) – First revision to get.

Returns Batch status.

Return type dict

connect (*host*, *port=5840*)

Connect to the server.

Parameters

- `host` (*string*) – Server hostname.
- `port` (*int*) – Communication port.

createBatch (*path*, *tasks*)

Create new batch.

Parameters

- **path** (*string*) – Project path relative to root folder.
- **tasks** (list of *NetworkTask*) – Project path relative to root folder.

Returns Batch id.

Return type int

disconnect ()

Disconnect from the server.

findBatch (*path*)

Get batch id based on project path.

Parameters **path** (*string*) – Project path relative to root folder.

Returns Batch id.

Return type int

nodeList (*revision=0*)

Get list of nodes.

Parameters **revision** (*int*) – First revision to get.

Returns List of nodes.

Return type dict

nodeStatus (*node_id*, *revision=0*)

Get node status.

Parameters

- **node_id** (*int*) – Node id.
- **revision** (*int*) – First revision to get.

Returns Node status.

Return type dict

pauseBatch (*batch_id*)

Pause batch.

Parameters **batch_id** (*int*) – Batch id.

pauseNode (*node_id*)

Pause node.

Parameters **node_id** (*int*) – Node id.

quitNode (*node_id*)

Quit node.

Parameters **node_id** (*int*) – Node id.

resumeBatch (*batch_id*)

Resume batch.

Parameters **batch_id** (*int*) – Batch id.

resumeNode (*node_id*)

Resume node.

Parameters **node_id** (*int*) – Node id.

serverInfo ()

Get server information.

Returns Server information.

Return type dict

setBatchPriority (*batch_id, priority*)

Set batch priority.

Parameters

- **batch_id** (*int*) – Batch id.
- **priority** (*int*) – Batch priority (2 - Highest, 1 - High, 0 - Normal, -1 - Low, -2 - Lowest).

setNodeCPUEnable (*node_id, cpu_enable*)

Set node CPU enable flag.

Parameters

- **node_id** (*int*) – Node id.
- **cpu_enable** (*bool*) – CPU enable flag.

setNodeCapability (*node_id, capability*)

Set node capability.

Parameters

- **node_id** (*int*) – Node id.
- **capability** (*int*) – Node capability (1 - CPU, 2 - GPU, 3 - Any).

setNodeGPUMask (*node_id, gpu_mask*)

Set node GPU mask.

Parameters

- **node_id** (*int*) – Node id.
- **gpu_mask** (*int*) – GPU device mask.

setNodePriority (*node_id, priority*)

Set node priority.

Parameters

- **node_id** (*int*) – Node id.
- **priority** (*int*) – Node priority (2 - Highest, 1 - High, 0 - Normal, -1 - Low, -2 - Lowest).

class PhotoScan.**NetworkTask**

NetworkTask class contains information about network task and its parameters.

The following example creates a new processing task and submits it to the server:

```
>>> import PhotoScan
>>> task = PhotoScan.NetworkTask()
>>> task.name = 'MatchPhotos'
```

```

>>> task.params['keypoint_limit'] = 40000
>>> client = PhotoScan.NetworkClient()
>>> client.connect('127.0.0.1')
>>> batch_id = client.createBatch('processing/project.psx', [task])
>>> client.resumeBatch(batch_id)

```

chunks

List of chunks.

Type list

encode()

Create a dictionary with task parameters.

frames

List of frames.

Type list

name

Task name.

Type string

params

Task parameters.

Type dict

class PhotoScan.**OrthoProjection**

Orthographic projection.

class **Type**

Projection type in [Planar, Cylindrical]

OrthoProjection.crs

Base coordinate system.

Type *CoordinateSystem*

OrthoProjection.matrix

Ortho transformation matrix.

Type *Matrix*

OrthoProjection.radius

Cylindrical projection radius.

Type float

OrthoProjection.transform (*point, source, target*)

Transform point coordinates between coordinate systems.

Parameters

- **point** (2 or 3 component *Vector*) – Point coordinates.
- **source** (*CoordinateSystem*) – Source coordinate system.
- **target** (*CoordinateSystem*) – Target coordinate system.

Returns Transformed point coordinates.

Return type *Vector*

`OrthoProjection.type`
 Projection type.

Type *OrthoProjection.Type*

class `PhotoScan.Orthomosaic`
 Orthomosaic data.

The following sample assigns to the first shape in the chunk the image from the first camera for the orthomosaic patch and updates the mosaic:

```
>>> import PhotoScan
>>> chunk = PhotoScan.app.document.chunk
>>> ortho = chunk.orthomosaic
>>> camera = chunk.cameras[0]
>>> shape = chunk.shapes[0]
>>> patch = PhotoScan.Orthomosaic.Patch()
>>> patch.image_keys = [camera.key]
>>> ortho.patches[shape] = patch
>>> ortho.update()
```

class `Patch`

Orthomosaic patch.

copy()

Returns a copy of the patch.

Returns Copy of the patch.

Return type *Orthomosaic.Patch*

excluded

Excluded flag.

Type bool

image_keys

Image keys.

Type list of int

class `Orthomosaic.Patches`

A set of orthomosaic patches.

items()

List of items.

keys()

List of item keys.

values()

List of item values.

`Orthomosaic.bottom`

Y coordinate of the bottom side.

Type float

`Orthomosaic.clear()`

Clears orthomosaic data.

`Orthomosaic.copy()`

Create a copy of the orthomosaic.

Returns Copy of the orthomosaic.

Return type *Orthomosaic*

Orthomosaic.crs
Coordinate system of orthomosaic.
Type *CoordinateSystem*

Orthomosaic.height
Orthomosaic height.
Type int

Orthomosaic.key
Orthomosaic identifier.
Type int

Orthomosaic.label
Orthomosaic label.
Type string

Orthomosaic.left
X coordinate of the left side.
Type float

Orthomosaic.meta
Orthomosaic meta data.
Type *MetaData*

Orthomosaic.modified
Modified flag.
Type bool

Orthomosaic.patches
Orthomosaic patches.
Type *Orthomosaic.Patches*

Orthomosaic.projection
Orthomosaic projection.
Type *OrthoProjection*

Orthomosaic.removeOrthophotos()
Remove orthorectified images from orthomosaic.

Orthomosaic.reset([progress])
Reset all edits to orthomosaic.
Parameters **progress** (*Callable[[float], None]*) – Progress callback.

Orthomosaic.resolution
Orthomosaic resolution in meters.
Type float

Orthomosaic.right
X coordinate of the right side.
Type float

Orthomosaic.top
Y coordinate of the top side.
Type float

`Orthomosaic.update` (*progress*)

Apply edits to orthomosaic.

Parameters `progress` (*Callable*[[*float*], *None*]) – Progress callback.

`Orthomosaic.width`

Orthomosaic width.

Type `int`

class `PhotoScan.Photo`

Photo instance

`alpha` ()

Returns alpha channel data.

Returns Alpha channel data.

Return type *Image*

`copy` ()

Returns a copy of the photo.

Returns Copy of the photo.

Return type *Photo*

`image` (*channels* [, *datatype*])

Returns image data.

Parameters

- **datatype** (*string*) – pixel data type in ['U8', 'U16', 'U32', 'F16', 'F32', 'F64']
- **channels** (*string*) – color channels to be loaded, e.g. 'RGB', 'RGBA', etc.

Returns Image data.

Return type *Image*

`imageMeta` ()

Returns image meta data.

Returns Image meta data.

Return type *MetaData*

layer

Layer index in the image file.

Type `int`

meta

Frame meta data.

Type *MetaData*

`open` (*path* [, *layer*])

Loads specified image file.

Parameters

- **path** (*string*) – Path to the image file to be loaded.
- **layer** (*int*) – Optional layer index in case of multipage files.

path

Path to the image file.

Type string

thumbnail (*width=192, height=192*)

Creates new thumbnail with specified dimensions.

Returns Thumbnail data.

Return type *Thumbnail*

class PhotoScan.**PointClass**

Point class in [Created, Unclassified, Ground, LowVegetation, MediumVegetation, HighVegetation, Building, LowPoint, ModelKeyPoint, Water, Rail, RoadSurface, OverlapPoints, WireGuard, WireConductor, TransmissionTower, WireConnector, BridgeDeck, HighNoise]

class PhotoScan.**PointCloud**

Sparse point cloud instance

class **Cameras**

Collection of *PointCloud.Projections* objects indexed by corresponding cameras

class PointCloud.**Filter**

Sparse point cloud filter

The following example selects all points of the sparse cloud from the active chunk that have reprojection error higher than defined threshold:

```
>>> chunk = PhotoScan.app.document.chunk # active chunk
>>> threshold = 0.5
>>> f = PhotoScan.PointCloud.Filter()
>>> f.init(chunk, criterion = PhotoScan.PointCloud.Filter.ReprojectionError)
>>> f.selectPoints(threshold)
```

class **Criterion**

Point filtering criterion in [ReprojectionError, ReconstructionUncertainty, ImageCount, ProjectionAccuracy]

PointCloud.Filter.**init** (*points, criterion, progress*)

Initialize point cloud filter based on specified criterion.

Parameters

- **points** (*PointCloud* or *Chunk*) – Point cloud to filter.
- **criterion** (*PointCloud.Filter.Criterion*) – Point filter criterion.
- **progress** (*Callable[[float], None]*) – Progress callback.

PointCloud.Filter.**max_value**

Maximum value.

Type int or double

PointCloud.Filter.**min_value**

Minimum value.

Type int or double

PointCloud.Filter.**removePoints** (*threshold*)

Remove points based on specified threshold.

Parameters **threshold** (*float*) – Criterion threshold.

PointCloud.Filter.**resetSelection** ()

Reset previously made selection.

PointCloud.Filter.**selectPoints** (*threshold*)

Select points based on specified threshold.

Parameters **threshold** (*float*) – Criterion threshold.

`PointCloud.Filter.values`
List of values.
Type list of int or list of double

class `PointCloud.Point`
3D point in the point cloud

coord
Point coordinates.
Type *Vector*

selected
Point selection flag.
Type bool

track_id
Track index.
Type int

valid
Point valid flag.
Type bool

class `PointCloud.Points`
Collection of 3D points in the point cloud

copy()
Returns a copy of points buffer.
Returns Copy of points buffer.
Return type *PointCloud.Points*

resize(count)
Resize points list.
Parameters `count` (*int*) – new point count

class `PointCloud.Projection`
Projection of the 3D point on the photo

coord
Projection coordinates.
Type tuple of 2 float

size
Point size.
Type float

track_id
Track index.
Type int

class `PointCloud.Projections`
Collection of *PointCloud.Projection* for the camera

copy()
Returns a copy of projections buffer.
Returns Copy of projections buffer.
Return type *PointCloud.Projections*

resize(count)
Resize projections list.
Parameters `count` (*int*) – new projections count

class `PointCloud.Track`

Track in the point cloud

color

Track color.

Type tuple of 3 int

class `PointCloud.Tracks`

Collection of tracks in the point cloud

copy ()

Returns a copy of tracks buffer.

Returns Copy of tracks buffer.

Return type `PointCloud.Tracks`

resize (*count*)

Resize track list.

Parameters *count* (*int*) – new track count

`PointCloud.copy` (*keypoints=True*)

Returns a copy of the point cloud.

Parameters *keypoints* (*bool*) – copy key points data.

Returns Copy of the point cloud.

Return type `PointCloud`

`PointCloud.cropSelectedPoints` ()

Crop selected points.

`PointCloud.cropSelectedTracks` ()

Crop selected tie points.

`PointCloud.export` (*path*, *format='obj'* [, *projection*])

Export point cloud.

Parameters

- **path** (*string*) – Path to output file.
- **format** (*string*) – Export format in ['obj', 'ply'].
- **projection** (*Matrix* or *CoordinateSystem*) – Sets output projection.

`PointCloud.meta`

Point cloud meta data.

Type `MetaData`

`PointCloud.modified`

Modified flag.

Type bool

`PointCloud.pickPoint` (*origin*, *target*)

Returns ray intersection with the point cloud (point on the ray nearest to some point).

Parameters

- **origin** (`PhotoScan.Vector`) – Ray origin.
- **target** (`PhotoScan.Vector`) – Point on the ray.

Returns Coordinates of the intersection point.

Return type *PhotoScan.Vector*

PointCloud.points

List of points.

Type *PointCloud.Points*

PointCloud.projections

Point projections for each photo.

Type *PointCloud.Projections*

PointCloud.removeKeypoints()

Remove keypoints from point cloud.

PointCloud.removeSelectedPoints()

Remove selected points.

PointCloud.removeSelectedTracks()

Remove selected tie points.

PointCloud.tracks

List of tracks.

Type *PointCloud.Tracks*

class *PhotoScan.PointsFormat*

Point cloud format in [PointsFormatNone, PointsFormatOBJ, PointsFormatPLY, PointsFormatXYZ, PointsFormatLAS, PointsFormatExpe, PointsFormatU3D, PointsFormatPDF, PointsFormatE57, PointsFormatOC3, PointsFormatPotree, PointsFormatLAZ, PointsFormatCL3, PointsFormatPTS, PointsFormatDXF, PointsFormatCesium]

class *PhotoScan.Preselection*

Image pair preselection in [NoPreselection, GenericPreselection, ReferencePreselection]

class *PhotoScan.Quality*

Dense point cloud quality in [UltraQuality, HighQuality, MediumQuality, LowQuality, LowestQuality]

class *PhotoScan.RasterFormat*

Raster format in [RasterFormatNone, RasterFormatTiles, RasterFormatKMZ, RasterFormatXYZ, RasterFormatMBTiles, RasterFormatWW, RasterFormatTMS]

class *PhotoScan.RasterTransform*

Raster transform definition.

calibrateRange()

Auto detect range based on orthomosaic histogram.

enabled

Enable flag.

Type bool

false_color

False color channels.

Type list

formula

Raster calculator expression.

Type string

interpolation

Interpolation enable flag.

Type bool

palette

Color palette.

Type dict

range

Palette mapping range.

Type tuple

reset ()

Reset raster transform.

class PhotoScan.**RasterTransformType**

Raster transformation type in [RasterTransformNone, RasterTransformValue, RasterTransformPalette]

class PhotoScan.**ReferenceFormat**

Reference format in [ReferenceFormatNone, ReferenceFormatXML, ReferenceFormatTEL, ReferenceFormatCSV, ReferenceFormatMavinci, ReferenceFormatBramor, ReferenceFormatAPM]

class PhotoScan.**ReferenceItems**

Reference items in [ReferenceItemsCameras, ReferenceItemsMarkers, ReferenceItemsScalebars]

class PhotoScan.**Region**

Region parameters

center

Region center coordinates.

Type *Vector*

rot

Region rotation matrix.

Type *Matrix*

size

Region size.

Type *Vector*

class PhotoScan.**RotationOrder**

Rotation order in [RotationOrderXYZ, RotationOrderXZY, RotationOrderYXZ, RotationOrderYZX, RotationOrderZXY, RotationOrderZYX]

class PhotoScan.**Scalebar**

Scale bar instance

class **Reference**

Scale bar reference data

accuracy

Scale bar length accuracy.

Type float

distance

Scale bar length.

Type float

enabled

Enabled flag.

Type bool

`Scalebar.chunk`

Chunk the scalebar belongs to.

Type *Chunk*

`Scalebar.frames`

Scale bar frames.

Type list of *Scalebar*

`Scalebar.group`

Scale bar group.

Type *ScalebarGroup*

`Scalebar.key`

Scale bar identifier.

Type int

`Scalebar.label`

Scale bar label.

Type string

`Scalebar.meta`

Scale bar meta data.

Type *MetaData*

`Scalebar.point0`

Start of the scale bar.

Type *Marker*

`Scalebar.point1`

End of the scale bar.

Type *Marker*

`Scalebar.reference`

Scale bar reference data.

Type *ScalebarReference*

`Scalebar.selected`

Selects/deselects the scale bar.

Type bool

class `PhotoScan.ScalebarGroup`

ScalebarGroup objects define groups of multiple scale bars. The grouping is established by assignment of a ScalebarGroup instance to the Scalebar.group attribute of participating scale bars.

label

Scale bar group label.

Type string

selected

Current selection state.

Type bool

class `PhotoScan.Sensor`

Sensor instance

class Type

Sensor type in [Frame, Fisheye, Spherical]

Sensor. `antenna`

GPS antenna correction.

Type *Antenna*

Sensor. `bands`

List of image bands.

Type list of string

Sensor. `black_level`

Black level for each band.

Type list of float

Sensor. `calibrateFiducials` (*resolution=0.014*)

Fit fiducial coordinates to image measurements.

Parameters `resolution` (*float*) – Scanning resolution in mm/pix.

Sensor. `calibration`

Refined calibration of the photo.

Type *Calibration*

Sensor. `chunk`

Chunk the sensor belongs to.

Type *Chunk*

Sensor. `fiducials`

Fiducial marks.

Type list of *Marker*

Sensor. `fixed`

Fix calibration flag.

Type bool

Sensor. `fixed_calibration`

Fix calibration flag.

Type bool

Sensor. `fixed_location`

Fix location flag.

Type bool

Sensor. `fixed_rotation`

Fix rotation flag.

Type bool

Sensor. `focal_length`

Focal length in mm.

Type float

Sensor. `height`

Image height.

Type int

Sensor.key
Sensor identifier.
Type int

Sensor.label
Sensor label.
Type string

Sensor.layer_index
Sensor layer index.
Type int

Sensor.location
Sensor plane location.
Type *Vector*

Sensor.master
Master sensor.
Type *Sensor*

Sensor.normalize_sensitivity
Enable sensitivity normalization.
Type bool

Sensor.normalize_to_float
Convert pixel values to floating point after normalization.
Type bool

Sensor.pixel_height
Pixel height in mm.
Type float

Sensor.pixel_size
Pixel size in mm.
Type *Vector*

Sensor.pixel_width
Pixel width in mm.
Type float

Sensor.planes
Sensor planes.
Type list of *Sensor*

Sensor.rolling_shutter
Enable rolling shutter compensation.
Type bool

Sensor.rotation
Sensor plane rotation.
Type *Matrix*

Sensor.sensitivity
Sensitivity for each band.

Type list of float

Sensor.type

Sensor projection model.

Type *Sensor.Type*

Sensor.user_calib

Custom calibration used as initial calibration during photo alignment.

Type *Calibration*

Sensor.vignetting

Vignetting for each band.

Type list of *Vignetting*

Sensor.width

Image width.

Type int

class PhotoScan.**Shape**

Shape data.

class **BoundaryType**

Shape boundary type in [NoBoundary, OuterBoundary, InnerBoundary]

class Shape.**Type**

Shape type in [Point, Polyline, Polygon]

class Shape.**Vertices**

Collection of shape vertices

Shape.**area** ()

Return area of the shape on DEM.

Returns Shape area.

Return type float

Shape.**attributes**

Shape attributes.

Type *MetaData*

Shape.**boundary_type**

Shape boundary type.

Type *Shape.BoundaryType*

Shape.**group**

Shape group.

Type *ShapeGroup*

Shape.**has_z**

Z enable flag.

Type bool

Shape.**key**

Shape identifier.

Type int

`Shape.label`
Shape label.

Type string

`Shape.perimeter2D()`
Return perimeter of the shape on DEM.

Returns Shape perimeter.

Return type float

`Shape.perimeter3D()`
Return perimeter of the shape.

Returns Shape perimeter.

Return type float

`Shape.selected`
Selects/deselects the shape.

Type bool

`Shape.type`
Shape type.

Type `Shape.Type`

`Shape.vertex_ids`
List of shape vertex ids.

Type `ShapeVertices`

`Shape.vertices`
List of shape vertices.

Type `ShapeVertices`

`Shape.volume (level='bestfit')`
Return volume of the shape measured on DEM above and below best fit, mean level or custom level plane.

Parameters `level` (*float*) – Plane level: 'bestfit', 'mean' or custom value.

Returns Shape volumes.

Return type dict

class `PhotoScan.ShapeGroup`

`ShapeGroup` objects define groups of multiple shapes. The grouping is established by assignment of a `ShapeGroup` instance to the `Shape.group` attribute of participating shapes.

color
Shape group color.

Type tuple of 3 int

enabled
Enable flag.

Type bool

key
Shape group identifier.

Type int

label
Shape group label.

Type string

selected
Current selection state.

Type bool

show_labels
Shape labels visibility flag.

Type bool

class PhotoScan.**Shapes**
A set of shapes for a chunk frame.

addGroup()
Add new shape group to the set of shapes.

Returns Created shape group.

Return type *ShapeGroup*

addShape()
Add new shape to the set of shapes.

Returns Created shape.

Return type *Shape*

crs
Shapes coordinate system.

Type *CoordinateSystem*

groups
List of shape groups.

Type list of *ShapeGroup*

items()
List of items.

meta
Shapes meta data.

Type *MetaData*

modified
Modified flag.

Type bool

projection
Shapes projection.

Type *OrthoProjection*

remove(items)
Remove items from the shape layer.

Parameters **items** (list of *Shape* or *ShapeGroup*) – A list of items to be removed.

shapes
List of shapes.

Type list of *Shape*

updateAltitudes (*items*[, *progress*])

Update altitudes for items.

Parameters

- **items** (list of *Shape* or *ShapeGroup*) – A list of items to be updated.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

class `PhotoScan.ShapesFormat`

Shapes format in [ShapesFormatNone, ShapesFormatSHP, ShapesFormatKML, ShapesFormatDXF]

class `PhotoScan.Shutter`

Shutter object contains estimated parameters of the rolling shutter correction model.

rotation

Rotation matrix of the rolling shutter model.

Type *Matrix*

translation

Translation vector of the rolling shutter model.

Type *Vector*

class `PhotoScan.SurfaceType`

Surface type in [Arbitrary, HeightField]

class `PhotoScan.Target`

Target parameters

code

Target code.

Type *int*

coord

Target location.

Type *Vector*

radius

Target radius.

Type *float*

class `PhotoScan.TargetType`

Target type in [CircularTarget12bit, CircularTarget14bit, CircularTarget16bit, CircularTarget20bit, CircularTarget, CrossTarget]

class `PhotoScan.Tasks`

Task classes.

class `AddFrames`

Task class containing processing parameters.

apply (*object*[, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

chunk
Chunk to copy frames from.
Type int

copy_dense_cloud
Copy dense cloud.
Type bool

copy_depth_maps
Copy depth maps.
Type bool

copy_elevation
Copy DEM.
Type bool

copy_model
Copy model.
Type bool

copy_orthomosaic
Copy orthomosaic.
Type bool

copy_tiled_model
Copy tiled model.
Type bool

encode ()
Create a dictionary with task parameters.

frames
List of frame keys to copy.
Type list of int

name
Task name.
Type string

class `Tasks.AddPhotos`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

encode ()
Create a dictionary with task parameters.

filegroups
List of file groups.
Type list of int

filenames
List of files to add.
Type list of string

group
Camera group key.
Type int

layout
Image layout.
Type *PhotoScan.ImageLayout*

load_reference
Load reference coordinates.
Type bool

load_xmp_accuracy
Load accuracy from XMP meta data.
Type bool

load_xmp_antenna
Load GPS/INS offset from XMP meta data.
Type bool

load_xmp_calibration
Load calibration from XMP meta data.
Type bool

load_xmp_orientation
Load orientation from XMP meta data.
Type bool

name
Task name.
Type string

strip_extensions
Strip file extensions from camera labels.
Type bool

class `Tasks.AlignCameras`
Task class containing processing parameters.

adaptive_fitting
Enable adaptive fitting of distortion coefficients.
Type bool

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

cameras
List of cameras to align.
Type list of int

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

network_distribute
Enable distributed processing.
Type bool

reset_alignment
Reset current alignment.
Type bool

class `Tasks.AlignChunks`
Task class containing processing parameters.

align_method
Alignment method.
Type int

apply (*object* [, *progress*])
Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

chunks
List of chunks to be aligned.
Type list of int

encode ()
Create a dictionary with task parameters.

fit_scale
Fit chunk scale during alignment.
Type bool

match_downscale
Alignment accuracy.
Type int

match_filter_mask
Filter points by mask.
Type bool

match_point_limit
Maximum number of points for each photo.
Type int

match_select_pairs
Enables image pair preselection.
Type bool

name
Task name.
Type string

reference
Chunk to be used as a reference.
Type int

class `Tasks.AnalyzePhotos`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

cameras
List of cameras to be analyzed.
Type list of int

encode ()
Create a dictionary with task parameters.

filter_mask
Constrain analyzed image region by mask.
Type bool

name
Task name.
Type string

class *Tasks*.**BuildContours**
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode ()
Create a dictionary with task parameters.

interval
Contour interval.
Type float

max_value
Maximum value of contour range.
Type float

min_value
Minimum value of contour range.
Type float

name
Task name.
Type string

prevent_intersections
Prevent contour intersections.
Type bool

source_data
Source data for contour generation.
Type *PhotoScan.DataSource*

class *Tasks*.**BuildDem**
Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

classes

List of dense point classes to be used for surface extraction.

Type list of int

encode ()

Create a dictionary with task parameters.

flip_x

Flip X axis direction.

Type bool

flip_y

Flip Y axis direction.

Type bool

flip_z

Flip Z axis direction.

Type bool

interpolation

Interpolation mode.

Type *PhotoScan.Interpolation*

name

Task name.

Type string

network_distribute

Enable distributed processing.

Type bool

projection

Output projection.

Type *PhotoScan.OrthoProjection*

region

Region to be exported in the (x0, y0, x1, y1) format.

Type list of 4 floats

resolution

Output resolution in meters.

Type float

source_data

Selects between dense point cloud and sparse point cloud.

Type *PhotoScan.DataSource*

class *Tasks*.**BuildDenseCloud**

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode()

Create a dictionary with task parameters.

max_neighbors

Maximum number of neighbor images to use for depth map filtering.

Type int

name

Task name.

Type string

network_distribute

Enable distributed processing.

Type bool

point_colors

Enable point colors calculation.

Type bool

store_depth

Enable store depth maps option.

Type bool

class *Tasks*.**BuildDepthMaps**

Task class containing processing parameters.

apply (*object*[, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

cameras

List of cameras to process.

Type list of int

downscale

Depth map quality.

Type int

encode()

Create a dictionary with task parameters.

filter_mode

Depth map filtering mode.

Type *PhotoScan.FilterMode*

max_neighbors

Maximum number of neighbor images to use for depth map generation.

Type int

name

Task name.

Type string

network_distribute

Enable distributed processing.

Type bool

reuse_depth

Enable reuse depth maps option.

Type bool

class `Tasks.BuildModel`

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

cameras

List of cameras to process.

Type list of int

classes

List of dense point classes to be used for surface extraction.

Type list of int

downscale

Depth map quality.

Type int

encode ()

Create a dictionary with task parameters.

face_count

Target face count.

Type *PhotoScan.FaceCount*

face_count_custom

Custom face count.

Type int

filter_mode

Depth map filtering mode.

Type *PhotoScan.FilterMode*

interpolation

Interpolation mode.

Type *PhotoScan.Interpolation*

max_neighbors

Maximum number of neighbor images to use for depth map generation.

Type int

name

Task name.

Type string

network_distribute

Enable distributed processing.

Type bool

reuse_depth
Enable reuse depth maps option.
Type bool

source_data
Selects between dense point cloud, sparse point cloud and depth maps.
Type *PhotoScan.DataSource*

store_depth
Enable store depth maps option.
Type bool

surface_type
Type of object to be reconstructed.
Type *PhotoScan.SurfaceType*

vertex_colors
Enable vertex colors calculation.
Type bool

visibility_mesh
Enable visibility consistent mesh generation method.
Type bool

volumetric_masks
Enable strict volumetric masking.
Type bool

class `Tasks.BuildOrthomosaic`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

blending_mode
Orthophoto blending mode.
Type *PhotoScan.BlendingMode*

cull_faces
Enable back-face culling.
Type bool

encode ()
Create a dictionary with task parameters.

fill_holes
Enable hole filling.
Type bool

flip_x
Flip X axis direction.
Type bool

flip_y
Flip Y axis direction.
Type bool

flip_z
Flip Z axis direction.
Type bool

name
Task name.
Type string

network_distribute
Enable distributed processing.
Type bool

ortho_surface
Orthorectification surface.
Type *PhotoScan.DataSource*

projection
Output projection.
Type *PhotoScan.OrthoProjection*

region
Region to be exported in the (x0, y0, x1, y1) format.
Type list of 4 floats

resolution
Pixel size in meters.
Type float

resolution_x
Pixel size in the X dimension in projected units.
Type float

resolution_y
Pixel size in the Y dimension in projected units.
Type float

class *Tasks*.**BuildSeamlines**
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode ()
Create a dictionary with task parameters.

epsilon
Contour simplification threshold.
Type float

name
Task name.
Type string

class *Tasks*.**BuildTexture**
Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

blending_mode

Texture blending mode.

Type *PhotoScan.BlendingMode*

cameras

A list of cameras to be used for texturing.

Type list of int

encode ()

Create a dictionary with task parameters.

fill_holes

Enable hole filling.

Type bool

ghosting_filter

Enable ghosting filter.

Type bool

name

Task name.

Type string

texture_size

Texture size.

Type int

class *Tasks.BuildTiledModel*

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

classes

List of dense point classes to be used for surface extraction.

Type list of int

encode ()

Create a dictionary with task parameters.

name

Task name.

Type string

network_distribute

Enable distributed processing.

Type bool

pixel_size

Target model resolution in meters.

Type float

source_data
Selects between dense point cloud and mesh.
Type *PhotoScan.DataSource*

store_depth
Enable store depth maps option.
Type bool

tile_size
Size of tiles in pixels.
Type int

class `Tasks.BuildUV`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable* [[*float*], *None*]) – Progress callback.

camera
Camera to be used for texturing in MappingCamera mode.
Type int

encode ()
Create a dictionary with task parameters.

mapping_mode
Texture mapping mode.
Type *PhotoScan.MappingMode*

name
Task name.
Type string

texture_count
Texture count.
Type int

class `Tasks.CalibrateColors`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable* [[*float*], *None*]) – Progress callback.

calibrate_color_balance
Turn on color balance compensation.
Type bool

cameras
List of cameras to process.
Type list of int

data_source
Source data for calibration.
Type *PhotoScan.DataSource*

encode()
Create a dictionary with task parameters.

name
Task name.
Type string

class `Tasks.CalibrateLens`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

border
Border size to ignore.
Type int

encode()
Create a dictionary with task parameters.

fit_b1
Enable optimization of aspect ratio.
Type bool

fit_b2
Enable optimization of skew coefficient.
Type bool

fit_cxcy
Enable optimization of principal point coordinates.
Type bool

fit_f
Enable optimization of focal length coefficient.
Type bool

fit_k1
Enable optimization of k1 radial distortion coefficient.
Type bool

fit_k2
Enable optimization of k2 radial distortion coefficient.
Type bool

fit_k3
Enable optimization of k3 radial distortion coefficient.
Type bool

fit_k4
Enable optimization of k4 radial distortion coefficient.
Type bool

fit_p1
Enable optimization of p1 tangential distortion coefficient.
Type bool

fit_p2
Enable optimization of p2 tangential distortion coefficient.
Type bool

fit_p3
Enable optimization of p3 tangential distortion coefficient.
Type bool

fit_p4
Enable optimization of p4 tangential distortion coefficient.
Type bool

name
Task name.
Type string

class `Tasks.CalibrateReflectance`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

use_reflectance_panels
Use calibrated reflectance panels.
Type bool

use_sun_sensor
Apply irradiance sensor measurements.
Type bool

class `Tasks.ClassifyGroundPoints`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

cell_size
Cell size (meters).
Type float

cls_from
Class of points to be re-classified.

Type int

encode()
Create a dictionary with task parameters.

max_angle
Maximum angle (degrees).
Type float

max_distance
Maximum distance (meters).
Type float

name
Task name.
Type string

class `Tasks.CloseHoles`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode()
Create a dictionary with task parameters.

level
Hole size threshold in percents.
Type int

name
Task name.
Type string

class `Tasks.ColorizeDenseCloud`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode()
Create a dictionary with task parameters.

name
Task name.
Type string

source_data
Source data to extract colors from.
Type *PhotoScan.DataSource*

class `Tasks.CompactDenseCloud`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

class *Tasks.DecimateModel*
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

target_face_count
Target face count.
Type int

class *Tasks.DetectFiducials*
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

class *Tasks.DetectMarkers*
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.

- **progress** (*Callable*[[float], None]) – Progress callback.

encode()
Create a dictionary with task parameters.

frames
List of frames to process.
Type list of int

inverted
Detect markers on black background.
Type bool

minimum_dist
Minimum distance between targets in pixels (CrossTarget type only).
Type int

minimum_size
Minimum target radius in pixels to be detected (CrossTarget type only).
Type int

name
Task name.
Type string

noparity
Disable parity checking.
Type bool

target_type
Type of targets.
Type *PhotoScan.TargetType*

tolerance
Detector tolerance (0 - 100).
Type int

class *Tasks.DuplicateChunk*
Task class containing processing parameters.

apply (*object*[, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[float], None]) – Progress callback.

chunk
Chunk to copy.
Type int

copy_dense_cloud
Copy dense cloud.
Type bool

copy_depth_maps
Copy depth maps.
Type bool

copy_elevation
Copy DEM.

Type bool

copy_keypoints
Copy keypoints.
Type bool

copy_model
Copy model.
Type bool

copy_orthomosaic
Copy orthomosaic.
Type bool

copy_tiled_model
Copy tiled model.
Type bool

encode ()
Create a dictionary with task parameters.

frames
List of frame keys to copy.
Type list of int

label
New chunk label.
Type string

name
Task name.
Type string

class `Tasks.ExportCameras`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

binary
Enables/disables binary encoding for selected format (if applicable).
Type bool

chan_order_rotate
Rotation order (CHAN format only).
Type *PhotoScan.RotationOrder*

coordinates
Output coordinate system.
Type *CoordinateSystem*

encode ()
Create a dictionary with task parameters.

export_markers
Enables/disables export of manual matching points.
Type bool

export_points
Enables/disables export of automatic tie points.
Type bool

format
Export format.
Type *PhotoScan.CamerasFormat*

name
Task name.
Type string

path
Path to output file.
Type string

use_labels
Enables/disables label based item identifiers.
Type bool

class *Tasks*.**ExportDepth**
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

cameras
List of cameras to process.
Type list of int

encode ()
Create a dictionary with task parameters.

export_depth
Enable export of depth map.
Type bool

export_diffuse
Enable export of diffuse map.
Type bool

export_normals
Enable export of normal map.
Type bool

name
Task name.
Type string

path_depth
Path to depth map.
Type string

path_diffuse
Path to diffuse map.
Type string

path_normals

Path to normal map.

Type string**class** Tasks.**ExportMarkers**

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

binary

Enables/disables binary encoding for selected format (if applicable).

Type bool**coordinates**

Output coordinate system.

Type *CoordinateSystem***encode** ()

Create a dictionary with task parameters.

name

Task name.

Type string**path**

Path to output file.

Type string**class** Tasks.**ExportMasks**

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

cameras

List of cameras to process.

Type list of int**encode** ()

Create a dictionary with task parameters.

name

Task name.

Type string**path**

Path to output file.

Type string**class** Tasks.**ExportModel**

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

binary

Enables/disables binary encoding (if supported by format).

Type bool

comment

Optional comment (if supported by selected format).

Type string

coordinates

Output coordinate system.

Type *CoordinateSystem*

encode ()

Create a dictionary with task parameters.

export_alpha

Enables/disables alpha channel export.

Type bool

export_cameras

Enables/disables camera export.

Type bool

export_colors

Enables/disables export of vertex colors.

Type bool

export_comment

Enables/disables comment export.

Type bool

export_markers

Enables/disables marker export.

Type bool

export_normals

Enables/disables export of vertex normals.

Type bool

export_texture

Enables/disables texture export.

Type bool

export_udim

Enables/disables UDIM texture layout.

Type bool

export_uv

Enables/disables uv coordinates export.

Type bool

format

Export format.

Type *PhotoScan.ModelFormat*

name
Task name.
Type string

path
Path to output model.
Type string

precision
Number of digits after the decimal point (for text formats).
Type int

raster_transform
Raster band transformation.
Type *PhotoScan.RasterTransformType*

shift
Optional shift to be applied to vertex coordinates.
Type 3-element vector

strip_camera_ext
Strips camera label extensions during export.
Type bool

texture_format
Texture format.
Type *PhotoScan.ImageFormat*

viewpoint
Default view.
Type *Viewpoint*

class `Tasks.ExportOrthophotos`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

cameras
List of cameras to process.
Type list of int

encode ()
Create a dictionary with task parameters.

jpeg_quality
JPEG quality.
Type int

name
Task name.
Type string

north_up
Use north-up orientation for export.
Type bool

path

Path to output orthophoto.

Type string

projection

Output projection.

Type *PhotoScan.OrthoProjection*

raster_transform

Raster band transformation.

Type *PhotoScan.RasterTransformType*

region

Region to be exported in the (x0, y0, x1, y1) format.

Type list of 4 floats

resolution

Output resolution in meters.

Type float

resolution_x

Pixel size in the X dimension in projected units.

Type float

resolution_y

Pixel size in the Y dimension in projected units.

Type float

tiff_big

Enable BigTIFF compression for TIFF files.

Type bool

tiff_compression

Tiff compression.

Type int

tiff_overviews

Enable image pyramid deneneration for TIFF files.

Type bool

write_alpha

Enable alpha channel generation.

Type bool

write_kml

Enable kml file generation.

Type bool

write_world

Enable world file generation.

Type bool

class `Tasks.ExportPanorama`

Task class containing processing parameters.

apply (*object*[, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

camera_groups
List of camera groups to process.
Type list of int

encode()
Create a dictionary with task parameters.

height
Height of output panorama.
Type int

name
Task name.
Type string

path
Path to output file.
Type string

region
Region to be exported in the (x0, y0, x1, y1) format.
Type list of 4 floats

rotation
Panorama 3x3 orientation matrix.
Type *PhotoScan.Matrix*

width
Width of output panorama.
Type int

class *Tasks.ExportPoints*
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

binary
Enables/disables binary encoding for selected format (if applicable).
Type bool

classes
List of dense point classes to be exported.
Type list of int

comment
Optional comment (if supported by selected format).
Type string

coordinates
Output coordinate system.
Type *CoordinateSystem*

data_source
Selects between dense point cloud and sparse point cloud. If not specified, uses dense cloud if available.
Type *PhotoScan.DataSource*

encode()
Create a dictionary with task parameters.

export_colors
Enables/disables export of point colors.
Type bool

export_comment
Enable comment export.
Type bool

export_images
Enable image export.
Type bool

export_normals
Enables/disables export of point normals.
Type bool

format
Export format.
Type *PhotoScan.PointsFormat*

image_format
Image data format.
Type *PhotoScan.ImageFormat*

name
Task name.
Type string

path
Path to output file.
Type string

precision
Number of digits after the decimal point (for text formats).
Type int

raster_transform
Raster band transformation.
Type *PhotoScan.RasterTransformType*

shift
Optional shift to be applied to vertex coordinates.
Type 3-element vector

tile_height
Tile height in meters.
Type float

tile_width
Tile width in meters.
Type float

viewpoint
Default view.
Type *Viewpoint*

write_tiles
Enable tiled export.

Type bool

class `Tasks.ExportRaster`

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

data_source

Selects between DEM and orthomosaic.

Type *PhotoScan.DataSource*

description

Export description.

Type string

encode ()

Create a dictionary with task parameters.

format

Export format.

Type *PhotoScan.RasterFormat*

height

Raster height.

Type int

image_description

Optional description to be added to image files.

Type string

image_format

Tile format.

Type *PhotoScan.ImageFormat*

jpeg_quality

JPEG quality.

Type int

kmz_section_enable

Enable network links generation for KMZ format.

Type bool

name

Task name.

Type string

nodata_value

No-data value (DEM export only).

Type float

north_up

Use north-up orientation for export.

Type bool

path

Path to output orthomosaic.

Type string

projection
Output projection.
Type *PhotoScan.OrthoProjection*

raster_transform
Raster band transformation.
Type *PhotoScan.RasterTransformType*

region
Region to be exported in the (x0, y0, x1, y1) format.
Type list of 4 floats

resolution
Output resolution in meters.
Type float

resolution_x
Pixel size in the X dimension in projected units.
Type float

resolution_y
Pixel size in the Y dimension in projected units.
Type float

tiff_big
Enable BigTIFF compression for TIFF files.
Type bool

tiff_compression
Tiff compression.
Type int

tiff_overviews
Enable image pyramid deneneration for TIFF files.
Type bool

tile_height
Specifies block height of the orthomosaic in pixels.
Type int

tile_width
Specifies block width of the orthomosaic in pixels.
Type int

title
Export title.
Type string

white_background
Enable white background.
Type bool

width
Raster width.
Type int

world_transform
2x3 raster-to-world transformation matrix.
Type *PhotoScan.Matrix*

write_alpha
Enable alpha channel generation.
Type bool

write_kml
Enable kml file generation.
Type bool

write_scheme
Enable tile scheme files generation.
Type bool

write_tiles
Enable tiled export.
Type bool

write_world
Enable world file generation.
Type bool

xyz_level_max
Maximum zoom level (Google Map Tiles, MBTiles and World Wind Tiles formats only).
Type int

xyz_level_min
Minimum zoom level (Google Map Tiles, MBTiles and World Wind Tiles formats only).
Type int

class `Tasks.ExportReference`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

columns
Column order in csv format (n - label, o - enabled flag, x/y/z - coordinates, X/Y/Z - coordinate accuracy, a/b/c - rotation angles, A/B/C - rotation angle accuracy, u/v/w - estimated coordinates, U/V/W - coordinate errors, d/e/f - estimated orientation angles, D/E/F - orientation errors, [] - group of multiple values, l - column separator within group).
Type string

delimiter
Column delimiter in csv format.
Type string

encode ()
Create a dictionary with task parameters.

format
Export format.
Type *PhotoScan.ReferenceFormat*

items
Items to export in CSV format.
Type *PhotoScan.ReferenceItems*

name
Task name.
Type string

path
Path to the output file.
Type string

class `Tasks.ExportReport`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

description
Report description.
Type string

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

page_numbers
Enable page numbers.
Type bool

path
Path to output report.
Type string

title
Report title.
Type string

class `Tasks.ExportShapes`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

coordinates
Output coordinate system.
Type *CoordinateSystem*

encode ()
Create a dictionary with task parameters.

export_attributes
Export attributes.
Type bool

export_labels
Export labels.
Type bool

export_points
Export points.
Type bool

export_polygons
Export polygons.
Type bool

export_polylines
Export polylines.
Type bool

format
Export format.
Type *PhotoScan.ShapesFormat*

groups
A list of shape groups to export.
Type list of int

name
Task name.
Type string

path
Path to shape file.
Type string

polygons_as_polylines
Save polygons as polylines.
Type bool

shift
Optional shift to be applied to vertex coordinates.
Type 3-element vector

class `Tasks.ExportTexture`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

path
Path to output file.
Type string

write_alpha
Enable alpha channel export.
Type bool

class `Tasks.ExportTiledModel`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode ()
Create a dictionary with task parameters.

format
Export format.
Type *PhotoScan.TiledModelFormat*

mesh_format
Mesh format for zip export.
Type *PhotoScan.ModelFormat*

name
Task name.
Type string

path
Path to output model.
Type string

raster_transform
Raster band transformation.
Type *PhotoScan.RasterTransformType*

class `Tasks.ImportCameras`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode ()
Create a dictionary with task parameters.

format
File format.
Type *PhotoScan.CamerasFormat*

name
Task name.
Type string

path
Path to the file.
Type string

class `Tasks.ImportDem`

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

coordinates

Default coordinate system if not specified in GeoTIFF file.

Type *CoordinateSystem*

encode ()

Create a dictionary with task parameters.

name

Task name.

Type string

path

Path to elevation model in GeoTIFF format.

Type string

class `Tasks.ImportMarkers`

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode ()

Create a dictionary with task parameters.

name

Task name.

Type string

path

Path to the file.

Type string

class `Tasks.ImportMasks`

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

cameras

Optional list of cameras to be processed.

Type list of int

encode()
Create a dictionary with task parameters.

method
Mask source.
Type *PhotoScan.MaskSource*

name
Task name.
Type string

operation
Mask operation.
Type *PhotoScan.MaskOperation*

path
Mask file name template.
Type string

tolerance
Background masking tolerance.
Type int

class *Tasks.ImportModel*
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

coordinates
Model coordinate system.
Type *CoordinateSystem*

encode()
Create a dictionary with task parameters.

format
Model format.
Type *PhotoScan.ModelFormat*

name
Task name.
Type string

path
Path to model.
Type string

shift
Optional shift to be applied to vertex coordinates.
Type 3-element vector

class *Tasks.ImportPoints*
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

coordinates

Point cloud coordinate system.

Type *CoordinateSystem*

encode()

Create a dictionary with task parameters.

format

Point cloud format.

Type *PhotoScan.PointsFormat*

name

Task name.

Type string

path

Path to point cloud.

Type string

shift

Optional shift to be applied to point coordinates.

Type 3-element vector

class *Tasks.ImportReference*

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

columns

Column order in csv format (n - label, o - enabled flag, x/y/z - coordinates, X/Y/Z - coordinate accuracy, a/b/c - rotation angles, A/B/C - rotation angle accuracy, [] - group of multiple values, | - column separator within group).

Type string

coordinates

Reference data coordinate system (csv format only).

Type *CoordinateSystem*

create_markers

Create markers for missing entries (csv format only).

Type bool

delimiter

Column delimiter in csv format.

Type string

encode()

Create a dictionary with task parameters.

format

File format.

Type *PhotoScan.ReferenceFormat*

group_delimiters

Combine consecutive delimiters in csv format.

Type bool

ignore_labels

Matches reference data based on coordinates alone (csv format only).

Type bool

items

List of items to load reference for (csv format only).

Type *PhotoScan.ReferenceItems*

name

Task name.

Type string

path

Path to the file with reference data.

Type string

skip_rows

Number of rows to skip in (csv format only).

Type int

threshold

Error threshold in meters used when ignore_labels is set (csv format only).

Type float

class `Tasks.ImportShapes`

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

boundary_type

Boundary type to be applied to imported shapes.

Type *Shape.BoundaryType*

encode ()

Create a dictionary with task parameters.

format

Shapes format.

Type *PhotoScan.ShapesFormat*

name

Task name.

Type string

path

Path to shape file.

Type string

replace

Replace current shapes with new data.

Type bool

class `Tasks.InvertMasks`

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

cameras

List of cameras to process.

Type list of int

encode ()

Create a dictionary with task parameters.

name

Task name.

Type string

class `Tasks.LoadProject`

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode ()

Create a dictionary with task parameters.

name

Task name.

Type string

path

Path to project file.

Type string

read_only

Open project in read only mode.

Type bool

class `Tasks.MatchPhotos`

Task class containing processing parameters.

apply (*object* [, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

cameras

List of cameras to match.

Type list of int

downscale

Image alignment accuracy.

Type int

encode()

Create a dictionary with task parameters.

filter_mask

Filter points by mask.

Type bool

keypoint_limit

Key point limit.

Type int

mask_tiepoints

Apply mask filter to tie points.

Type bool

name

Task name.

Type string

network_distribute

Enable distributed processing.

Type bool

pairs

User defined list of camera pairs to match.

Type list of int

preselection_generic

Enable generic preselection.

Type bool

preselection_reference

Enable reference preselection.

Type bool

reset_matches

Reset current matches.

Type bool

store_keypoints

Store keypoints in the project.

Type bool

tiepoint_limit

Tie point limit.

Type int

class Tasks.**MergeChunks**

Task class containing processing parameters.

apply(*object*[, *progress*])

Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

chunks
List of chunks to process.
Type list of int

encode()
Create a dictionary with task parameters.

merge_dense_clouds
Merge dense clouds.
Type bool

merge_markers
Merge markers.
Type bool

merge_models
Merge models.
Type bool

merge_tiepoints
Merge tie points.
Type bool

name
Task name.
Type string

class `Tasks.OptimizeCameras`
Task class containing processing parameters.

adaptive_fitting
Enable adaptive fitting of distortion coefficients.
Type bool

apply(*object*[, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode()
Create a dictionary with task parameters.

fit_b1
Enable optimization of aspect ratio.
Type bool

fit_b2
Enable optimization of skew coefficient.
Type bool

fit_cx
Enable optimization of X principal point coordinates.
Type bool

fit_cy
Enable optimization of Y principal point coordinates.
Type bool

fit_f
Enable optimization of focal length coefficient.
Type bool

fit_k1
Enable optimization of k1 radial distortion coefficient.
Type bool

fit_k2
Enable optimization of k2 radial distortion coefficient.
Type bool

fit_k3
Enable optimization of k3 radial distortion coefficient.
Type bool

fit_k4
Enable optimization of k3 radial distortion coefficient.
Type bool

fit_p1
Enable optimization of p1 tangential distortion coefficient.
Type bool

fit_p2
Enable optimization of p2 tangential distortion coefficient.
Type bool

fit_p3
Enable optimization of p3 tangential distortion coefficient.
Type bool

fit_p4
Enable optimization of p4 tangential distortion coefficient.
Type bool

name
Task name.
Type string

class `Tasks.RefineMesh`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable[[float], None]*) – Progress callback.

cameras
List of cameras to process.
Type list of int

downscale
Refinement quality.
Type int

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

niterations
Number of refinement iterations.
Type int

smoothness
Smoothing strength. Should be in range [0, 1].
Type float

class `Tasks.RemoveLighting`
Task class containing processing parameters.

ambient_occlusion_multiplier
Ambient occlusion multiplier. Should be in range [0.25, 4].
Type float

ambient_occlusion_path
Path to ambient occlusion texture atlas. Can be empty.
Type string

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

color_mode
Enable multi-color processing mode.
Type bool

encode ()
Create a dictionary with task parameters.

internal_blur
Internal blur. Should be in range [0, 4].
Type float

mesh_noise_suppression
Mesh normals noise suppression strength. Should be in range [0, 4].
Type float

name
Task name.
Type string

class `Tasks.ResetMasks`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

cameras
List of cameras to process.

Type list of int

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

class `Tasks.RunScript`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable* [[*float*], *None*]) – Progress callback.

args
Script arguments.
Type string

code
Script code.
Type string

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

path
Script path.
Type string

class `Tasks.SaveProject`
Task class containing processing parameters.

absolute_paths
Store absolute image paths.
Type bool

apply (*object* [, *progress*])
Apply task to specified object.

Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable* [[*float*], *None*]) – Progress callback.

chunks
List of chunks to be saved.
Type list of int

compression
Project compression level.
Type int

encode()
Create a dictionary with task parameters.

name
Task name.
Type string

path
Path to project.
Type string

version
Project version to save.
Type string

class `Tasks.SmoothModel`
Task class containing processing parameters.

apply(*object*[, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

apply_to_selected
Apply to selected faces.
Type bool

encode()
Create a dictionary with task parameters.

fix_borders
Fix borders.
Type bool

name
Task name.
Type string

strength
Smoothing strength.
Type float

class `Tasks.TrackMarkers`
Task class containing processing parameters.

apply(*object*[, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode()
Create a dictionary with task parameters.

frame_end
Ending frame index.
Type int

frame_start
Starting frame index.
Type int

name
Task name.
Type string

class `Tasks.TriangulatePoints`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

encode ()
Create a dictionary with task parameters.

name
Task name.
Type string

class `Tasks.UndistortPhotos`
Task class containing processing parameters.

apply (*object* [, *progress*])
Apply task to specified object.
Parameters

- **object** (*PhotoScan.Chunk* or *PhotoScan.Document*) – Chunk or Document object to be processed.
- **progress** (*Callable*[[*float*], *None*]) – Progress callback.

cameras
List of cameras to process.
Type list of int

color_correction
Apply color correction.
Type bool

encode ()
Create a dictionary with task parameters.

fix_pixel_aspect
Fix pixel aspect.
Type bool

fix_principal_point
Fix principal point.
Type bool

jpeg_quality
JPEG quality.
Type int

name
Task name.
Type string

path
Path to output file.
Type string

remove_distortions
Remove distortions.
Type bool

tiff_compression
Tiff compression.
Type int

update_gps_tags
Update GPS tags.
Type bool

class PhotoScan.**Thumbnail**
Thumbnail instance

copy()
Returns a copy of thumbnail.
Returns Copy of thumbnail.
Return type *Thumbnail*

image()
Returns image data.
Returns Image data.
Return type *Image*

load(*path*[, *layer*])
Loads thumbnail from file.

Parameters

- **path** (*string*) – Path to the image file to be loaded.
- **layer** (*int*) – Optional layer index in case of multipage files.

setImage(*image*)

Parameters **image** (*Image*) – Image object with thumbnail data.

class PhotoScan.**Thumbnails**
A set of thumbnails generated for a chunk frame.

items()
List of items.

keys()
List of item keys.

meta
Thumbnails meta data.
Type *MetaData*

modified
Modified flag.
Type bool

values ()
List of item values.

class PhotoScan.**TiffCompression**
Tiff compression in [TiffCompressionNone, TiffCompressionLZW, TiffCompressionJPEG, TiffCompressionPackbits, TiffCompressionDeflate]

class PhotoScan.**TiledModel**
Tiled model data.

clear ()
Clears tiled model data.

copy ()
Create a copy of the tiled model.
Returns Copy of the tiled model.
Return type *TiledModel*

key
Tiled model identifier.
Type int

label
Tiled model label.
Type string

meta
Tiled model meta data.
Type *MetaData*

modified
Modified flag.
Type bool

pickPoint (origin, target)
Returns ray intersection with the tiled model.

Parameters

- **origin** (*PhotoScan.Vector*) – Ray origin.
- **target** (*PhotoScan.Vector*) – Point on the ray.

Returns Coordinates of the intersection point.

Return type *PhotoScan.Vector*

class PhotoScan.**TiledModelFormat**
Tiled model format in [TiledModelFormatNone, TiledModelFormatTLS, TiledModelFormatLOD, TiledModelFormatZIP, TiledModelFormatCesium, TiledModelFormatSLPK, TiledModelFormatOSGB]

class PhotoScan.**Utils**
Utility functions.

createChessboardImage (calib, cell_size=150, max_tilt=30)
Synthesizes photo of a chessboard.

Parameters

- **calib** (*Calibration*) – Camera calibration.

- **cell_size** (*float*) – Chessboard cell size.
- **max_tilt** (*float*) – Maximum camera tilt in degrees.

Returns Resulting image.

Return type *Image*

createDifferenceMask (*image, background, tolerance=10, fit_colors=True*)
Creates mask from a pair of images or an image and specified color.

Parameters

- **image** (*Image*) – Image to be masked.
- **background** (*Image* or color tuple) – Background image or color value.
- **tolerance** (*int*) – Tolerance value.
- **fit_colors** (*bool*) – Enables white balance correction.

Returns Resulting mask.

Return type *Image*

createMarkers (*chunk, projections*)
Creates markers from a list of non coded projections.

Parameters

- **chunk** (*Chunk*) – Chunk to create markers in.
- **projections** (list of (*Camera, Target*) tuples) – List of marker projections.

detectTargets (*image, type=TargetCircular12bit, tolerance=50, inverted=False, noparity=False* [, *minimum_size*] [, *minimum_dist*])
Detect targets on the image.

Parameters

- **image** (*Image*) – Image to process.
- **type** (*PhotoScan.TargetType*) – Type of targets.
- **tolerance** (*int*) – Detector tolerance (0 - 100).
- **inverted** (*bool*) – Detect markers on black background.
- **noparity** (*bool*) – Disable parity checking.
- **minimum_size** (*int*) – Minimum target radius in pixels to be detected (CrossTarget type only).
- **minimum_dist** (*int*) – Minimum distance between targets in pixels (CrossTarget type only).

Returns List of detected targets.

Return type list of *Target*

estimateImageQuality (*image* [, *mask*])
Estimate image sharpness.

Parameters

- **image** (*Image*) – Image to be analyzed.
- **mask** (*Image*) – Mask of the analyzed image region.

Returns Quality metric.

Return type float

mat2opk (*R*)

Calculate omega, phi, kappa from camera to world rotation matrix.

Parameters *R* (*Matrix*) – Rotation matrix.

Returns Omega, phi, kappa angles in degrees.

Return type *Vector*

mat2ypr (*R*)

Calculate yaw, pitch, roll from camera to world rotation matrix.

Parameters *R* (*Matrix*) – Rotation matrix.

Returns Yaw, pitch roll angles in degrees.

Return type *Vector*

opk2mat (*angles*)

Calculate camera to world rotation matrix from omega, phi, kappa angles.

Parameters *angles* (*Vector*) – Omega, phi, kappa angles in degrees.

Returns Rotation matrix.

Return type *Matrix*

ypr2mat (*angles*)

Calculate camera to world rotation matrix from yaw, pitch, roll angles.

Parameters *angles* (*Vector*) – Yaw, pitch, roll angles in degrees.

Returns Rotation matrix.

Return type *Matrix*

class PhotoScan.**Vector**

n-component vector

```
>>> import PhotoScan
>>> vect = PhotoScan.Vector( (1, 2, 3) )
>>> vect2 = vect.copy()
>>> vect2.size = 4
>>> vect2.w = 5
>>> vect2 *= -1.5
>>> vect.size = 4
>>> vect.normalize()
>>> PhotoScan.app.messageBox("Scalar product is " + str(vect2 * vect))
```

copy ()

Return a copy of the vector.

Returns A copy of the vector.

Return type *Vector*

cross (*a*, *b*)

Cross product of 2 vectors.

Parameters

- *a* (*Vector*) – First vector.
- *b* (*Vector*) – Second vector.

Returns Cross product.

Return type *Vector*

norm()

Return norm of the vector.

norm2()

Return squared norm of the vector.

normalize()

Normalize vector to the unit length.

normalized()

Return a new, normalized vector.

Returns a normalized copy of the vector

Return type *Vector*

size

Vector dimensions.

Type int

w

Vector W component.

Type float

x

Vector X component.

Type float

y

Vector Y component.

Type float

z

Vector Z component.

Type float

zero()

Set all elements to zero.

class PhotoScan.**Version**

Version object contains application version numbers.

build

Build number.

Type int

major

Major version number.

Type int

micro

Micro version number.

Type int

minor

Minor version number.

Type int

class PhotoScan.**Viewpoint** (*app*)

Represents viewpoint in the model view

center

Camera center.

Type *Vector*

coo

Center of orbit.

Type *Vector*

fov

Camera vertical field of view in degrees.

Type float

height

OpenGL window height.

Type int

mag

Camera magnification defined by distance to the center of rotation.

Type float

rot

Camera rotation matrix.

Type *Matrix*

width

OpenGL window width.

Type int

class PhotoScan.**Vignetting**

Vignetting polynomial

PYTHON API CHANGE LOG

3.1 PhotoScan version 1.4.4

- Added AddPhotos.strip_extensions attribute
- Added ExportRaster.image_description attribute
- Added ExportShapes.export_attributes, ExportShapes.export_labels and ExportShapes.polygons_as_polylines attributes
- Added image_description argument to Chunk.exportDem() and Chunk.exportOrthomosaic() methods
- Added format, polygons_as_polylines, export_labels and export_attributes arguments to Chunk.exportShapes() method
- Added format argument to Chunk.importShapes() method
- Added RasterFormatTMS to RasterFormat enum

3.2 PhotoScan version 1.4.3

- Added Version class
- Added Tasks.DetectFiducials class
- Added Chunk.detectFiducials() method
- Added Sensor.calibrateFiducials() method
- Added CoordinateSystem.addGeoid() method
- Added PhotoScan.version attribute
- Added Sensor.normalize_to_float attribute
- Added minimum_dist attribute to Tasks.DetectMarkers class
- Added minimum_dist argument to Chunk.detectMarkers() and Utils.detectTargets() methods
- Added keypoints argument to PointCloud.copy() method
- Changed default value of adaptive_fitting argument in Chunk.alignCameras() to False

3.3 PhotoScan version 1.4.2

- Added `Tasks.ColorizeDenseCloud` class
- Added `PointCloud.removeKeypoints()` method
- Added `CoordinateSystem.transformationMatrix()` method
- Added `Vector.cross()` method
- Added `Shapes.updateAltitudes()` method
- Added `log_enable`, `log_path`, `network_enable`, `network_host`, `network_path` and `network_port` attributes to `Application.Settings` class
- Added `covariance_matrix` and `covariance_params` attributes to `Calibration` class
- Added `flip_x`, `flip_y`, `flip_z` attributes to `Tasks.BuildDem` and `Tasks.BuildOrthomosaic` classes
- Added `max_neighbors` attribute to `Tasks.BuildDenseCloud`, `Tasks.BuildDepthMaps` and `Tasks.BuildModel` classes
- Added `jpeg_quality`, `tiff_compression` and `update_gps_tags` attributes to `Tasks.UndistortPhotos` class
- Added `copy_keypoints` attribute to `Tasks.DuplicateChunk` class
- Added `width`, `height` and `world_transform` attributes to `Tasks.ExportRaster` class
- Added `store_depth` attribute to `Tasks.BuildTiledModel` class
- Added `DenseCloud.crs` and `DenseCloud.transform` attributes
- Added `CoordinateSystem.wkt2` attribute
- Added `keep_keypoints` argument to `Chunk.matchPhotos()` method
- Added `flip_x`, `flip_y`, `flip_z` arguments to `Chunk.buildDem()` and `Chunk.buildOrthomosaic()` methods
- Added `max_neighbors` argument to `Chunk.buildDenseCloud()` and `Chunk.buildDepthMaps()` methods
- Added `cull_faces` argument to `Chunk.buildOrthomosaic()` method
- Added `reuse_depth` and `ghosting_filter` arguments to `Chunk.buildTiledModel()` method
- Added `use_reflectance_panels` and `use_sun_sensor` arguments to `Chunk.calibrateReflectance()` method
- Added `width`, `height` and `world_transform` arguments to `Chunk.exportDem()` and `Chunk.exportOrthomosaic()` methods
- Added `filter_mask` argument to `Chunk.estimateImageQuality()` method
- Added `revision` argument to `NetworkClient.nodeList()` method
- Added `ImagesData` to `DataSource` enum
- Added `ModelFormatOSGB` to `ModelFormat` enum
- Added `TiledModelFormatOSGB` to `TiledModelFormat` enum

3.4 PhotoScan version 1.4.1

- Added `OrthoProjection.Type` enum
- Added `Camera.image()` method
- Added `Chunk.loadReflectancePanelCalibration()` method

- Added `PointCloud.Points.copy()` and `PointCloud.Points.resize()` methods
- Added `PointCloud.Projections.resize()` method
- Added `PointCloud.Tracks.copy()` and `PointCloud.Tracks.resize()` methods
- Added `OrthoProjection.matrix`, `OrthoProjection.radius` and `OrthoProjection.type` attributes
- Added `Tasks.AnalyzePhotos.filter_mask` attribute
- Added `Tasks.CalibrateReflectance.use_reflectance_panels` and `Tasks.CalibrateReflectance.use_sun_sensor` attributes
- Added `Tasks.MatchPhotos.mask_tiepoints` attribute
- Added `Tasks.OptimizeCameras.adaptive_fitting` attribute
- Added `strip_extensions` argument to `Chunk.addPhotos()` method
- Added `keep_depth` argument to `Chunk.buildDenseCloud()` method
- Added `adaptive_resolution` argument to `Chunk.buildUV()` method
- Added `alpha` argument to `Chunk.exportModel()` method
- Added `mask_tiepoints` argument to `Chunk.matchPhotos()` method
- Added `adaptive_fitting` argument to `Chunk.optimizeCameras()` method
- Added `mask` argument to `Utils.estimateImageQuality()` method
- Added `CamerasFormatABC` and `CamerasFormatFBX` to `CamerasFormat` enum
- Added `ImageFormatJP2` to `ImageFormat` enum
- Added `LegacyMapping` to `MappingMode` enum

3.5 PhotoScan version 1.4.0

- Added `Tasks` classes
- Added `Animation`, `OrthoProjection`, `Target` and `Vignetting` classes
- Added `ShapesFormat` enum
- Added `Marker.Type` enum
- Added `Chunk.calibrateColors()`, `Chunk.calibrateReflectance()` and `Chunk.locateReflectancePanels()` methods
- Added `Chunk.buildDepthMaps()`, `Chunk.importPoints()`, `Chunk.refineModel()` and `Chunk.removeLighting()` methods
- Added `Chunk.addDenseCloud()`, `Chunk.addDepthMaps()`, `Chunk.addElevation()`, `Chunk.addModel()`, `Chunk.addOrthomosaic()` and `Chunk.addTiledModel()` methods
- Added `Chunk.sortCameras()`, `Chunk.sortMarkers()` and `Chunk.sortScalebars()` methods
- Added `DenseCloud.clear()` method
- Added `DepthMaps.clear()` and `DepthMaps.copy()` methods
- Added `Elevation.clear()` and `Elevation.copy()` methods
- Added `Model.clear()` method
- Added `Orthomosaic.clear()` and `Orthomosaic.copy()` methods

- Added `TiledModel.clear()` and `TiledModel.copy()` methods
- Added `Image.gaussianBlur()` and `Image.uniformNoise()` methods
- Added `NetworkTask.encode()` method
- Added `Utils.createChessboardImage()` and `Utils.detectTargets()` methods
- Added `Camera.Reference.location_accuracy` and `Camera.Reference.rotation_accuracy` attributes
- Added `Camera.layer_index`, `Camera.master` and `Camera.vignetting` attributes
- Added `Chunk.dense_clouds`, `Chunk.depth_maps_sets`, `Chunk.elevations`, `Chunk.models`, `Chunk.orthomosaics` and `Chunk.tiled_models` attributes
- Added `Chunk.animation`, `Chunk.camera_crs`, `Chunk.marker_crs` and `Chunk.world_crs` attributes
- Added `CoordinateSystem.geoccs` and `CoordinateSystem.geoid_height` attributes
- Added `Marker.Projection.valid` attribute
- Added `Sensor.black_level`, `Sensor.fiducials`, `Sensor.fixed_calibration`, `Sensor.fixed_location`, `Sensor.fixed_rotation`, `Sensor.layer_index`, `Sensor.location`, `Sensor.master`, `Sensor.normalize_sensitivity`, `Sensor.rolling_shutter`, `Sensor.rotation`, `Sensor.sensitivity` and `Sensor.vignetting` attributes
- Added `Camera.chunk`, `Marker.chunk`, `Scalebar.chunk` and `Sensor.chunk` attributes
- Added `Marker.sensor` and `Marker.type` attributes
- Added `Elevation.projection`, `Orthomosaic.projection` and `Shapes.projection` attributes
- Added `DenseCloud.key` and `DenseCloud.label` attributes
- Added `DepthMaps.key` and `DepthMaps.label` attributes
- Added `Elevation.key` and `Elevation.label` attributes
- Added `Model.key` and `Model.label` attributes
- Added `Orthomosaic.key` and `Orthomosaic.label` attributes
- Added `TiledModel.key` and `TiledModel.label` attributes
- Added `point_colors` argument to `Chunk.buildDenseCloud()` method
- Added `ghosting_filter` argument to `Chunk.buildTexture()` method
- Added `minimum_size` argument to `Chunk.detectMarkers()` method
- Added `raster_transform` argument to `Chunk.exportModel()`, `Chunk.exportPoints()`, `Chunk.exportTiledModel()` methods
- Added `tiff_overviews` argument to `Chunk.exportDem()`, `Chunk.exportOrthomosaic()` and `Chunk.exportOrthophotos()` methods
- Added `min_zoom_level` and `max_zoom_level` arguments to `Chunk.exportDem()` and `Chunk.exportOrthomosaic()` methods
- Added `cameras` argument to `Chunk.exportOrthophotos()` method
- Added `image_format` argument to `Chunk.exportPoints()` method
- Added `page_numbers` argument to `Chunk.exportReport()` method
- Added `items`, `crs`, `ignore_labels`, `threshold` and `progress` arguments to `Chunk.loadReference()` method
- Added `create_markers` argument to `Chunk.loadReference()` method
- Added `progress` argument to `Chunk.saveReference()` method

- Added quality, volumetric_masks, keep_depth and reuse_depth arguments to Chunk.buildModel() method
- Added selected_faces and fix_borders arguments to Chunk.smoothModel() method
- Added export_points, export_markers, use_labels and progress arguments to Chunk.exportCameras() method
- Added channels and datatype arguments to Photo.image() method
- Added CamerasFormatBlocksExchange and CamerasFormatORIMA to CamerasFormat enum
- Added ImageFormatNone to ImageFormat enum
- Added UndefinedLayout to ImageLayout enum
- Added ModelFormatNone and ModelFormatABC to ModelFormat enum
- Added PointsFormatNone and PointsFormatCesium to PointsFormat enum
- Added RasterFormatNone to RasterFormat enum
- Added ReferenceFormatNone and ReferenceFormatAPM to ReferenceFormat enum
- Added TiledModelFormatNone, TiledModelFormatCesium and TiledModelFormatSLPK to TiledModelFormat enum
- Renamed Chunk.master_channel attribute to Chunk.primary_channel
- Removed MatchesFormat enum
- Removed Chunk.exportMatches() method
- Removed Camera.Reference.accuracy_ypr attribute
- Removed quality, filter, cameras, keep_depth, reuse_depth arguments from Chunk.buildDenseCloud() method
- Removed color_correction argument from Chunk.buildOrthomosaic() and Chunk.buildTexture() methods
- Removed fit_shutter argument from Chunk.optimizeCameras() method

3.6 PhotoScan version 1.3.5

No Python API changes

3.7 PhotoScan version 1.3.4

No Python API changes

3.8 PhotoScan version 1.3.3

- Added network_links argument to Chunk.exportDem() and Chunk.exportOrthomosaic() methods
- Added read_only argument to Document.open() method
- Added NetworkClient.setNodeCPUEnable() and NetworkClient.setNodeGPUMask() methods
- Added Chunk.modified, DenseCloud.modified, DepthMaps.modified, Document.modified, Elevation.modified, Masks.modified, Model.modified, Orthomosaic.modified, PointCloud.modified, Shapes.modified, Thumbnails.modified, TiledModel.modified attributes
- Added Document.read_only attribute

- Added CamerasFormatSummit to CamerasFormat enum

3.9 PhotoScan version 1.3.2

- Added vertex_colors argument to Chunk.buildModel() method
- Added Shape.vertex_ids attribute

3.10 PhotoScan version 1.3.1

- Added Settings and TiledModel classes
- Added Application.getBool() method
- Added Camera.unproject() method
- Added Chunk.addFrames(), Chunk.addMarkerGroup(), Chunk.addScalebarGroup() and Chunk.buildSeamlines() methods
- Added DenseCloud.pickPoint() and DenseCloud.updateStatistics() methods
- Added Elevation.altitude() method
- Added Matrix.svd() method
- Added Model.pickPoint() method
- Added Orthomosaic.reset() and Orthomosaic.update() methods
- Added PointCloud.pickPoint() method
- Added filter argument to Application.getOpenFileName(), Application.getOpenFileNames() and Application.getSaveFileName() methods
- Added point and visibility arguments to Chunk.addMarker() method
- Added raster_transform and write_scheme arguments to Chunk.exportDem() method
- Added write_scheme and white_background arguments to Chunk.exportOrthomosaic() method
- Added white_background argument to Chunk.exportOrthophotos() method
- Added projection argument to Chunk.exportMarkers() method
- Added markers argument to Chunk.exportModel() method
- Added pairs argument to Chunk.matchPhotos() method
- Added columns and delimiter arguments to Chunk.saveReference() method
- Added version argument to Document.save() method
- Renamed npasses argument in Chunk.smoothModel() method to strength and changed its type to float
- Renamed from and to arguments in CoordinateSystem.transform(), DenseCloud.assignClass(), DenseCloud.assignClassToSelection() and DenseCloud.classifyGroundPoints() methods to avoid collision with reserved words
- Added Application.settings attribute
- Added Chunk.tiled_model attribute
- Added ShapeGroup.color and ShapeGroup.show_labels attributes

- Added ImageFormatTGA to ImageFormat enum

3.11 PhotoScan version 1.3.0

- Added MarkerGroup, Masks, ScalebarGroup, Shutter and Thumbnails classes
- Added Application.PhotosPane class
- Added Model.Statistics class
- Added Orthomosaic.Patch and Orthomosaic.Patches classes
- Added PointCloud.Filter class
- Added CamerasFormat, EulerAngles, ImageFormat, ImageLayout, MaskOperation, MaskSource, MatchesFormat, ModelFormat, ModelViewMode, PointClass, PointsFormat, RasterFormat, ReferenceFormat, ReferenceItems, RotationOrder, TiffCompression, TiledModelFormat enums
- Added Application.captureOrthoView() method
- Added Chunk.refineMarkers() method
- Added CoordinateSystem.listBuiltinCRS() class method
- Added Matrix.translation() method
- Added Model.statistics() method
- Added NetworkClient.serverInfo(), NetworkClient.nodeStatus(), NetworkClient.setNodeCapability() and NetworkClient.quitNode() methods
- Added Photo.imageMeta() method
- Added Shape.area(), Shape.perimeter2D(), Shape.perimeter3D() and Shape.volume() methods
- Added Utils.createMarkers() method
- Added source argument to Application.captureModelView() method
- Added image_format argument to Chunk.exportDem() method
- Added write_alpha argument to Chunk.exportOrthophotos() method
- Added image_format and write_alpha arguments to Chunk.exportOrthomosaic() method
- Added groups, projection, shift and progress arguments to Chunk.exportShapes() method
- Added items and progress arguments to Chunk.copy() method
- Added sensor argument to Chunk.addCamera() method
- Added layout argument to Chunk.addPhotos() method
- Added jpeg_quality argument to Chunk.exportOrthomosaic() and Chunk.exportOrthophotos() methods
- Added fill_holes argument to Chunk.buildOrthomosaic() method
- Added fit_shutter argument to Chunk.optimizeCameras() method
- Added settings argument to Chunk.exportReport() method
- Added progress argument to various DenseCloud methods
- Added from argument to DenseCloud.classifyGroundPoints() method
- Added chunks and progress arguments to Document.append() method

- Added progress argument to Document.alignChunks() and Document.mergeChunks() methods
- Added revision argument to NetworkClient.batchList(), NetworkClient.batchStatus() methods
- Added Application.photos_pane attribute
- Added Camera.shutter attribute
- Added Chunk.masks and Chunk.thumbnails attributes
- Added Chunk.marker_groups and Chunk.scalebar_groups attributes
- Added Chunk.euler_angles and Chunk.scalebar_accuracy attributes
- Added CoordinateSystem.name attribute
- Added Marker.group and Scalebar.group attributes
- Added Orthomosaic.patches attribute
- Added RasterTransform.false_color attribute
- Added Sensor.bands attribute
- Added Shape.attributes attribute
- Added DepthMapsData, TiledModelData and OrthomosaicData to DataSource enum
- Added CircularTarget14bit to TargetType enum
- Renamed CameraReference class to Camera.Reference
- Renamed ConsolePane class to Application.ConsolePane
- Renamed MarkerProjection class to Marker.Projection
- Renamed MarkerProjections class to Marker.Projections
- Renamed MarkerReference class Marker.Reference
- Renamed MeshFace class to Model.Face
- Renamed MeshFaces class to Model.Faces
- Renamed MeshTexVertex class to Model.TexVertex
- Renamed MeshTexVertices class to Model.TexVertices
- Renamed MeshVertex class to Model.Vertex
- Renamed MeshVertices class to Model.Vertices
- Renamed PointCloudCameras class to PointCloud.Cameras
- Renamed PointCloudPoint class to PointCloud.Point
- Renamed PointCloudPoints class to PointCloud.Points
- Renamed PointCloudProjection class to PointCloud.Projection
- Renamed PointCloudProjections class to PointCloud.Projections
- Renamed PointCloudTrack class to PointCloud.Track
- Renamed PointCloudTracks class to PointCloud.Tracks
- Renamed ScalebarReference class to Scalebar.Reference
- Renamed ShapeVertices class to Shape.Vertices
- Renamed Application.enumOpenCLDevices() method to Application.enumGPUDevices()

- Renamed Shape.boundary attribute to Shape.boundary_type
- Renamed Chunk.accuracy_cameras to Chunk.camera_location_accuracy
- Renamed Chunk.accuracy_cameras_ypr to Chunk.camera_rotation_accuracy
- Renamed Chunk.accuracy_markers to Chunk.marker_location_accuracy
- Renamed Chunk.accuracy_projections to Chunk.marker_projection_accuracy
- Renamed Chunk.accuracy_tiepoints to Chunk.tiepoint_accuracy
- Renamed method argument in Chunk.importMasks() method to source and changed its type to MaskSource
- Replaced preselection argument with generic_preselection and reference_preselection arguments in Chunk.matchPhotos() method
- Replaced fit_cxcy argument with fit_cx and fit_cy arguments in Chunk.optimizeCameras() method
- Replaced fit_k1k2k3 argument with fit_k1, fit_k2 and fit_k3 arguments in Chunk.optimizeCameras() method
- Replaced fit_p1p2 argument with fit_p1 and fit_p2 arguments in Chunk.optimizeCameras() method
- Replaced Application.cpu_cores_inactive with Application.cpu_enable attribute
- Changed type of source_data argument in Chunk.buildContours() to DataSource
- Changed type of format argument in Chunk.importCameras() and Chunk.exportCameras() methods to Cameras-Format
- Changed type of rotation_order argument in Chunk.exportCameras() to RotationOrder
- Changed type of format argument in Chunk.exportDem() and Chunk.exportOrthomosaic() methods to Raster-Format
- Changed type of format argument in Chunk.exportMatches() method to MatchesFormat
- Changed type of texture_format argument in Chunk.exportModel() method to ImageFormat
- Changed type of format argument in Chunk.importModel() and Chunk.exportModel() methods to ModelFormat
- Changed type of format argument in Chunk.exportPoints() method to PointsFormat
- Changed type of tiff_compression argument in Chunk.exportOrthomosaic() and Chunk.exportOrthophotos() methods to TiffCompression
- Changed type of items argument in Chunk.exportShapes() method to Shape.Type
- Changed type of format argument in Chunk.exportTiledModel() method to TiledModelFormat
- Changed type of mesh_format argument in Chunk.exportTiledModel() method to ModelFormat
- Changed type of operation argument in Chunk.importMasks() method to MaskOperation
- Changed type of format argument in Chunk.loadReference() and Chunk.saveReference() methods to Reference-Format
- Changed type of items argument in Chunk.saveReference() method to ReferenceItems
- Removed return values from Camera.open(), Chunk.addPhotos(), Chunk.alignCameras(), Chunk.buildContours(), Chunk.buildDem(), Chunk.buildDenseCloud(), Chunk.buildModel(), Chunk.buildOrthomosaic(), Chunk.buildPoints(), Chunk.buildTexture(), Chunk.buildTiledModel(), Chunk.buildUV(), Chunk.decimateModel(), Chunk.detectMarkers(), Chunk.estimateImageQuality(), Chunk.exportCameras(), Chunk.exportDem(), Chunk.exportMarkers(), Chunk.exportMatches(), Chunk.exportModel(), Chunk.exportOrthomosaic(), Chunk.exportOrthophotos(), Chunk.exportPoints(), Chunk.exportReport(), Chunk.exportShapes(), Chunk.exportTiledModel(), Chunk.importCameras(), Chunk.importDem(), Chunk.importMarkers(), Chunk.importMasks(), Chunk.importModel(),

Chunk.importShapes(), Chunk.loadReference(), Chunk.loadReferenceExif(), Chunk.matchPhotos(),
Chunk.optimizeCameras(), Chunk.remove(), Chunk.saveReference(), Chunk.smoothModel(),
Chunk.thinPointCloud(), Chunk.trackMarkers(), CirTransform.calibrate(), CoordinateSystem.init(),
DenseCloud.classifyGroundPoints(), DenseCloud.compactPoints(), DenseCloud.selectMaskedPoints(),
DenseCloud.selectPointsByColor(), Document.alignChunks(), Document.append(), Document.clear(),
Document.mergeChunks(), Document.open(), Document.remove(), Document.save(), Mask.load(),
Model.closeHoles(), Model.fixTopology(), Model.loadTexture(), Model.removeComponents(),
Model.saveTexture(), Model.setTexture(), NetworkClient.abortBatch(), NetworkClient.abortNode(), Network-
Client.connect(), NetworkClient.pauseBatch(), NetworkClient.pauseNode(), NetworkClient.resumeBatch(),
NetworkClient.resumeNode(), NetworkClient.setBatchPriority(), NetworkClient.setNodePriority(),
Photo.open(), PointCloud.export(), RasterTransform.calibrateRange(), Thumbnail.load() methods in favor
of exceptions

- Removed Chunk.exportContours() method
- Removed obsolete Matrix.diag() and Matrix.translation() class methods
- Removed unused focal_length argument from Calibration.save() method
- Modified Utils.mat2opk() and Utils.opk2mat() methods to work with camera to world rotation matrices

3.12 PhotoScan version 1.2.6

No Python API changes

3.13 PhotoScan version 1.2.5

- Added ShapeGroup and ShapeVertices classes
- Added CoordinateSystem.proj4 and CoordinateSystem.geogcs attributes
- Added Shapes.shapes and Shapes.groups attributes
- Added Shape.label, Shape.vertices, Shape.group, Shape.has_z, Shape.key and Shape.selected attributes
- Added Shapes.addGroup(), Shapes.addShape() and Shapes.remove() methods
- Added CoordinateSystem.transform() method
- Added Matrix.Diag(), Matrix.Rotation(), Matrix.Translation() and Matrix.Scale() class methods
- Added Matrix.rotation() and Matrix.scale() methods
- Added DenseCloud.restorePoints() and DenseCloud.selectPointsByColor() methods
- Added Application.captureModelView() method
- Added Mask.invert() method
- Added adaptive_fitting parameter to Chunk.alignCameras() method
- Added load_rotation and load_accuracy parameters to Chunk.loadReferenceExif() method
- Added source parameter to Chunk.buildTiledModel() method
- Added fill_holes parameter to Chunk.buildTexture() method

3.14 PhotoScan version 1.2.4

- Added NetworkClient and NetworkTask classes
- Added Calibration.f, Calibration.b1, Calibration.b2 attributes
- Added Chunk.exportMatches() method
- Added DenseCloud.compactPoints() method
- Added Orthomosaic.removeOrthophotos() method
- Added fit_b1 and fit_b2 parameters to Chunk.optimizeCameras() method
- Added tiff_big parameter to Chunk.exportOrthomosaic(), Chunk.exportDem() and Chunk.exportOrthophotos() methods
- Added classes parameter to Chunk.exportPoints() method
- Added progress parameter to processing methods
- Removed Calibration.fx, Calibration.fy, Calibration.skew attributes

3.15 PhotoScan version 1.2.3

- Added tiff_compression parameter to Chunk.exportOrthomosaic() and Chunk.exportOrthophotos() methods

3.16 PhotoScan version 1.2.2

- Added Camera.orientation attribute
- Added chunks parameter to Document.save() method

3.17 PhotoScan version 1.2.1

- Added CirTransform and RasterTransform classes
- Added Chunk.cir_transform and Chunk.raster_transform attributes
- Added Chunk.exportOrthophotos() method
- Added udim parameter to Chunk.exportModel() method
- Renamed RasterTransform enum to RasterTransformType

3.18 PhotoScan version 1.2.0

- Added Elevation and Orthomosaic classes
- Added Shape and Shapes classes
- Added Antenna class
- Added DataSource enum
- Added Camera.error() method

- Added `Chunk.buildContours()` and `Chunk.exportContours()` methods
- Added `Chunk.importShapes()` and `Chunk.exportShapes()` methods
- Added `Chunk.exportMarkers()` and `Chunk.importMarkers()` methods
- Added `Chunk.importDem()` method
- Added `Chunk.buildDem()`, `Chunk.buildOrthomosaic()` and `Chunk.buildTiledModel()` methods
- Added `PointCloud.removeSelectedPoints()` and `PointCloud.cropSelectedPoints()` methods
- Added `Utils.mat2opk()`, `Utils.mat2ypr()`, `Utils.opk2mat()` and `Utils.ypr2mat()` methods
- Added `Chunk.elevation`, `Chunk.orthomosaic` and `Chunk.shapes` attributes
- Added `Chunk.accuracy_cameras_ypr` attribute
- Added `Sensor.antenna`, `Sensor.plane_count` and `Sensor.planes` attributes
- Added `Calibration.p3` and `Calibration.p4` attributes
- Added `Camera.planes` attribute
- Added `CameraReference.accuracy_ypr` attribute
- Added `CameraReference.accuracy`, `MarkerReference.accuracy` and `ScalebarReference.accuracy` attributes
- Added `Application.activated` attribute
- Added `Chunk.image_brightness` attribute
- Added `fit_p3` and `fit_p4` parameters to `Chunk.optimizeCameras()` method
- Added `icon` parameter to `Application.addItem()` method
- Added `title` and `description` parameters to `Chunk.exportReport()` method
- Added `operation` parameter to `Chunk.importMasks()` method
- Added `columns`, `delimiter`, `group_delimiters`, `skip_rows` parameters to `Chunk.loadReference()` method
- Added `items` parameter to `Chunk.saveReference()` method
- Renamed `Chunk.exportModelTiled()` to `Chunk.exportTiledModel()`
- Renamed `Chunk.exportOrthophoto()` to `Chunk.exportOrthomosaic()`
- Removed `OrthoSurface` and `PointsSource` enums
- Removed `PointCloud.groups` attribute
- Removed `Chunk.camera_offset` attribute

3.19 PhotoScan version 1.1.1

- Added `Chunk.exportModelTiles()` method
- Added `noparity` parameter to `Chunk.detectMarkers()` method
- Added `blockw` and `blockh` parameters to `Chunk.exportPoints()` method

3.20 PhotoScan version 1.1.0

- Added CameraOffset and ConsolePane classes
- Added CameraGroup, CameraReference, ChunkTransform, DepthMap, DepthMaps, MarkerReference, MarkerProjection, Mask, PointCloudGroups, PointCloudTrack, PointCloudTracks, ScalebarReference, Thumbnail classes
- Added Chunk.key, Sensor.key, Camera.key, Marker.key and Scalebar.key attributes
- Added Application.console attribute
- Added Application.addMenuSeparator() method
- Added Chunk.importMasks() method
- Added Chunk.addSensor(), Chunk.addCameraGroup(), Chunk.addCamera(), Chunk.addMarker(), Chunk.addScalebar() methods
- Added Chunk.addPhotos(), Chunk.addFrame() methods
- Added Chunk.master_channel and Chunk.camera_offset attributes
- Added Calibration.error() method
- Added Matrix.mulp() and Matrix.mulv() methods
- Added DenseCloud.assignClass(), DenseCloud.assignClassToSelection(), DenseCloud.removePoints() methods
- Added DenseCloud.classifyGroundPoints() and DenseCloud.selectMaskedPoints() methods
- Added Model.renderNormalMap() method
- Added DenseCloud.meta and Model.meta attributes
- Added PointCloud.tracks, PointCloud.groups attributes
- Added Image.tostring() and Image.fromstring() methods
- Added Image.channels property
- Added U16 data type support in Image class
- Added classes parameter to Chunk.buildModel() method
- Added crop_borders parameter to Chunk.exportDem() method
- Added chunk parameter to Document.addChunk() method
- Added format parameter to Calibration.save() and Calibration.load() methods
- Moved OpenCL settings into Application class
- Converted string constants to enum objects
- Removed Cameras, Chunks, DenseClouds, Frame, Frames, GroundControl, GroundControlLocations, GroundControlLocation, Markers, MarkerPositions, Models, Scalebars, Sensors classes

3.21 PhotoScan version 1.0.0

- Added DenseCloud and DenseClouds classes
- Added Chunk.exportModel() and Chunk.importModel() methods

- Added `Chunk.estimateImageQuality()` method
- Added `Chunk.buildDenseCloud()` and `Chunk.smoothModel()` methods
- Added `Photo.thumbnail()` method
- Added `Image.resize()` method
- Added `Application.enumOpenCLDevices()` method
- Added `Utils.estimateImageQuality()` method
- Added `Camera.meta`, `Marker.meta`, `Scalebar.meta` and `Photo.meta` attributes
- Added `Chunk.dense_cloud` and `Chunk.dense_clouds` attributes
- Added `page` parameter to `Model.setTexture()` and `Model.texture()` methods
- Added `shortcut` parameter to `Application.addItem()` method
- Added `absolute_paths` parameter to `Document.save()` method
- Added `fit_f`, `fit_cxcy`, `fit_k1k2k3` and `fit_k4` parameters to `Chunk.optimizePhotos()` method
- Changed parameters of `Chunk.buildModel()` and `Chunk.buildTexture()` methods
- Changed parameters of `Chunk.exportPoints()` method
- Changed parameters of `Model.save()` method
- Changed return value of `Chunks.add()` method
- Removed `Chunk.buildDepth()` method
- Removed `Camera.depth()` and `Camera.setDepth()` methods
- Removed `Frame.depth()` and `Frame.setDepth()` methods
- Removed `Frame.depth_calib` attribute

3.22 PhotoScan version 0.9.1

- Added `Sensor`, `Scalebar` and `MetaData` classes
- Added `Camera.sensor` attribute
- Added `Chunk.sensors` attribute
- Added `Calibration.width`, `Calibration.height` and `Calibration.k4` attributes
- Added `Chunk.refineMatches()` method
- Added `Model.area()` and `Model.volume()` methods
- Added `Model.renderDepth()`, `Model.renderImage()` and `Model.renderMask()` methods
- Added `Chunk.meta` and `Document.meta` attributes
- Added `Calibration.project()` and `Calibration.unproject()` methods
- Added `Application.addItem()` method
- Added `Model.closeHoles()` and `Model.fixTopology()` methods

3.23 PhotoScan version 0.9.0

- Added Camera, Frame and CoordinateSystem classes
- Added Chunk.exportReport() method
- Added Chunk.trackMarkers() and Chunk.detectMarkers() methods
- Added Chunk.extractFrames() and Chunk.removeFrames() methods
- Added Chunk.matchPhotos() method
- Added Chunk.buildDepth() and Chunk.resetDepth() methods
- Added Chunk.cameras property
- Added Utils.createDifferenceMask() method
- Revised Chunk.alignPhotos() method
- Revised Chunk.buildPoints() method
- Revised Chunk.buildModel() method
- Removed Photo class (deprecated)
- Removed GeoProjection class (deprecated)
- Removed Chunk.photos property (deprecated)

3.24 PhotoScan version 0.8.5

- Added Chunk.fix_calibration property
- Added Chunk.exportCameras() method
- Added Chunk.exportPoints() method for dense/sparse point cloud export
- Added accuracy_cameras, accuracy_markers and accuracy_projections properties to the GroundControl class
- Added Image.undistort() method
- Added PointCloudPoint.selected and PointCloudPoint.valid properties
- Added GeoProjection.authority property
- Added GeoProjection.init() method
- Moved GroundControl.optimize() method to Chunk.optimize()
- Removed “fix_calibration” parameter from Chunk.alignPhotos() method
- Removed GeoProjection.epsg property

3.25 PhotoScan version 0.8.4

- Added GroundControl.optimize() method
- Command line scripting support removed

3.26 PhotoScan version 0.8.3

Initial version of PhotoScan Python API

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