Intel RealSense D435i

We use the [Intel RealSense](#) [D435i](#), which has an integrated Inertial Measurement Unit (IMU).

Intel RealSense D435i resources:

- [Intel RealSense Documentation](#)
- [librealsense](#)

Script

The **librealsense** can be installed as a) **Debian package** (default) or b) **build from source**.

When installed as Debian package, the librealsense is installed under **/usr**.

Note that the latest Debian package for arm64 version (e.g. 2.41) might be behind the latest release version (e.g. 2.45).

When building from source, the librealsense is put under **/opt/Intel_RealSense_D435i/librealsense** and is installed under **usr/local**.

Run one of the Intel RealSense D435i installation scripts
sw/NVIDIA_Jetson_Xavier_NX/Scripts$ bash **install-4-Intel_RealSense_D435i-Debian.sh**
sw/NVIDIA_Jetson_Xavier_NX/Scripts$ bash **install-4-Intel_RealSense_D435i-Source.sh**

Dockerfile

Intel RealSense D435i Dockerfile
sw/NVIDIA_Jetson_Xavier_NX/Docker/**Dockerfile-4-Intel_RealSense_D435i**

The docker build script sw/NVIDIA_Jetson_Xavier_NX/Docker/**build-Docker.sh** allows to chose between the different installation methods by setting the build argument REALSENSE to either realsense-debian or realsense-source.

Intel RealSense SDK 2.0 (librealsense v2.45.0)

Intel RealSense provides **librealsense**, a Software Development Kit (SDK) for the Intel RealSense depth cameras, on [GitHub](#).

Clone librealsense v2.45.0 repository from GitHub
sw/NVIDIA_Jetson_Xavier_NX/Intel_RealSense_D435i$: git clone https://github.com/IntelRealSense/librealsense.git

sw/NVIDIA_Jetson_Xavier_NX/Intel_RealSense_D435i/librealsense$: git pull
sw/NVIDIA_Jetson_Xavier_NX/Intel_RealSense_D435i/librealsense$: git checkout v2.45.0
An already downloaded copy can be found here:
sw/NVIDIA_Jetson_Xavier_NX/Intel_RealSense_D435i/**librealsense**

Update Firmware
$: **realsense-viewer**
> Click Intel RealSense D435i More and select Install Recommended Firmware...

View Imagery
$: **realsense-viewer**