RealSense D4XX Sensors

This includes sensor D435i, D455

- Different modes configurations can be done with the SDK, and generate the Json file with the configuration.
    - This only runs on a X86 machine
    - recommended to use "high accuracy" mode
    - In ROS pass the parameter "json_file_path" with the file to the json file.
- The color image and depth image topics in ROS are not rectified, It assumed that you will rectify them externally.

For the color image, you can use the package image_proc/rectify

EXAMPLE:

```
<node pkg="nodelet" type="nodelet" name="image_proc_manager" args="manager"/>
    <node pkg="nodelet" type="nodelet" name="rectify_color" args="load image_proc/rectify image_proc_manager">
    <remap from="image_mono" to="$(arg camera_raw_topic)" />
    <remap from="camera_info" to="$(arg camera_info_topic)"/>
    <remap from="image_rect" to="$(arg image_rect_topic)" />
    <param name="queue_size" type="int" value="1" />
</node>
```

For the Depth image, you can use the same image_proc/rectify (notice that interpolation needs to be set to `0` . It introduces lots of noise if it is `1`, by default it is set to true.

EXAMPLE:

```
<node pkg="nodelet" type="nodelet" name="rectify_depth" args="load image_proc/rectify image_proc_manager">
    <remap from="image_mono"  to="$(arg depth_registed_image_topic)" />
    <remap from="camera_info" to="$(arg depth_registed_info_topic)"/>
    <remap from="image_rect"  to="$(arg depth_image_rect_topic)" />
    <param name="queue_size"     type="int"  value="1" />
    <param name="interpolation"  type="int"  value="0" />
 </node>
```