Intel RealSense D435

1. Install ROS package

```
sudo apt-get install ros-noetic-realsense2-camera
sudo apt-get install ros-noetic-realsense2-description
```

2. Launch driver

```
roslaunch realsense2_camera rs_aligned_depth.launch
```

3. Display image

```
rqt_image_view
```

4. Exmaples

```python
import rospy
import cv2
from sensor_msgs.msg import Image
from cv_bridge import CvBridge, CvBridgeError

bridge = CvBridge()


def callback(data):
    try:
        cv_image = bridge.imgmsg_to_cv2(data, "bgr8")
    except CvBridgeError as e:
        print(e)

    cv2.imshow("Image window", cv_image)
    cv2.waitKey(3)

def main():
  rospy.init_node('image_converter', anonymous=True)
  rospy.Subscriber("/camera/color/image_raw",Image,callback)
  try:
    rospy.spin()
  except KeyboardInterrupt:
    print("Shutting down")
  cv2.destroyAllWindows()
```

```python
if __name__ == '__main__':
    main()
```