

Refer to the realsense-ros scripts demo

[x,y,z,(0,0,0,1),time,/bottle,/camera\_color\_frame]

Tf.TransformBroadcaster

pulish\_bottle\_tf.py

rs2.rs2\_deproject\_pixel\_to\_point

/camera/aligned\_depth\_to\_color/camera\_info

/camera/aligned\_depth\_to\_color/image\_raw

/yolo\_result\_out

[x1,y1,x2,y2]

Arg: align\_depth

D435i

rs\_camera.launch

Yolov5

Ros.py

/camera/color/image\_raw