1. Camera usage instructions

Using Orbbec_ After the launch command in the SDK feature pack drives the camera, you will find that using USB_ The cam cannot drive the camera and will report an error as shown in the following figure.

```
process[image_view-3]: started with pid [10766]
[ INFO] [1697529235.315517776]: Initializing nodelet with 4 worker threads.
[ INFO] [1697529235.405725041]: Using transport "raw"
[ INFO] [1697529235.425513328]: using default calibration URL
[ INFO] [1697529235.426148155]: camera calibration URL: file:///home/yahboom/.ro
s/camera_info/head_camera.yaml
[ WARN] [1697529235.426534453]: [head_camera] does not match name narrow_stereo
in file /home/yahboom/.ros/camera_info/head_camera.yaml
[ INFO] [1697529235.426583374]: Starting 'head_camera' (/dev/video0) at 640x480
via mmap (yuyv) at 30 FPS
[ERROR] [1697529235.426640067]: Cannot identify '/dev/video0': 2, No such file o
r directory
[usb_cam-2] process has died [pid 10765, exit code 1, cmd /opt/ros/noetic/lib/us
b_cam/usb_cam_node __name:=usb_cam __log:=/home/yahboom/.ros/log/51dd48e6-6cc2-1
1ee-b19d-65f5d1e636b5/usb_cam-2.log].
log file: /home/yahboom/.ros/log/51dd48e6-6cc2-11ee-b19d-65f5d1e636b5/usb_cam-2*
.log
```

Solution:
Reseat the camera and then use USB_ The camera can now be turned on normally, including using OpenCV to turn on the camera. If the above error occurs, unplug and plug it again.

Just use Orbbec first_ After the launch in the SDK drives the camera and before using OpenCV to drive the camera, it needs to be unplugged and unplugged again.