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Using ROS Launch

Normally this is used to start nodes based on a launch file.

Normal Usage:

roslaunch <PACKAGE> <LAUNCH_FILE>

Listing the Nodes Launched

This will list the nodes that a launch file will run on stdout.

roslaunch <PACKAGE> <LAUNCH_FILE> --nodes

Topic Remapping/Argument Replacement

This allows for changing the topic that a node publishes or subscribes to. This is really useful when using image_view.

roslaunch <PACKAGE> <LAUNCH FILE> <ARG>:=<NEW VALUE> <TOPIC>:=<NEW TOPIC>

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From:

https://robosub-vm.eecs.wsu.edu/wiki/ - Palouse RoboSub Technical Documentation

Permanent link:

https://robosub-vm.eecs.wsu.edu/wiki/cs/ros/roslaunch/start

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