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>
```

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

Permanent link: https://robosub.eecs.wsu.edu/wiki/cs/ros/roslaunch/start

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