

# 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:

<http://robosub-vm.eecs.wsu.edu/wiki/> - **Palouse RoboSub Technical Documentation**

Permanent link:

<http://robosub-vm.eecs.wsu.edu/wiki/cs/ros/roslaunch/start>



Last update: **2017/01/14 21:09**