

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>



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