06. ROS 2 Launch, Param, Bag

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ROS 2 Launch

- Launch multiple nodes
- Set arguments
- Monitor running nodes
- React on changes in the state of nodes
- Python, XML and YAML file formats

Usage

```
ros2 launch package_name file.launch
ros2 launch irob_robot dvrk_server.launch arm_typ:=PSM1
```

ROS 2 Parameters

- Configure nodes at startup or during runtime without changing the code
- Associated with individual nodes
- Consists of: key, value, descriptor
- Available data types: bool, int64, float64, string, byte[], bool[], int64[], float64[] or string[].
- Useful command: `ros2 param`

ROS 2 Bag

- Record and playback ROS topics