

06. Roslaunch, ROS paraméter szerver, Rosbag

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Roslaunch

- Launch multiple nodes
 - Also launches ROS master if not running
 - Set parameters
 - XML file format, `.launch` extension
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Example launch file

```
<!-- dvrk_server.launch -->
<!-- Launch the irob dVRK high-level robot controller. After start, it
will wait for irob_msgs/Robot actions -->

<launch>
  <group ns="saf">

    <arg name="arm_typ" default="PSM2"/>
    <arg name="arm_name" default="arm_1"/>
    <arg name="camera_registration_file"
default="registration_psm1.yaml"/>

    <arg name="instrument_info_file" default="prograsp_forceps.yaml"/>

    <include file="$(find irob_robot)/config/dvrk_topic_names.xml" />

    <node name="robot_server_${arg arm_typ}" pkg="irob_robot"
type="robot_server_dvrk"

output="screen">

    <param name="arm_typ" type="string" value="$(arg arm_typ)" />
    <param name="arm_name" type="string" value="$(arg arm_name)" /
>
    <param name="home_joint_angles" type="yaml" value="[0.0, 0.0,
0.0, 0.0, 0.0, 0.0]" />

    <rosparam command="load"
```