bag_tools Document

Version	Author	Date
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1. Pre requests 装机准备

安装以下两个库, glog和gflags在我们的愚公里面因为一直有,这里就不赘述.

```
sudo apt-get install ros-kinetic-ros-type-introspection
sudo apt-get install ros-kinetic-topic-tools
cd ~/yugong_ws/src
git clone https://bitbucket.org/bito-robotics/bag_tools
```

之后正常在yugong_ws里面编译即可.

2.launch和参数说明

2.1 rosbag_record.launch:

```xml
<?xml version="1.0"?>
<launch>
    <group>
        <arg name="repo_name" default="yugong"/>
        <arg name="deploy_dir" default="$(env ROS_HOME)/../yugong_ws/src/$(arg repo_name)/$(arg repo_name)"/>
        <arg name="agent_serial" default="$(env HOSTNAME)"/>
        <!-- <arg name="agent_serial" default="yg00b10018042309000n00"/> -->
        <node name="node_rosbag_record" pkg="bag_tools" type="rosbag_record" args="--log_dir $(arg deploy_dir)/log --minloglevel 0 --max_log_size 10" output="screen">
            <rosparam param="/deploy_dir" subst_value="True">$(arg deploy_dir)/log</rosparam>
            <rosparam param="/agent_serial" subst_value="True">$(arg agent_serial)</rosparam>
            <rosparam command="load" file="$(find bag_tools)/param/common.yaml" />
        </node>
    </group>
</launch>
```

会输出两个文件出来,一个是log,一个是bag文件.其中log会存在yugong/log下面, bag会存在/deploy_dir 制定的位置,所以如果自定义存放,可以修改上述的rosparam里面加载的位置.

2.2 common.yaml:

```
/add_agent_serial: true
/topics_name: ["/trajectory_index", "/tracker_state"]
```

topics_name表示需要录制的topic的名称.

add_agent_serial表示是否要在topic前面加上launch中写的名称, 如文档中,加入的话, remap后的topic名称变成:

(假设HOSTNAME为yg00b00019120100001n00) ["/yg00b00019120100001n00/trajectory_index", "/yg00b00019120100001n00/tracker_state"]

3. 运行方法

```
roslaunch bag_tools rosbag_record.launch
```

然后默认的在yugong/log下面可以找到rosbag和log文件

4.TODO

1) bag的获取大小和中断重连的接口.

2) 自动删除bag包的操作.(shell脚本可能会更好)