

• S#1 Creating Custom Launch Files from Package

Sunday, October 24, 2021 11:49 AM

①

```
<launch>
  <arg name="model" default="$(env TURTLEBOT3_MODEL)" doc="model type [burger, waffle, waffle_pi]"/>
  <arg name="multi_robot_name" default="" />

  <include file="$(find turtlebot3_bringup)/launch/includes/description.launch.xml">
    <arg name="model" value="$(arg model)" />
  </include>

  <node pkg="robot_state_publisher" type="robot_state_publisher" name="robot_state_publisher">
    <param name="publish_frequency" type="double" value="50.0" />
    <param name="tf_prefix" value="$(arg multi_robot_name)" />
  </node>
</launch>
```

②

```
<launch>
  <arg name="model"/>
  <arg name="urdf_file" default="$(find xacro)/xacro --inorder '$(find turtlebot3_description)/urdf/turtlebot3_${arg model}.urdf'"/>
  <param name="robot_description" command="$(arg urdf_file)" />
</launch>
```

③

```
<launch>
  <arg name="model" default="$(env TURTLEBOT3_MODEL)" doc="model type [burger, waffle, waffle_pi]"/>
  <arg name="multi_robot_name" default="" />

  <include file="$(find turtlebot3_bringup)/launch/includes/description.launch.xml">
    <arg name="model" value="$(arg model)" />
  </include>

  <node pkg="robot_state_publisher" type="robot_state_publisher" name="robot_state_publisher">
    <param name="publish_frequency" type="double" value="50.0" />
    <param name="tf_prefix" value="$(arg multi_robot_name)" />
  </node>
</launch>
```

