


## ROS bags: shell commands

- Record all topics in a bag  
> `rosbag record --all`
- Record given topics  
> `rosbag record topic_1 topic_2 topic_3`
- Show information about a bag  
> `rosbag info bag_name.bag`
- Read a bag and publish its contents  
> `rosbag play bag_name.bag`
- Playback options can be defined e.g.  
> `rosbag play --rate=0.5 bag_name.bag`  
    `--rate=`*factor*      Publish rate factor  
    `--clock`            Publish the clock time (set param  
                          `use_sim_time` to true)  
    `--loop`             Loop playback
- Convert a bag file using the given Python expression  
> `rosbag filter bag_name.bag new_bag_name.bag "Python expression"`

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