

ChatGPT



I have published this map: /tb3_1/map and /tb3_2/map
how can i remap /tb3_1/map to /map1 and /tb3_2/map to /map2

To remap ROS (Robot Operating System) topics like `/tb3_1/map` to `/map1` and `/tb3_2/map` to `/map2`, you can use **ROS topic remapping**, which is often done in launch files.

✓ Option 1: Remap using the `roslaunch` file

In your launch file, you can use the `<remap>` tag like this:

```
xml

<node name="map1_node" pkg="your_package" type="your_node_type">
  <remap from="/tb3_1/map" to="/map1"/>
</node>

<node name="map2_node" pkg="your_package" type="your_node_type">
  <remap from="/tb3_2/map" to="/map2"/>
</node>
```

Make sure the node subscribing to or publishing `/map1` or `/map2` internally uses `/tb3_1/map` or `/tb3_2/map`, so the remap takes effect properly.

✓ Option 2: Remap using the command line

If you're running the nodes manually, you can do this directly with the `roslaunch` or `roslaunch` command:

```
bash

roslaunch your_package your_node _map:=/map1
```

Or, using remap syntax directly:

```
bash

roslaunch your_package your_node /tb3_1/map:=/map1
roslaunch your_package your_node /tb3_2/map:=/map2
```

🧠 Important Notes:

- ROS topic remapping is **local to each node**, meaning it only affects the node where the remap is defined.

- If you're just trying to alias the topic globally (i.e., have `/map1` publish the same data as `/tb3_1/map`), you can use `roslaunch topic_tools relay`:

```
bash
roslaunch topic_tools relay /tb3_1/map
```



no in ros2 from terminal

Ah, got it — you're using **ROS 2** and want to remap topics **from the terminal**, not in launch files.

✓ **In ROS 2, you can remap topics directly from the command line like this:**

Use the `--ros-args --remap` option when launching your node.


Example:

Let's say you have a node that subscribes to `/tb3_1/map` and you want it to receive from `/map1` instead.

```
bash
ros2 run your_package your_node --ros-args --remap /tb3_1/map:=/map1
```

And for the second one:

```
bash
ros2 run your_package your_node --ros-args --remap /tb3_2/map:=/map2
```

 **If you want to just relay (duplicate) the map topics to new topic names (like an alias), you can use `topic_tools relay` in ROS 2 as well:**

```
bash
ros2 run topic_tools relay --ros-args -r input:=/tb3_1/map -r output:=/map1
ros2 run topic_tools relay --ros-args -r input:=/tb3_2/map -r output:=/map2
```

This will publish `/map1` and `/map2` with the same content as `/tb3_1/map` and `/tb3_2/map`, respectively.

Let me know if you're trying to do it for a launch file in ROS 2 too — the syntax is a bit different.



```
ros2 run your_package your_node --ros-args --remap /tb3_1/map:=/map1 and other map2 in same line
```

If you want to run a **single ROS 2 node** and remap **multiple topics** in the **same command line**, you can chain the `--remap` arguments like this:`

```
bash

ros2 run your_package your_node \
  --ros-args \
  --remap /tb3_1/map:=/map1 \
  --remap /tb3_2/map:=/map2
```

✓ This will remap both topics in a **single execution** of the node.

Important:

This only works if the **same node** is subscribing or publishing to both `/tb3_1/map` and /tb3_2/map`. If those topics are used in different nodes, you'll need to run separate commands for each node or use a launch file.`

Let me know your exact setup if you want help combining this into a launch file or managing multiple nodes.