```
<launch>
  <arg name="x" default="0.0" />
  <arg name="y" default="0.0" />
  <arg name="z" default="0.0" />
  <arg name="yaw" default="0.0" />
  <arg name="robot_name"/>
  <arg name="ns" default="fetch" />

  <rosparam command="load" file="$(find fetch_gazebo)/config/default_controllers.yaml"/>
<!--  <rosparam command="load" file="$(find fetch_gazebo)/config/freight_controllers.yaml"/>-->

  <!-- URDF and TF support -->
  <node name="robot_state_publisher_fetch" pkg="robot_state_publisher"
type="robot_state_publisher" >
    <param name="publish_frequency" value="100.0"/>
  </node>

  <!-- Put a robot in gazebo, make it look pretty -->
  <param name="robot_description" command="$(find xacro)/xacro.py $(find
fetch_gazebo)/robots/fetch.gazebo.xacro"/>
<!--  <param name="robot_description" command="$(find xacro)/xacro.py $(find
fetch_gazebo)/robots/freight.gazebo.xacro"/>-->
  <node name="fetch_urdf_spawner" pkg="gazebo_ros" type="spawn_model" respawn="false"
output="screen"
        args="-urdf -x $(arg x) -y $(arg y) -z $(arg z) -Y $(arg yaw) -model fetch -param
robot_description">
    <remap from="robot_description" to="/fetch/robot_description" />
  </node>

  <node name="prepare_robot" pkg="fetch_gazebo" type="prepare_simulated_robot.py" />

  <!-- Give this robot a serial number and version -->
  <param name="robot/serial" value="ABCDEFGHIJKLMNOPQRSTUVWX" />
  <param name="robot/version" value="0.0.1" />

  <!-- Head Camera Pipeline -->
  <include file="$(find fetch_gazebo)/launch/include/head_camera.launch.xml" />

  <!-- Publish base_scan_raw if anything subscribes to it -->
  <node name="publish_base_scan_raw" pkg="topic_tools" type="relay" args="base_scan
base_scan_raw" >
    <param name="lazy" type="bool" value="True"/>
  </node>

  <!-- Start a mux between application and teleop -->
  <node pkg="topic_tools" type="mux" name="cmd_vel_mux" respawn="true"
args="base_controller/command /cmd_vel /teleop/cmd_vel">
    <remap from="mux" to="cmd_vel_mux" />
  </node>


</launch>
```