ROS 2 Persistent Parameter Server

- inspired by ROS 1 parameter server.

- can set/get any parameters in this global server.

- can save/load the parameters in storage.
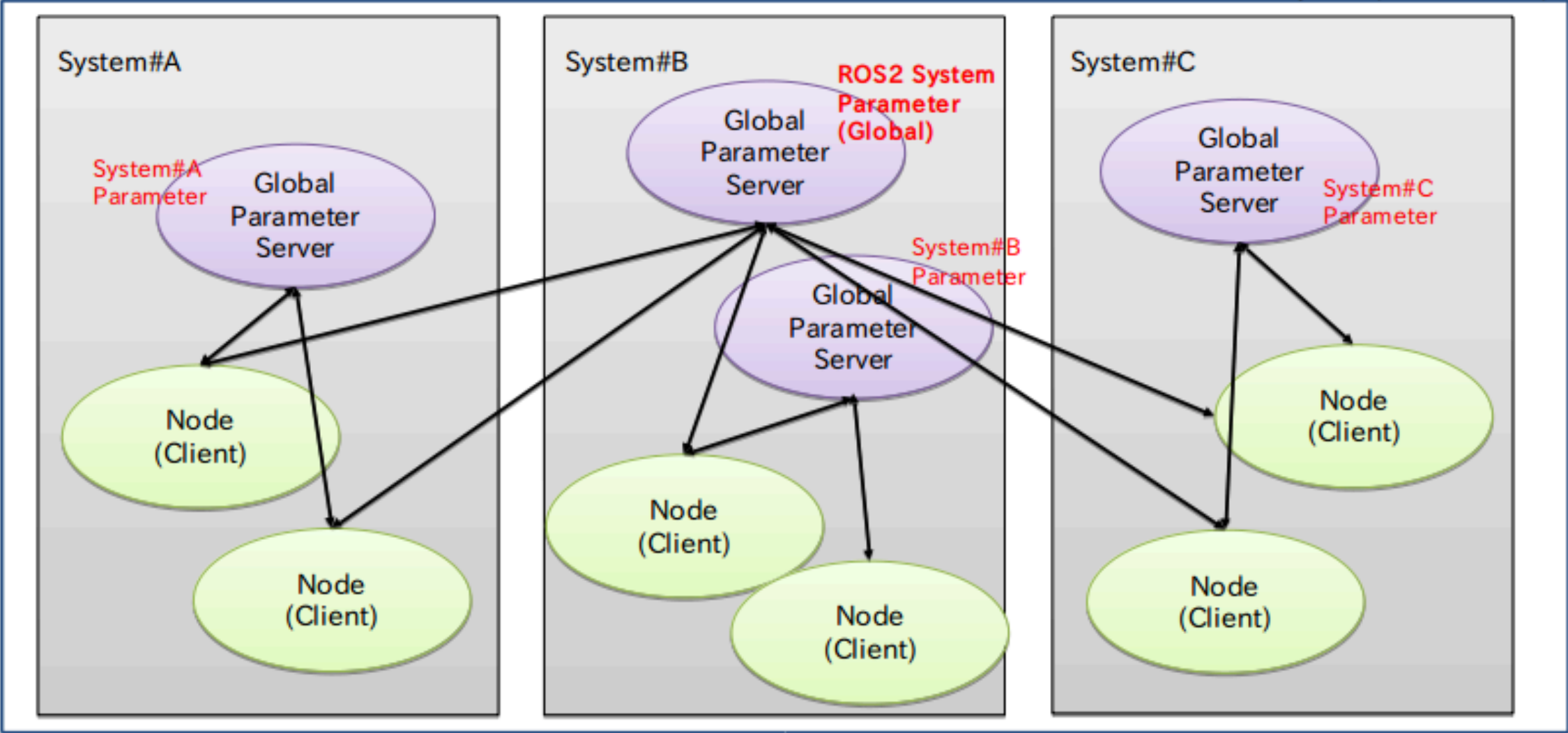
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Why we need this?

- Global configuration that many nodes share (e.g. RTOS priorities, vehicle dimensions, …)

- Generic ROS 2 system or localhost wide parameter server.

- Persistent storage support to re-initialize the system.

    - **parameters are modified in runtime and cached into persistent volume as well. and next boot or next re-spawn, modified parameters will be loaded at initialization. (parameter lifetime is dependent on use case, sometimes system lifetime, sometimes node lifetime.)**

- Using ROS 1 based application with Parameter Server.

ROS 2 Persistent Parameter Server

Architecture

- ⬤ Global Parameter Server
- ⬤ Global Parameter Client

ROS2 System(DDS Domain)

System#A

System#A Parameter — Global Parameter Server

Node (Client)

Node (Client)

System#B

ROS2 System Parameter (Global)

Global Parameter Server

System#B Parameter — Global Parameter Server

Node (Client)

Node (Client)

System#C

Global Parameter Server — System#C Parameter

Node (Client)

Node (Client)

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Issues and PRs are always welcome 🚀

https://github.com/fujitatomoya/ros2_persist_parameter_server