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.

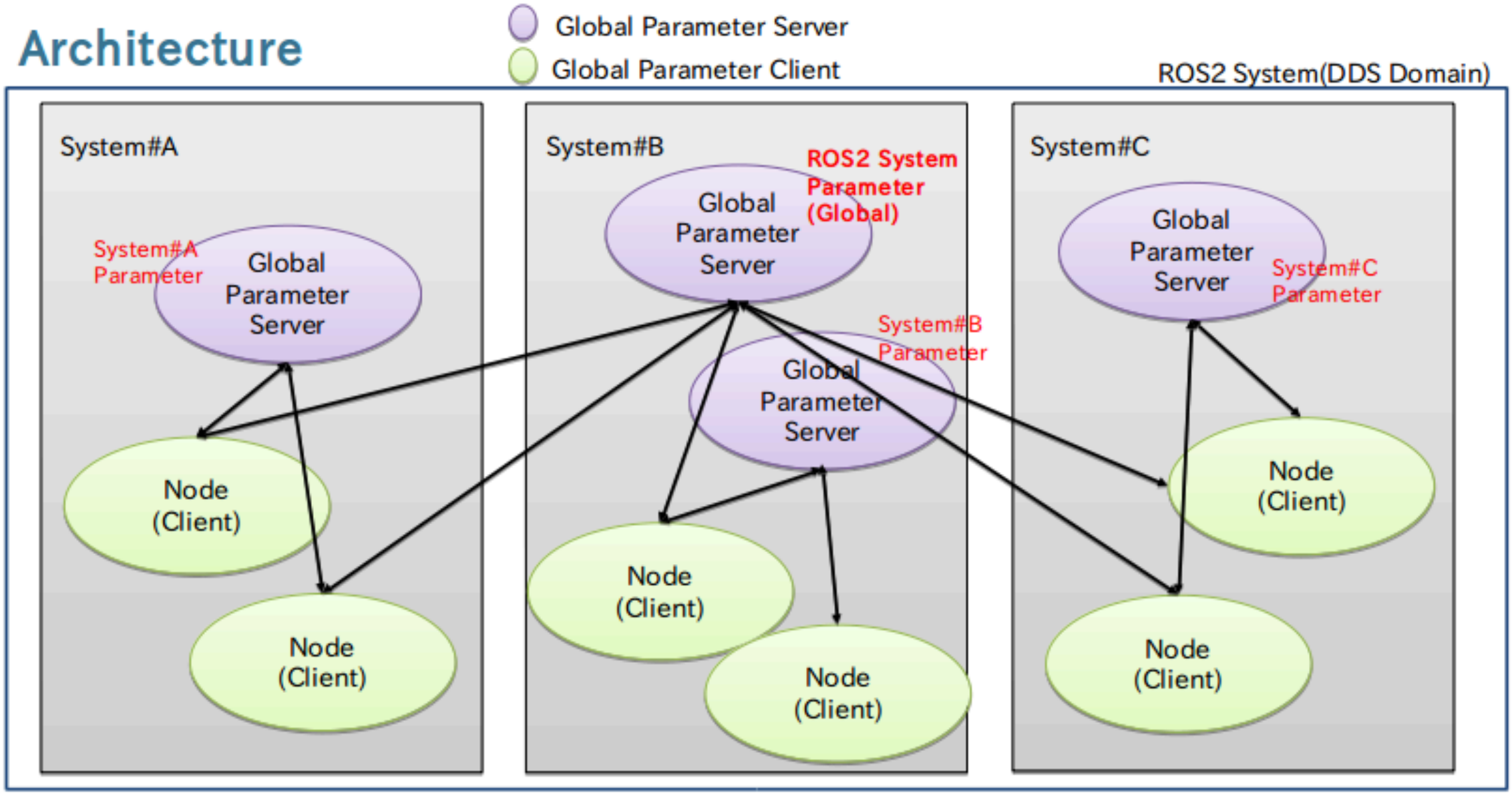
fujitatomoya@github

ROS 2 Persistent Parameter Server

fujitatomoya@github

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.


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)

Issues and PRs are always welcome 🚀

https://github.com/fujitatomoya/ros2_persist_parameter_server

fujitatomoya@github