

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.





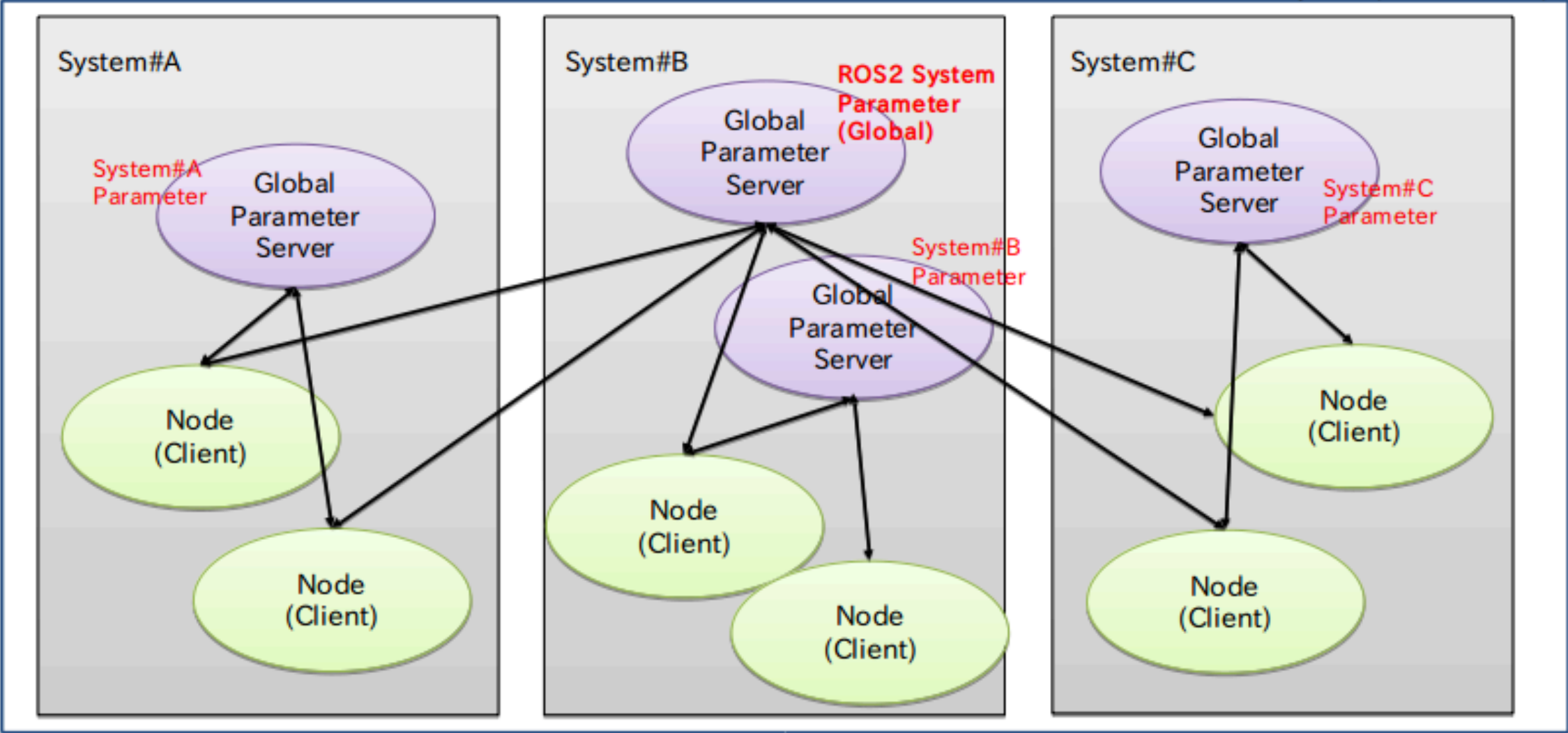
Why we need this?

- 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)



How to Run

- Docker

```
$ docker run -it tomoyafujita/ros2_param_server:rolling /bin/bash  
root@bf4d904e3800:~/colcon_ws# ros2 run parameter_server server
```

- Kubernetes

```
$ kubectl apply -f ./k8s/parameters.yaml  
$ kubectl apply -f ./k8s/deployment.yaml
```



Issues and PRs are always welcome 🚀

https://github.com/fujitatomoya/ros2_persist_parameter_server