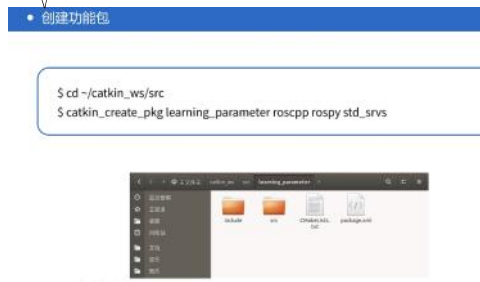


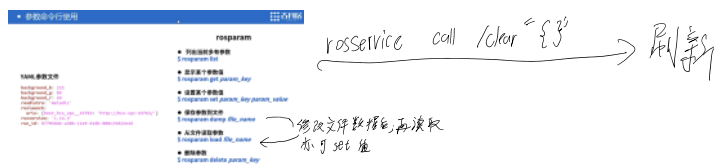
# 参数服务器的使用

2022年11月23日 星期三 19:40

创个包先



以命令行控制 ros param



以 Cpp 控制 ros param



编译他

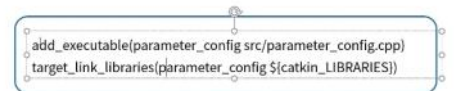
## 配置代码编译规则

```
## declare a C++ executable
## with catkin_make all packages are built within a single catkin context
## The recommended catkin_make approach is to build against a catkin
## target, like 'catkin_make_exe' or 'catkin_make_node'
## Specify libraries to link a library or executable target against
# target_link_libraries(CATKIN_LIBRARIES)
# catkin_libraries
# )

add_executable(parameter_config src/parameter_config.cpp)
target_link_libraries(parameter_config ${catkin_LIBRARIES})
```

如何配置CMakeLists.txt中的编译规则

- 设置需要编译的代码和生成的可执行文件;
- 设置链接库;



CMakeLists.txt

```
$ cd ~/catkin_ws
$ catkin_make
$ source devel/setup.bash
$ roscore
$ roslaunch turtlesim turtlesim_node
$ roslaunch learning_parameter parameter_config
```

```
bash@hcx-vpc1:~$ roslaunch learning_parameter parameter_config
[INFO] [1562816981.090709151]: Get Background Color(09, 06, 255)
[INFO] [1562816981.104602231]: Set Background Color(255, 255, 255)
[INFO] [1562816981.110197845]: Re-get Background Color(255, 255, 255)
```