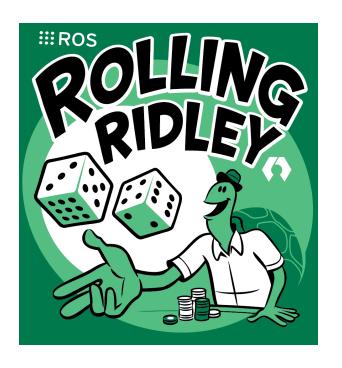
ROS 2 Persistent Parameter Server

- 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.

Global Parameter Server **Architecture** Global Parameter Client ROS2 System(DDS Domain) System#A System#C System#B ROS2 System Parameter Global (Global) Global Parameter System#A Parameter Global Server System#C Parameter Server Parameter Parameter Server System#B Parameter Global Parameter Server Node Node (Client) (Client) Node (Client) Node Node (Client) Node (Client) (Client)



Issues and PRs are always welcome 🚀



https://github.com/fujitatomoya/ros2_persist_param eter_server