

ROS 2

Node configuration

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Recap

Multiple **ROS 2 nodes** can communicate using three different **paradigms**:

- **Topics**: asynchronous, unidirectional communication.
- **Services**: synchronous, bidirectional communication.
- **Actions**: asynchronous, bidirectional communication.

All rely on **messages**, which must be **defined**, and on **QoS policies**.

New code examples are available.

This lecture is [here](#).

Roadmap

1 Namespaces

2 Node parameters

3 Launch files

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Why parameters?

Example: The camera driver node

Suppose you have to integrate an **RGB camera** into your architecture, by writing a ROS 2 node that acts as a **driver**:

- the node uses the necessary libraries to interact with the camera hardware;
- RGB frames are constantly published on some topic;
- during constant operation, you would like to **change some values** to tune image quality, e.g., exposure.

You could **encode** such parameters in your program, or pass them as **command-line arguments**, but this is just the beginning...

Why parameters?

Example: The controller node

Suppose you implemented some **discrete-time control law** in a ROS 2 node:

- subscribers constantly sample sensor measurements, and callbacks embed the control algorithm;
- the control law depends on some **parameters**;
- you would like to change the parameters without having to **recompile** your software each time;
- you would like to have **other modules** to change such parameters automatically if need be, and to **automatically react** to such changes.

... Middleware support is evidently needed.

Node parameters

A ROS 2 node can have one or more **parameters**: values that can be specified at **startup**, changed at **runtime**, and used in the implementation.

The parameter system is **decentralized** and **built on messages and services**: each node has its own parameters and related services, and updates are **broadcasted** to every other node over the `/parameter_events` topic (try to inspect it! Remember to log it too during experiments!).

Parameters can be **listed**, **queried**, **described** and **set**, using either **CLI tools** or **service calls**; **YAML** configuration files may be **loaded** or **dumped**.

It is possible to specify what to do when a parameter update is requested by defining a **callback**.

A parameter may be **read-only** and its type may be **dynamic**.

Parameter types

From the `rcl_interfaces/ParameterType` message file:

- `BOOL`
- `INTEGER`
- `DOUBLE`
- `STRING`
- `BYTE_ARRAY`
- `BOOL_ARRAY`
- `INTEGER_ARRAY`
- `DOUBLE_ARRAY`
- `STRING_ARRAY`

Parameters CLI commands

- `ros2 param list NODE_NAME`
Lists available parameters of a node.
- `ros2 param describe NODE_NAME PARAMETER_NAME`
Shows information about a parameter.
- `ros2 param get NODE_NAME PARAMETER_NAME`
Returns the value of a parameter.
- `ros2 param set NODE_NAME PARAMETER_NAME VALUE`
Sets a given value for a parameter.
- `ros2 param dump NODE_NAME`
Dumps the current parameter configuration in a YAML file.
- `ros2 param load NODE_NAME PARAMETER_FILE`
Loads parameters from a YAML file.

Parameters CLI commands

When starting a node with `ros2 run`, it is possible to specify parameters as **command-line arguments**:

```
ros2 run PACKAGE_NAME EXECUTABLE_NAME --ros2-args -p  
param_name:=param_value ...
```

It is also possible to specify a **configuration file**:

```
ros2 run PACKAGE_NAME EXECUTABLE_NAME --ros2-args --params-file  
PARAMETER_FILE
```

Parameters services

When a node is launched, it **automatically** instantiates the following **services**:

- `~/get_parameters`
- `~/set_parameters`
- `~/list_parameters`
- `~/describe_parameters`
- `~/get_parameter_types`
- `~/set_parameters_atomically`

Try to inspect them with `ros2 service type`! They all take **groups of parameters** on which to operate, and can be called either from a **CLI tool** or from a **client node**: that is the way to go if you want to **automate parameter updates**.

Coding with parameters

Hints and best practices

- Parameters are referred to by their **name**.
- Before being used, a parameter must be **declared** to the middleware: this is usually done in the constructor of a node specifying their **name** and **default value**.
- Parameter values can be retrieved **atomically** by calling an API, but accessing the middleware's internals to do this might be **slow**: define **class member variables** that track the value of each parameter by being updated each time the parameter is.

Coding with parameters

Suggested TODO list

- ➊ Define **class member variables** to track the value of each parameter.
- ➋ Define a **callback** to be called when a parameter is updated.
- ➌ **Declare** the parameters in the **constructor** of the node; do this **first**, so that the parameters are available as soon as the node is started.
- ➍ **Register** the callback to the middleware.
- ➎ **Use** the parameter values in the implementation.

Coding with parameters

About declarations

There are **two APIs**, corresponding to **two ways** to declare parameters:

- ① the **lazy way**: `declare_parameter(...)` specifying **only the name and the default value** of the parameter;
- ② the **complete way**: `declare_parameter(...)` specifying **all the information** about the parameter, including its **type**, **description**, **read-only** flag, **max** and **min** values, **constraints** and more, using a `rcl_interfaces::msg::ParameterDescriptor` object.

The complete way is **recommended**, but induces a lot of **boilerplate code**!

Check out our [params_manager](#) library!

Example: Parametric publisher

Now go have a look at the [ros2-examples/src/cpp/parameters_example_cpp](https://github.com/ros2-examples/src/cpp/parameters_example_cpp) package!

Roadmap

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Scripting ROS 2 Architectures

A ROS 2-based control architecture for a robot can easily get to have 20 nodes or more.

It then becomes critical to be able to **automate startup and configuration** of all the modules, or some subsets, also for testing.

That is what the ROS 2 **Launch System** is for.

Launch Files

Launch files are **Python scripts** that specify how ROS 2 modules must be **located**, **configured** and **started**. Their format is such that the Launch System can parse and integrate them when invoked.

Many things can be configured about modules in such files:

- console and text files **logs**;
- command line **arguments**;
- node **parameters**;
- **remappings**.

Targeted modules may even not be ROS 2 nodes.

Launch files may be **included**, so that large architectures can be started with single commands.

Launch Files

```
1 from launch import LaunchDescription
2 from launch_ros.actions import Node
3
4 # The following function MUST be specified
5
6 """Builds a launch description."""
7 def generate_launch_description():
8     ld = LaunchDescription()
9     node = Node(
10         package='PACKAGE_NAME',
11         executable='EXECUTABLE_NAME',
12     )
13     ld.add_action(node)
14     return ld
```

Listing 1: Minimal example of a launch file

Launch Files Best Practices

- Their extension is usually `.launch.py`.
- They are usually placed in a directory named `launch` that is installed in the workspace path during build.
- A module can have its own launch files but those for the entire architecture must form an appropriate package, whose name is usually `PROJECT_bringup`.

A comprehensive description of all the features of launch files can be found in [launch_files.md](#).

Example: Bringup Package

Now go have a look at the [ros2-examples/src/ros2_examples_bringup](https://github.com/ros2/examples/tree/main/src/ros2_examples/bringup) package!