~/ros2_ws3/src/talkerlistener/talkerlistener/talker.py

```python
import rclpy
from rclpy.node import Node
from std_msgs.msg import String

class TalkerNode(Node):
    def __init__(self):
        super().__init__('talker')
        self.publisher_ = self.create_publisher(String, 'chatter', 10)
        self.timer_ = self.create_timer(1.0, self.publish_message)
        self.declare_parameter('message', 'Hello from ROS 2!')

    def publish_message(self):
        msg = String()
        msg.data = self.get_parameter('message').get_parameter_value().string_value
        self.publisher_.publish(msg)
        self.get_logger().info(f'Published: "{msg.data}"')

def main(args=None):
    rclpy.init(args=args)
    node = TalkerNode()
    rclpy.spin(node)
    node.destroy_node()
    rclpy.shutdown()
```