ROS2 Publisher C++ Cheat Sheet

Using RCL Node Class

```cpp
#include "rclcpp/rclcpp.hpp"

class YourNodeClassName : public rclcpp::Node
    {
      public:
        YourNodeClassName() : Node("name_of_node"){...}
      private:
        ...
    };

int main(int argc, char * argv[])
    {
        rclcpp::init(argc, argv);
        rclcpp::spin(std::make_shared<YourNodeClassName>());
        rclcpp::shutdown();

        return 0;
    }
```

Creating And Using Publishers

```cpp
#include "std_msgs/msg/string.hpp"

rclcpp::Publisher<std_msgs::msg::String>::SharedPtr publisher_;
publisher_ =
    this->create_publisher<std_msgs::msg::String>("topic_name", 10);

auto message = std_msgs::msg::String();
message.data = "My String Message Data"
publisher_->publish(message);
```