#!/usr/bin/env python3

import rclpy

from rclpy.node import Node

from std\_msgs.msg import Int32

class publisher(Node):

def \_\_init\_\_(self):

super().\_\_init\_\_("Publsiher")

self.get\_logger().info("Hello from ROS2, Node is Started")

# self.counter = 0

self.publisher\_ = self.create\_publisher(Int32,"/message",10)

self.timer\_ = self.create\_timer(1.0,self.timer\_callback)

def timer\_callback(self):

msg = Int32()

msg.data = 8 #"Hello " + str(self.counter)

#self.get\_logger().info(msg.data)

self.publisher\_.publish(msg)

# self.counter+=1

def main(args=None):

rclpy.init(args=args)

node = publisher()

rclpy.spin(node)

rclpy.shutdown()

if \_\_name\_\_=="\_\_main\_\_":

main()