map Broadcaster: /amcl Average rate: 5.208 Hz Most recent transform: 29308.980 (0.070 sec old) Buffer length: 4.800 sec odom Broadcaster: /gazebo Average rate: 10.204 Hz Most recent transform: 29309.020 (0.030 sec old) Buffer length: 4.900 sec base_link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (29309.050 sec old) Buffer length: 0.000 sec body_link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: $1\overline{0000.000}$ Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 50.000 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 50.000 Hz Average rate: 50.000 Hz Average rate: 50.000 Hz Most recent transform: 0.000 (29309.050 sec old) / Most recent transform: 0.000 (29309.050 sec old) / Most recent transform: 29309.030 (0.020 sec old) Most recent transform: 0.000 (29309.050 sec old) Most recent transform: 0.000 (29309.050 sec old) / Most recent transform: 0.000 (29309.050 sec old) Most recent transform: 0.000 (29309.050 sec old) Most recent transform: 0.000 (29309.050 sec old) Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec camera_link range_fr rear_left_wheel range_fl range_rl range_rr front_left_wheel front_right_wheel rear_right_wheel laser Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (29309.050 sec old) \ Most recent transform: 0.000 (29309.050 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec camera_rgb_frame camera_depth_frame

view_frames Result

Recorded at time: 29309.050