view_frames Result Recorded at time: 1575.069 Broadcaster: /map_odom_broadcaster Average rate: 10.258 Hz Most recent transform: 1575.167 (-0.098 sec old) Buffer length: 3.412 sec odom Broadcaster: /gazebo Average rate: 10.294 Hz Most recent transform: 1575.047 (0.022 sec old) Buffer length: 3.400 sec robot_footprint Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1575.069 sec old) Buffer length: 0.000 sec chassis Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 10.288 Hz Average rate: 10.288 Hz Average rate: 10.288 Hz Most recent transform: 0.000 (1575.069 sec old) Most recent transform: 0.000 (1575.069 sec old) Most recent transform: 1575.050 (0.019 sec old) Most recent transform: 1575.050 (0.019 sec old) Most recent transform: 1575.050 (0.019 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 3.402 sec Buffer length: 3.402 sec Buffer length: 3.402 sec LiDAR_mount left_wheel hokuyo right_wheel camera