view\_frames Result Recorded at time: 1590.041 Broadcaster: /map\_odom\_broadcaster Average rate: 10.228 Hz Most recent transform: 1590.134 (-0.093 sec old) Buffer length: 3.422 sec odom Broadcaster: /gazebo Average rate: 10.303 Hz Most recent transform: 1589.947 (0.094 sec old) Buffer length: 3.300 sec robot\_footprint Broadcaster: /robot\_state\_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1590.041 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: 10.297 Hz Average rate: 10.297 Hz Average rate: 10.297 Hz Most recent transform: 0.000 (1590.041 sec old) Most recent transform: 0.000 (1590.041 sec old) Most recent transform: 1589.951 (0.090 sec old) Most recent transform: 1589.951 (0.090 sec old) Most recent transform: 1589.951 (0.090 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 3.302 sec Buffer length: 3.302 sec Buffer length: 3.302 sec LiDAR\_mount left\_wheel hokuyo right\_wheel camera