```
view_frames Result

Recorded at time: 708.243
```

map

Broadcaster: /rtabmap/rtabmap
Average rate: 20.208 Hz
Most recent transform: 708.302 (-0.059 sec old)
Buffer length: 4.899 sec

odom

Broadcaster: /gazebo
Average rate: 10.208 Hz
Most recent transform: 708.145 (0.098 sec old)
Buffer length: 4.800 sec

robot_footprint

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (708.243 sec old)
Buffer length: 0.000 sec

chassis

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (708.243 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (708.243 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 10.208 Hz
Most recent transform: 708.165 (0.078 sec old)
Buffer length: 4.800 sec

Broadcaster: /robot_state_publisher
Average rate: 10.208 Hz
Most recent transform: 708.165 (0.078 sec old)
Buffer length: 4.800 sec

camera_rgb

hokuyo

left_wheel

right_wheel

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (708.243 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (708.243 sec old)
Buffer length: 0.000 sec

camera_depth

camera_rgb_optical_frame

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (708.243 sec old)
Buffer length: 0.000 sec

camera_depth_optical_frame