view_frames Result

Recorded at time: 766.774

world

Broadcaster: /world_to_map_broadcaster
Average rate: 10000.000 Hz
Most recent transform: 0.000 (766.774 sec old)
Buffer length: 0.000 sec

map

Broadcaster: /amcl
Average rate: 40.268 Hz
Most recent transform: 766.868 (-0.094 sec old)
Buffer length: 2.384 sec

odom

Broadcaster: /gazebo
Average rate: 100.420 Hz
Most recent transform: 766.767 (0.007 sec old)
Buffer length: 2.380 sec

base_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (766.774 sec old)
Buffer length: 0.000 sec

Broadcaster: /base_link_to_base_realsense_broadcaster
Average rate: 10000.000 Hz
Most recent transform: 0.000 (766.774 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 10.435 Hz
Most recent transform: 766.698 (0.076 sec old)
Buffer length: 2.300 sec

Broadcaster: /robot_state_publisher
Average rate: 10.435 Hz
Most recent transform: 766.698 (0.076 sec old)
Buffer length: 2.300 sec

base_rplidar

base_realsense

left_wheel

right_wheel

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (766.774 sec old)
Buffer length: 0.000 sec

Broadcaster: /base_realsense_to_camera_link_broadcaster
Average rate: 10000.000 Hz
Most recent transform: 0.000 (766.774 sec old)
Buffer length: 0.000 sec

scan

camera_link

Broadcaster: /map_nav_broadcaster
Average rate: 10000.000 Hz
Most recent transform: 0.000 (766.774 sec old)
Buffer length: 0.000 sec

laser