view frames Result Recorded at time: 1651423572.022 map Broadcaster: /hector mapping Broadcaster: /hector mapping Average rate: 12.916 Hz
Most recent transform: 1651423571.693 (0.329 sec old) Average rate: 12.916 Hz Most recent transform: 1651423571.693 (0.329 sec old) Buffer length: 5.032 sec Buffer length: 5.032 sec odom scanmatcher frame Broadcaster: /diff tf Average rate: 10.209 Hz Most recent transform: 1651423571.978 (0.044 sec old) Buffer length: 4.800 sec base_link Broadcaster: /base link to camera Average rate: 10.185 Hz Most recent transform: 1651423572.118 (-0.096 sec old) Buffer length: 4.909 sec camera link Broadcaster: /camera/realsense2 camera manager Broadcaster: /camera/realsense2 camera manager Broadcaster: /camera/realsense2 camera manager Average rate: $10000.\overline{0}00$ Hz Average rate: $10000.\overline{0}00$ Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (1651423572.022 sec old) Most recent transform: 0.000 (1651423572.022 sec old) Most recent transform: 0.000 (1651423572.022 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec camera aligned depth to color frame camera depth frame camera color frame Broadcaster: /camera/realsense2 camera manager Broadcaster: /camera/realsense2 camera manager Average rate: 10000.000 Hz Average rate: $10000.\overline{0}00$ Hz Most recent transform: 0.000 (1651423572.022 sec old) Most recent transform: 0.000 (1651423572.022 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec $camera_color_optical_frame$ camera depth optical frame Broadcaster: /apriltag ros continuous node Average rate: 3.922 Hz Most recent transform: 1651423571.693 (0.329 sec old) Buffer length: 5.099 sec dock