

view_frames Result
Recorded at time: 266.895

map

odom

Broadcaster: /camera_init_to_map
Average rate: 10000.000 Hz
Most recent transform: 1663744484.265 (-1663744217.370 sec old)
Buffer length: 0.000 sec

camera_init

Broadcaster: /lego_loam_bor
Average rate: 11.236 Hz
Most recent transform: 266.890 (0.005 sec old)
Buffer length: 0.623 sec

Broadcaster: /lego_loam_bor
Average rate: 11.673 Hz
Most recent transform: 436.288 (-169.393 sec old)
Buffer length: 0.600 sec

Broadcaster: /lego_loam_bor
Average rate: 3.643 Hz
Most recent transform: 266.827 (0.068 sec old)
Buffer length: 0.549 sec

camera

laser_odom

aft_mapped

Broadcaster: /base_link_to_camera
Average rate: 10000.000 Hz
Most recent transform: 1663744484.265 (-1663744217.370 sec old)
Buffer length: 0.000 sec

base_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

base_footprint

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

front_bumper_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

imu_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

inertial_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

rear_bumper_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

top_chassis_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

top_plate_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

top_plate_front_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

top_plate_rear_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

user_rail_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (266.895 sec old)
Buffer length: 0.000 sec

front_left_wheel_link

Broadcaster: /robot_state_publisher
Average rate: 51.613 Hz
Most recent transform: 266.876 (0.019 sec old)
Buffer length: 0.620 sec

front_right_wheel_link

Broadcaster: /robot_state_publisher
Average rate: 51.613 Hz
Most recent transform: 266.876 (0.019 sec old)
Buffer length: 0.620 sec

rear_left_wheel_link

Broadcaster: /robot_state_publisher
Average rate: 51.613 Hz
Most recent transform: 266.876 (0.019 sec old)
Buffer length: 0.620 sec

rear_right_wheel_link

Broadcaster: /husky_to_base_link
Average rate: 11.647 Hz
Most recent transform: 266.957 (-0.062 sec old)
Buffer length: 0.601 sec

husky

Broadcaster: /wld_ori_to_husky
Average rate: 10000.000 Hz
Most recent transform: 1663744484.265 (-1663744217.370 sec old)
Buffer length: 0.000 sec

wld_ori

Broadcaster: /basler_to_wld_ori
Average rate: 10000.000 Hz
Most recent transform: 1663744484.265 (-1663744217.370 sec old)
Buffer length: 0.000 sec

basler