view frames Result Recorded at time: 328.417 pioneer2dx_ros/odom base_link pioneer3at_ros/odom my_arm_robot/odom centaur_ros/odom Broadcaster: /static_transform_publisher_1499568953910012240 Broadcaster: /pioneer3at_ros/tf_static_odom_base Broadcaster: /my_arm_robot/tf_static_odom_base Broadcaster: /pioneer2dx_ros/tf_static_odom_base Average rate: 10.211 Hz Average rate: 20.200 Hz Average rate: 10.191 Hz Average rate: 10.218 Hz Most recent transform: 328.515 (-0.098 sec old) Most recent transform: 328.428 (-0.011 sec old) Most recent transform: 328.509 (-0.092 sec old) Most recent transform: 328.478 (-0.061 sec old) Buffer length: 4.514 sec Buffer length: 4.603 sec Buffer length: 4.604 sec Buffer length: 4.502 sec my_arm_robot/base_link pioneer2dx_ros/base_link centaur_ros/base_link pioneer3at_ros/base_link Broadcaster: /centaur_ros/robot_state_publisher Broadcaster: /centaur_ros/robot_state_publisher Broadcaster: /centaur_ros/robot_state_publisher Broadcaster: /centaur_ros/tf_static_base2pelvis Broadcaster: /centaur_ros/robot_state_publisher Average rate: 15.800 Hz Average rate: 24.691 Hz Average rate: 24.691 Hz Average rate: 10.206 Hz Average rate: 7.977 Hz Most recent transform: 328.366 (0.051 sec old) Most recent transform: 328.369 (0.048 sec old) Most recent transform: 328.369 (0.048 sec old) Most recent transform: 328.445 (-0.028 sec old) Most recent transform: 328.135 (0.282 sec old) Buffer length: 4.557 sec Buffer length: 4.536 sec Buffer length: 4.536 sec Buffer length: 4.507 sec Buffer length: 4.137 sec centaur_ros/cameraYawServo centaur_ros/left_front_flipper_base_link centaur_ros/left_rear_flipper_base_link centaur_ros/pelvis centaur_ros/laser1RollServo Broadcaster: /centaur_ros/robot_state_publisher Broadcaster: /centaur ros/robot state publisher Broadcaster: /centaur_ros/robot_state_publisher Average rate: 15.800 Hz Average rate: 24.691 Hz Average rate: 7.977 Hz Most recent transform: 328.369 (0.048 sec old) Most recent 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