view_frames Result

Recorded at time: 1752441315.3093424

all

Broadcaster: default_authority
Average rate: 10000.0
Buffer length: 0.0
Most recent transform: 0.0
Oldest transform: 0.0

Broadcaster: default_authority
Average rate: 10000.0
Buffer length: 0.0
Most recent transform: 0.0
Oldest transform: 0.0

robot_1/map

robot_0/map

Broadcaster: default_authority
Average rate: 200.201
Buffer length: 5.01
Most recent transform: 1752441315.284927
Oldest transform: 1752441310.274971

Broadcaster: default_authority
Average rate: 200.137
Buffer length: 5.017
Most recent transform: 1752441315.292549
Oldest transform: 1752441310.275977

Broadcaster: default_authority
Average rate: 200.199
Buffer length: 5.01
Most recent transform: 1752441315.288797
Oldest transform: 1752441310.278778

Broadcaster: default_authority
Average rate: 199.802
Buffer length: 5.01
Most recent transform: 1752441315.28646
Oldest transform: 1752441310.276494

robot_1/odom

robot_1/base_link_imu

robot_0/odom

robot_0/base_link_imu

Broadcaster: default_authority
Average rate: 200.137
Buffer length: 5.017
Most recent transform: 1752441315.292501
Oldest transform: 1752441310.275937

Broadcaster: default_authority
Average rate: 199.808
Buffer length: 5.01
Most recent transform: 1752441315.286271
Oldest transform: 1752441310.276461

robot_1/base_link

robot_0/base_link

Broadcaster: default_authority
Average rate: 10000.0
Buffer length: 0.0
Most recent transform: 0.0
Oldest transform: 0.0

Broadcaster: default_authority
Average rate: 10000.0
Buffer length: 0.0
Most recent transform: 0.0
Oldest transform: 0.0

Broadcaster: default_authority
Average rate: 10000.0
Buffer length: 0.0
Most recent transform: 0.0
Oldest transform: 0.0

Broadcaster: default_authority
Average rate: 10000.0
Buffer length: 0.0
Most recent transform: 0.0
Oldest transform: 0.0

Broadcaster: default_authority
Average rate: 10000.0
Buffer length: 0.0
Most recent transform: 0.0
Oldest transform: 0.0

Broadcaster: default_authority
Average rate: 10000.0
Buffer length: 0.0
Most recent transform: 0.0
Oldest transform: 0.0

robot_1/lidar_link

robot_1/camera_link

robot_1/base_footprint

robot_0/lidar_link

robot_0/camera_link

robot_0/base_footprint