

view_frames Result
Recorded at time: 1880.600

odom

Broadcaster: /ekf_localization
Average rate: 50.405 Hz
Most recent transform: 1880.580 (0.020 sec old)
Buffer length: 4.940 sec

base_link

base_footprint

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

robot_base

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

front_bumper_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

imu_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

inertial_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

rear_bumper_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

top_chassis_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

top_plate_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 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 (1880.600 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 (1880.600 sec old)
Buffer length: 0.000 sec

user_rail_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

front_left_wheel_link

Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 1880.570 (0.030 sec old)
Buffer length: 4.940 sec

front_right_wheel_link

Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 1880.570 (0.030 sec old)
Buffer length: 4.940 sec

rear_left_wheel_link

Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 1880.570 (0.030 sec old)
Buffer length: 4.940 sec

rear_right_wheel_link

Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 1880.570 (0.030 sec old)
Buffer length: 4.940 sec

camera_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

lidar_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

robot_base_link

Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 1880.570 (0.030 sec old)
Buffer length: 4.940 sec

shoulder_link

Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 1880.570 (0.030 sec old)
Buffer length: 4.940 sec

elbow_link

Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 1880.570 (0.030 sec old)
Buffer length: 4.940 sec

wrist_link

Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 1880.570 (0.030 sec old)
Buffer length: 4.940 sec

gripper_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

camera_link_optical

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1880.600 sec old)
Buffer length: 0.000 sec

ar_marker_0

Broadcaster: /ar_track_alvar
Average rate: 8.247 Hz
Most recent transform: 1880.520 (0.080 sec old)
Buffer length: 4.850 sec