view_frames Result Recorded at time: 1695612936.220 base_footprint map Broadcaster: /robot_state_publisher Broadcaster: /rtabmap/rtabmap Average rate: 10000.000 Hz Average rate: 20.204 Hz Buffer length: 0.000 sec Buffer length: 4.900 sec robot_base odom Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 0.000 (1695612936.220 sec old) / Most recent transform: 1695612936.207 (0.013 sec old) Most recent transform: 1695612936.207 (0.013 sec old) \ Most recent transform: 1695612936.207 (0.013 sec old) Most recent transform: 1695612936.207 (0.013 sec old) Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec front_left_steering_link rbot_base2 front_right_steering_link rear_left_steering_link rear_right_steering_link Broadcaster: /robot_state_publisher Broadcaster: /robot state publisher Broadcaster: /robot state publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 1695612936.207 (0.013 sec old) Most recent transform: 0.000 (1695612936.220 sec old) Most recent transform: 0.000 (1695612936.220 sec old) Most recent transform: 1695612936.207 (0.013 sec old) Most recent transform: 1695612936.207 (0.013 sec old) Most recent transform: 1695612936.207 (0.013 sec old) Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec ffr_wheel_link imu_link servo_bottom2 ffl_wheel_link rfl_wheel_link rfr_wheel_link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1695612936.220 sec old) Buffer length: 0.000 sec up_mount2 Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1695612936.220 sec old) Buffer length: 0.000 sec base_link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1695612936.220 sec old) Buffer length: 0.000 sec camera_bottom_screw_frame Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1695612936.220 sec old) Buffer length: 0.000 sec camera_link Broadcaster: /robot_state_publisher Broadcaster: /camera/realsense2_camera_manager Broadcaster: /camera/realsense2_camera_manager Broadcaster: /camera/realsense2_camera_manager Broadcaster: /camera/realsense2_camera_manager Broadcaster: /robot_state_publisher Broadcaster: /camera/realsense2 camera manager Average rate: 10000.000 Hz Most recent transform: 0.000 (1695612936.220 sec old) \ Most recent transform: 0.000 (1695612936.220 sec old) Most recent transform: 0.000 (1695612936.220 sec old) Most recent transform: 0.000 (1695612936.220 sec old) Buffer length: 0.000 sec camera_accel_frame camera_depth_frame camera_aligned_depth_to_color_frame camera_infra1_frame camera_infra2_frame camera_color_frame camera_gyro_frame Broadcaster: /camera/realsense2_camera_manager Broadcaster: /camera/realsense2_camera_manager Broadcaster: /camera/realsense2_camera_manager Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /camera/realsense2_camera_manager Average rate: 10000.000 Hz Most recent transform: 0.000 (1695612936.220 sec old) Buffer length: 0.000 sec camera_imu_optical_frame camera_color_optical_frame camera_depth_optical_frame camera_infra1_optical_frame camera_infra2_optical_frame camera_accel_optical_frame