To **compare the message rates** of `/scan` and `/odom`, we analyze the number of messages published over the duration of the rosbag.

Basic Information

- **Bag Duration:** 199.7 seconds (approx)
- **Message Counts:**
    - `/odom`: 5,794 messages
    - `/scan`: 984 messages

Calculated Message Rates

Topic	Message Count	Duration (s)	Rate (Hz)
`/odom`	5,794	199.7	≈ **29.0 Hz**
`/scan`	984	199.7	≈ **4.9 Hz**

In conclusion, the `/odom` topic publishes approximately **6 times faster** than `/scan`. This makes sense because odometry is used for continuous motion estimation, while LIDAR scans are more computationally expensive and need less frequent updates.