view frames Result Recorded at time: 1718106323.284053 map Broadcaster: /slam_gmapping Average rate: 20.204 Buffer length: 4.95 Most recent transform: 1718106323.304 Oldest transform: 1718106318.354 odom Broadcaster: /rf2o_laser_odometry Average rate: $6.1\overline{8}7$ Buffer length: 4.849 Most recent transform: 1718106323.183 Oldest transform: 1718106318.335 base_footprint Broadcaster: /robot_state_publisher Average rate: $1000\overline{0}.0$ Buffer length: 0.0 Most recent transform: 0.0 Oldest transform: 0.0 base 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: 10000.0 Average rate: $1000\overline{0}.0$ Average rate: $10.\overline{206}$ Average rate: $10.\overline{206}$ Average rate: $10.\overline{206}$ Average rate: $10.\overline{206}$ Buffer length: 4.899 Buffer length: 0.0 Buffer length: 0.0 Buffer length: 4.899 Buffer length: 4.899 Buffer length: 4.899 Most recent transform: 1718106323.264 Most recent transform: 0.0 Most recent transform: 1718106323.264 Most recent transform: 1718106323.264 Most recent transform: 0.0 Most recent transform: 1718106323.264 Oldest transform: 0.0 Oldest transform: 0.0 Oldest transform: 1718106318.365 Oldest transform: 1718106318.365 Oldest transform: 1718106318.365 Oldest transform: 1718106318.365 back_wheel front_wheel right_wheel left_wheel support camera Broadcaster: /robot state publisher Average rate: $1000\overline{0}.0$ Buffer length: 0.0 Most recent transform: 0.0 Oldest transform: 0.0 velodyne_base_link Broadcaster: /robot_state_publisher Average rate: $1000\overline{0}.0$ Buffer length: 0.0 Most recent transform: 0.0 Oldest transform: 0.0 velodyne Broadcaster: /static_transform_publisher Average rate: $10000.\overline{0}$ Buffer length: 0.0 Most recent transform: 0.0 Oldest transform: 0.0 PandarQT