view frames Result Recorded at time: 997.211 lidar_with_mirror_centor_link odom Broadcaster: /ekf localization node Broadcaster: /fitting Average rate: 40.260 Hz
Most recent transform: 997.201 (0.010 sec old) Average rate: 10.464 Hz Most recent transform: 997.166 (0.045 sec old) Buffer length: 2.198 sec Buffer length: 2.310 sec base link measurement_plane Broadcaster: /orne box/robot state publisher Broadcaster: /orne box/robot state publisher Broadcaster: /orne box/robot state publisher Broadcaster: /robot state publisher Broadcaster: /orne box/robot state publisher Broadcaster: /orne box/robot state publisher Broadcaster: /robot state publisher Average rate: 10.455 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 10.455 Hz Average rate: 10000.000 Hz Average rate: 60.345 Hz Average rate: 60.345 Hz Most recent transform: 0.000 (997.211 sec old) Most recent transform: 0.000 (997.211 sec old) Most recent transform: 0.000 (997.211 sec old) Most recent transform: 997.202 (0.009 sec old) \Most recent transform: 997.202 (0.009 sec old) \Most recent transform: 997.173 (0.038 sec old) Most recent transform: 997.173 (0.038 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 2.320 sec Buffer length: 2.320 sec Buffer length: 2.200 sec Buffer length: 2.200 sec wheel_left_link left_caster_swivel_link right_caster_swivel_link imu_link wheel_right_link hokuyo_link lidar with mirror prismatic link Broadcaster: /robot_state_publisher Average rate: 10.455 Hz Broadcaster: /orne box/robot state publisher Broadcaster: /robot state publisher Average rate: 10.455 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (997.211 sec old) Most recent transform: 997.173 (0.038 sec old) Most recent transform: 997.173 (0.038 sec old) Buffer length: 2.200 sec Buffer length: 2.200 sec Buffer length: 0.000 sec right_caster_wheel_link lidar with mirror pitch link left caster wheel link Broadcaster: /orne box/robot state publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (997.211 sec old) Buffer length: 0.000 sec lidar_with_mirror_roll_link Broadcaster: /orne box/robot state publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (997.211 sec old) Buffer length: 0.000 sec lidar_with_mirror_center_link Broadcaster: /orne box/robot state publisher Broadcaster: /orne box/robot state publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (997.211 sec old) \Most recent transform: 0.000 (997.211 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec

Broadcaster: /orne_box/robot_state_publisher
 Average rate: 10000.000 Hz

Most recent transform: 0.000 (997.211 sec old)
 Buffer length: 0.000 sec

| Buffer length: 0.000 sec | Buffer length: 0.000 sec | Buffer link | Broadcaster: /orne_box/robot_state_publisher
 Average rate: 10000.000 Hz

Most recent transform: 0.000 (997.211 sec old)
 Buffer length: 0.000 sec | Buffer length: 0.000 sec | Buffer link | Broadcaster: /orne_box/robot_state_publisher
 Average rate: 10000.000 Hz

lidar_with_mirror_mirror2_roll_link

lidar_with_mirror_mirror1_roll_link