view\_frames Result Recorded at time: 41.259 map Broadcaster: /rtabmap/rtabmap Average rate: 20.225 Hz Most recent transform: 41.326 (-0.067 sec old) Buffer length: 4.351 sec odom Broadcaster: /gazebo Average rate: 10.230 Hz Most recent transform: 41.202 (0.057 sec old) Buffer length: 4.301 sec robot\_footprint Broadcaster: /robot\_state\_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (41.259 sec old) Buffer length: 0.000 sec chassis Broadcaster: /robot\_state\_publisher Broadcaster: /robot\_state\_publisher Broadcaster: /robot\_state\_publisher Average rate: 10000.000 Hz Average rate: 10.233 Hz Average rate: 10.233 Hz Most recent transform: 0.000 (41.259 sec old) Most recent transform: 41.200 (0.059 sec old) Most recent transform: 0.000 (41.259 sec old) Most recent transform: 41.200 ( 0.059 sec old) Buffer length: 0.000 sec Buffer length: 4.300 sec Buffer length: 4.300 sec right\_wheel left\_wheel sensor\_base Broadcaster: /robot\_state\_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (41.259 sec old) Most recent transform: 0.000 (41.259 sec old) Buffer length: 0.000 sec

Broadcaster: /robot\_state\_publisher

Average rate: 10000.000 Hz

Buffer length: 0.000 sec

Broadcaster: /robot\_state\_publisher

Average rate: 10000.000 Hz

Buffer length: 0.000 sec

hokuyo

RGBD\_camera

Depth\_sensor