view\_frames Result Recorded at time: 39.808 map Broadcaster: /rtabmap/rtabmap Average rate: 20.339 Hz Most recent transform: 39.907 (-0.099 sec old) Buffer length: 2.950 sec odom Broadcaster: /gazebo Average rate: 10.341 Hz Most recent transform: 39.801 ( 0.007 sec old) Buffer length: 2.901 sec robot\_footprint Broadcaster: /robot\_state\_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (39.808 sec old) Buffer length: 0.000 sec chassis 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: 10.345 Hz Average rate: 10.345 Hz Most recent transform: 0.000 (39.808 sec old) Most recent transform: 0.000 (39.808 sec old) Most recent transform: 39.800 (0.008 sec old) Most recent transform: 39.800 ( 0.008 sec old) Buffer length: 0.000 sec Buffer length: 2.900 sec Buffer length: 0.000 sec Buffer length: 2.900 sec camera\_link left\_wheel hokuyo right\_wheel Broadcaster: /robot\_state\_publisher Average rate: 10000.000 Hz Broadcaster: /robot\_state\_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (39.808 sec old) Most recent transform: 0.000 (39.808 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec camera\_depth\_frame camera\_rgb\_frame Broadcaster: /robot\_state\_publisher Broadcaster: /robot\_state\_publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (39.808 sec old) Most recent transform: 0.000 (39.808 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec camera\_depth\_optical\_frame camera\_rgb\_optical\_frame