Recorded at time: 491.827 map Broadcaster: /map to odom Average rate: $3\overline{0}.4\overline{2}5$ Buffer length: 4.963 Most recent transform: 491.854 Oldest transform: 486.891 odom Broadcaster: /gazebo Average rate: 20.216 Buffer length: 4.897 Most recent transform: 491.79 Oldest transform: 486.893 base footprint Broadcaster: /robot state publisher Broadcaster: /base to laser broadcaster Average rate: $1000\overline{0}.0$ Average rate: 10000.0 Buffer length: 0.0 Buffer length: 0.0 Most recent transform: 0.0 Most recent transform: 0.0 Oldest transform: 0.0 Oldest transform: 0.0 base link scan link Broadcaster: /robot state publisher Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: $20.\overline{569}$ Average rate: $20.\overline{569}$ Average rate: $1000\overline{0}.0$ Buffer length: 4.959 Buffer length: 4.959 Buffer length: 0.0 Most recent transform: 0.0 Most recent transform: 491.803 Most recent transform: 491.803 Oldest transform: 486.844 Oldest transform: 486.844 Oldest transform: 0.0 right_wheel left_wheel chassis Broadcaster: /robot_state_publisher | Broadcaster: /robot_state_publisher Broadcaster: /robot state publisher Average rate: 10000.0 Average rate: $1000\overline{0}.0$ Average rate: $1000\overline{0}.0$ Buffer length: 0.0 Buffer length: 0.0 Buffer length: 0.0 Most recent transform: 0.0 Most recent transform: 0.0 Most recent transform: 0.0 Oldest transform: 0.0 Oldest transform: 0.0 Oldest transform: 0.0 caster_wheel $face_link$ camera link Broadcaster: /robot state publisher Average rate: $1000\overline{0}.0$ Buffer length: 0.0 Most recent transform: 0.0 Oldest transform: 0.0 camera link optical

view frames Result