view frames Result Recorded at time: 20.238 map Broadcaster: /map to odom Average rate:  $3\overline{0}.1\overline{1}9$ Buffer length: 4.947 Most recent transform: 20.224 Oldest transform: 15.277 odom Broadcaster: /gazebo Average rate: 20.212 Buffer length: 4.898 Most recent transform: 20.191 Oldest transform: 15.293 base footprint Broadcaster: /robot state publisher Broadcaster: /base to laser broadcaster Average rate: 10000.0 Average rate:  $1000\overline{0}.0$ 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 scan\_link base link Broadcaster: /robot state publisher Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate:  $1000\overline{0}.0$ Average rate: 20.716 Average rate: 20.716 Buffer length: 4.972 Buffer length: 0.0 Buffer length: 4.972 Most recent transform: 0.0 Most recent transform: 20.202 Most recent transform: 20.202 Oldest transform: 0.0 Oldest transform: 15.23 Oldest transform: 15.23 left\_wheel chassis right wheel Broadcaster: /robot\_state\_publisher | Broadcaster: /robot\_state\_publisher Broadcaster: /robot state publisher Average rate:  $1000\overline{0}.0$ 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 camera\_link  $face\_link$ 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