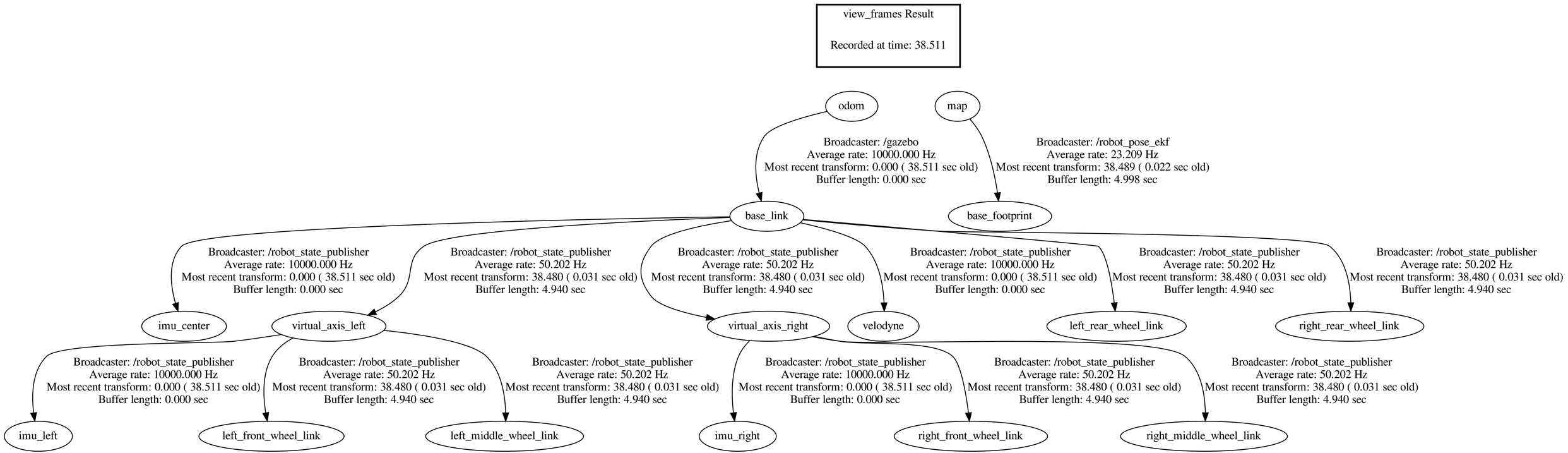
view_frames Result
Recorded at time: 38.511
odom
map
Broadcaster: /gazebo
Average rate: 10000.000 Hz
Most recent transform: 0.000 (38.511 sec old)
Buffer length: 0.000 sec
Broadcaster: /robot_pose_ekf
Average rate: 23.209 Hz
Most recent transform: 38.489 (0.022 sec old)
Buffer length: 4.998 sec
base_link
base_footprint
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (38.511 sec old)
Buffer length: 0.000 sec
Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 38.480 (0.031 sec old)
Buffer length: 4.940 sec
Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 38.480 (0.031 sec old)
Buffer length: 4.940 sec
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (38.511 sec old)
Buffer length: 0.000 sec
Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 38.480 (0.031 sec old)
Buffer length: 4.940 sec
Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 38.480 (0.031 sec old)
Buffer length: 4.940 sec
imu_center
virtual_axis_left
virtual_axis_right
velodyne
left_rear_wheel_link
right_rear_wheel_link
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (38.511 sec old)
Buffer length: 0.000 sec
Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 38.480 (0.031 sec old)
Buffer length: 4.940 sec
Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 38.480 (0.031 sec old)
Buffer length: 4.940 sec
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (38.511 sec old)
Buffer length: 0.000 sec
Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 38.480 (0.031 sec old)
Buffer length: 4.940 sec
Broadcaster: /robot_state_publisher
Average rate: 50.202 Hz
Most recent transform: 38.480 (0.031 sec old)
Buffer length: 4.940 sec
imu_left
left_front_wheel_link
left_middle_wheel_link
imu_right
right_front_wheel_link
right_middle_wheel_link