view frames Result Recorded at time: 21.832 world Broadcaster: /world to map broadcaster Average rate: 10000.0Buffer length: 0.0 Most recent transform: 0.0 Oldest transform: 0.0 map Broadcaster: /map to odom broadcaster Average rate: 10000.0Buffer length: 0.0 Most recent transform: 0.0 Oldest transform: 0.0 odom Broadcaster: /ekf localization Average rate: 50.202 Buffer length: 4.96 Most recent transform: 21.783 Oldest transform: 16.823 base link Broadcaster: /smb robot state publisher Average rate: 50.201 Average rate: 50.201 Average rate: 10000.0 Average rate: 10000.0 Average rate: 10000.0 Average rate: 10000.0 Average rate: 50.201 Average rate: 50.201 Average rate:  $1\overline{0}000.\overline{0}$ Buffer length: 4.98 Buffer length: 4.98 Buffer length: 4.98 Buffer length: 4.98 Buffer length: 0.0 Most recent transform: 21.788 Most recent transform: 21.788 Most recent transform: 21.788 Most recent transform: 21.788 Most recent transform: 0.0 Oldest transform: 0.0 Oldest transform: 0.0 Oldest transform: 16.808 Oldest transform: 16.808 Oldest transform: 16.808 Oldest transform: 16.808 Oldest transform: 0.0 Oldest transform: 0.0 Oldest transform: 0.0 LF WHEEL LH\_WHEEL RF\_WHEEL RH\_WHEEL rslidar\_base\_link imu\_link ( top base\_inertia lidar\_mount\_link Broadcaster: /smb robot state publisher Average rate: 10000.0 Buffer length: 0.0 Most recent transform: 0.0 Oldest transform: 0.0 rslidar