



map

odom

base\_link

base\_footprint

camera\_link

front\_left\_ultrasound\_link

front\_right\_ultrasound\_link

lidar\_link

rear\_left\_ultrasound\_link

rear\_right\_ultrasound\_link

front\_left\_wheel\_link

front\_right\_wheel\_link

rear\_left\_wheel\_link

rear\_right\_wheel\_link

Broadcaster: /slam\_toolbox  
Average rate: 50.201  
Buffer length: 4.98  
Most recent transform: 36.819  
Oldest transform: 31.839

Broadcaster: /gazebo  
Average rate: 50.201  
Buffer length: 4.98  
Most recent transform: 36.622  
Oldest transform: 31.642

Broadcaster: /robot\_state\_publisher  
Average rate: 10000.0  
Buffer length: 0.0  
Most recent transform: 0.0  
Oldest transform: 0.0

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Average rate: 10000.0  
Buffer length: 0.0  
Most recent transform: 0.0  
Oldest transform: 0.0

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