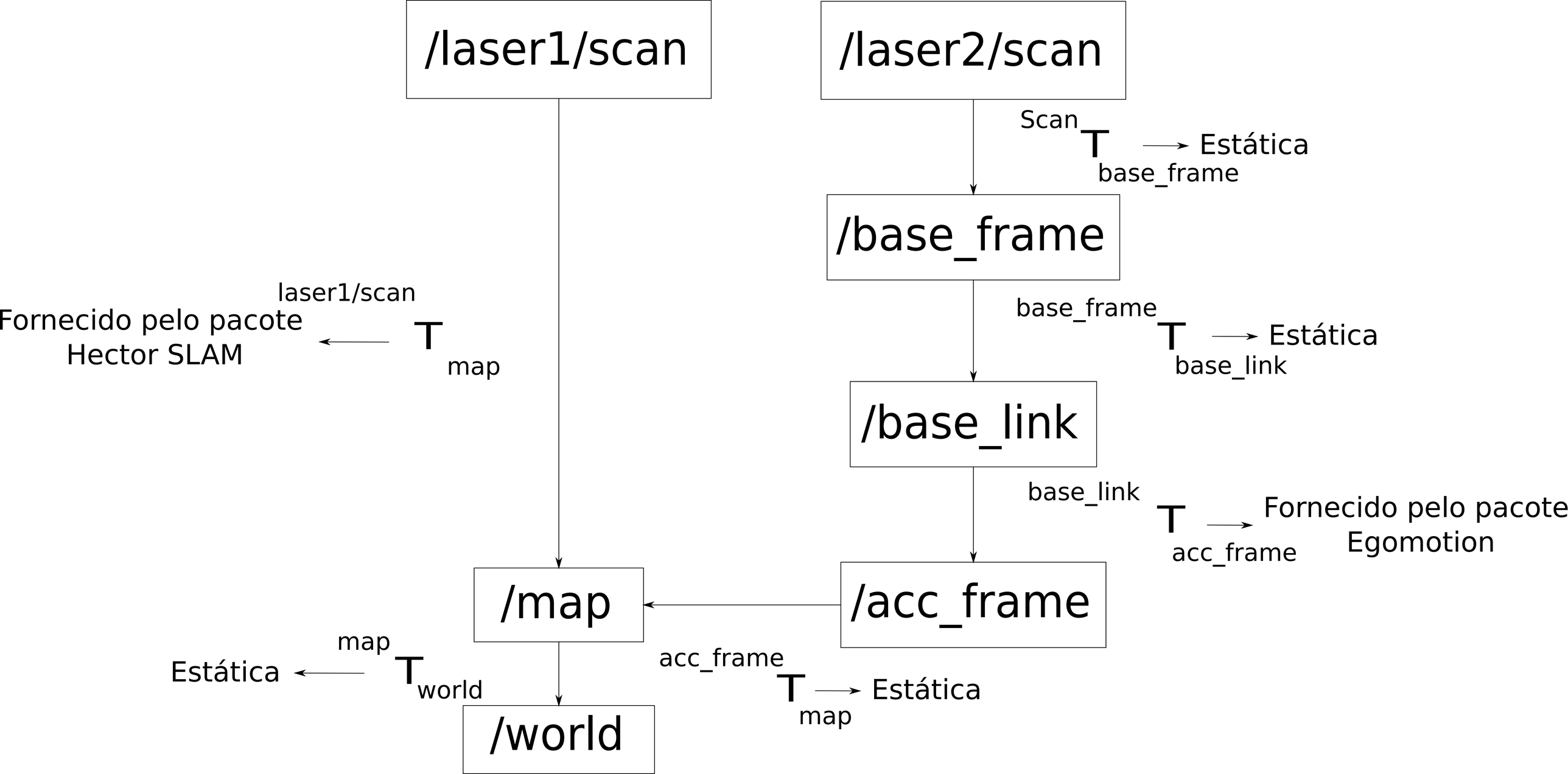
/laser1/scan
/laser2/scan
Scan
T
base_frame
Estática
/base_frame
laser1/scan
Fornecido pelo pacote
Hector SLAM
T
map
base_frame
T
base_link
Estática
/base_link
base_link
T
acc_frame
Fornecido pelo pacote
Egomotion
/map
/acc_frame
map
Estática
T
world
acc_frame
T
map
Estática
/world