view frames Result Recorded at time: 1752153786.510 base_dummy Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1752153786.510 sec old) Buffer length: 0.000 sec base link Broadcaster: /robot state publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1752153786.510 sec old) Most recent transform: 0.000 (1752153786.510 sec old) \Most recent transform: 0.000 (1752153786.510 sec old) Most recent transform: 0.000 (1752153786.510 sec old) Most recent transform: 0.000 (1752153786.510 sec old) / \Most recent transform: 0.000 (1752153786.510 sec old) \Most recent transform: 0.000 (1752153786.510 sec old) Buffer length: 0.000 sec BLWheel01_Link BRWheel01 Link FLWheel01_Link FRWheel01_Link FoldingModularJoint01_Link WheelL_Link WheelR_Link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot state publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 10.204 Hz Most recent transform: 0.000 (1752153786.510 sec old) Most recent transform: 1752153786.502 (0.009 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 0.000 sec BRWheel02_Link FRWheel02_Link FoldingModularJoint02_Link BLWheel02_Link FLWheel02_Link Broadcaster: /robot state publisher Average rate: 10.204 Hz Most recent transform: 1752153786.502 (0.009 sec old) Buffer length: 4.900 sec FoldingModularJoint03_Link Broadcaster: /robot state publisher Average rate: 10.204 Hz Most recent transform: 1752153786.502 (0.009 sec old) Buffer length: 4.900 sec Trunk Link Broadcaster: /robot state publisher Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (1752153786.510 sec old) Most recent transform: 0.000 (1752153786.510 sec old) \Most recent transform: 0.000 (1752153786.510 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec ArmR01 Link ArmL01_Link Head01_Link Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 1752153786.502 (0.009 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec ArmL02_Link ArmR02_Link Head02_Link Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10.204 Hz Average rate: $10.20\overline{4}$ Hz Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 1752153786.502 (0.009 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec Head03 Link ArmL03_Link ArmR03_Link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot state publisher Broadcaster: /robot state publisher Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10.204 Hz Average rate: 10000.000 Hz Average rate: 10.204 Hz Average rate: 10000.000 Hz Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 0.000 (1752153786.510 sec old) Most recent transform: 0.000 (1752153786.510 sec old) \Most recent transform: 0.000 (1752153786.510 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec ArmL04_Link ArmR04_Link EyeL_Link EyeM_Link EyeR_Link Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 1752153786.502 (0.009 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec ArmL05_Link ArmR05_Link Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot state publisher Average rate: 10.204 Hz Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 1752153786.502 (0.009 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec ArmL06_Link ArmR06_Link Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 1752153786.502 (0.009 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec ArmL07_Link ArmR07_Link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 1752153786.502 (0.009 sec old)
Buffer length: 4.900 sec Most recent transform: 1752153786.502 (0.009 sec old) Buffer length: 4.900 sec ArmL08_Link ArmR08 Link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1752153786.510 sec old) Most recent transform: 0.000 (1752153786.510 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec LinearclampinggripperJZ02_Link LinearclampinggripperJZ01_Link Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz Average rate: 10.204 Hz Most recent transform: 0.000 (1752153786.510 sec old) | Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 1752153786.502 (0.009 sec old) Most recent transform: 1752153786.502 (0.009 sec old)
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