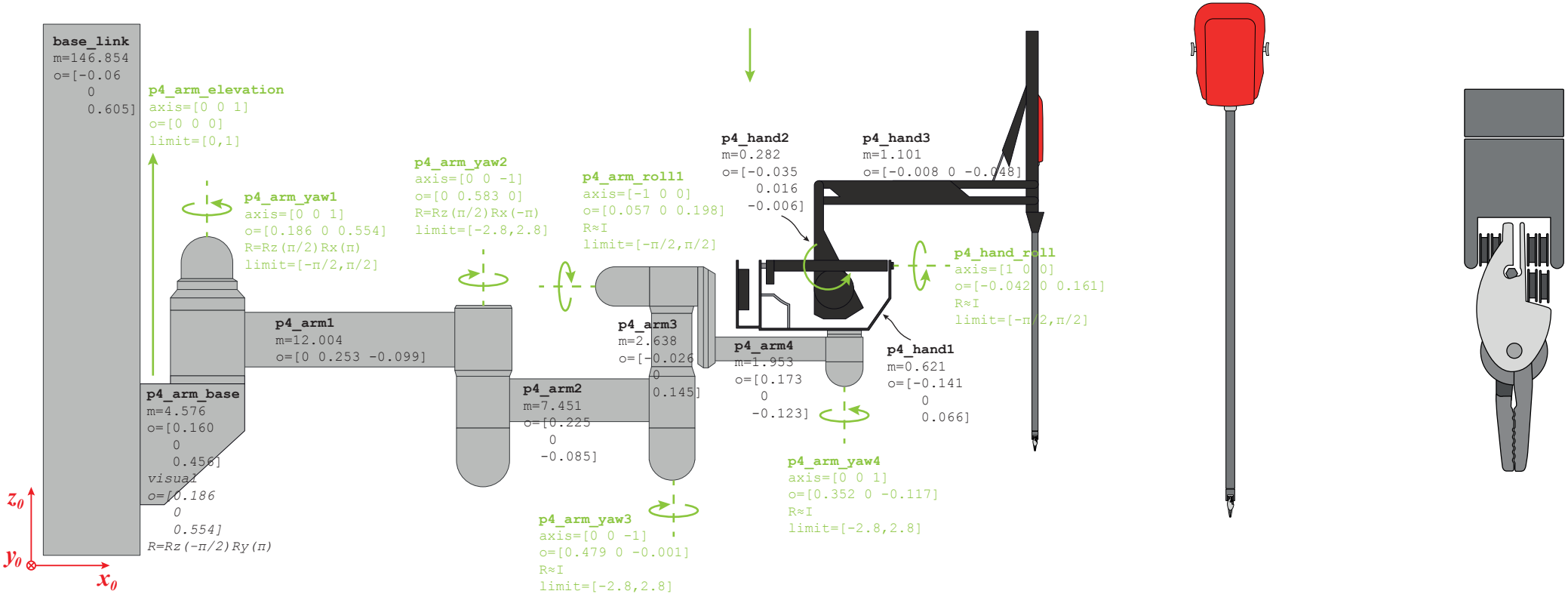
base_link
m=146.854
o=[-0.06
0
0.605]
p4_arm_elevation
axis=[0 0 1]
o=[0 0 0]
limit=[0,1]
p4_arm_yaw1
axis=[0 0 1]
o=[0.186 0 0.554]
R=Rz(π/2)Rx(π)
limit=[-π/2,π/2]
p4_arm_yaw2
axis=[0 0 -1]
o=[0 0.583 0]
R=Rz(π/2)Rx(-π)
limit=[-2.8,2.8]
p4_arm_roll1
axis=[-1 0 0]
o=[0.057 0 0.198]
R≈I
limit=[-π/2,π/2]
p4_hand2
m=0.282
o=[-0.035
0.016
-0.006]
p4_hand3
m=1.101
o=[-0.008 0 -0.048]
p4_hand_roll
axis=[1 0 0]
o=[-0.042 0 0.161]
R≈I
limit=[-π/2,π/2]
p4_arm1
m=12.004
o=[0 0.253 -0.099]
p4_arm3
m=2.638
o=[-0.026
0
0.145]
p4_arm4
m=1.953
o=[0.173
0
-0.123]
p4_hand1
m=0.621
o=[-0.141
0
0.066]
p4_arm_base
m=4.576
o=[0.160
0
0.456]
visual
o=[0.186
0
0.554]
R=Rz(-π/2)Ry(π)
p4_arm2
m=7.451
o=[0.225
0
-0.085]
p4_arm_yaw3
axis=[0 0 -1]
o=[0.479 0 -0.001]
R≈I
limit=[-2.8,2.8]
p4_arm_yaw4
axis=[0 0 1]
o=[0.352 0 -0.117]
R≈I
limit=[-2.8,2.8]
z0
y0
x0