view_frames Result

Recorded at time: 1564.000

map

Broadcaster: /amcl
Average rate: 20.210 Hz
Most recent transform: 1565.950 (-1.950 sec old)
Buffer length: 4.354 sec

world

Broadcaster: /sim_ros_interface
Average rate: 20.210 Hz
Most recent transform: 1564.000 (0.000 sec old)
Buffer length: 4.354 sec

odom

book

Broadcaster: /sim_ros_interface
Average rate: 20.210 Hz
Most recent transform: 1564.000 (0.000 sec old)
Buffer length: 4.354 sec

fetch_robot_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1564.000 sec old)
Buffer length: 0.000 sec

base_link

Broadcaster: /robot_state_publisher
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Buffer length: 4.354 sec

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1564.000 sec old)
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Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1564.000 sec old)
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Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1564.000 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 20.210 Hz
Most recent transform: 1564.000 (0.000 sec old)
Buffer length: 4.354 sec

Broadcaster: /robot_state_publisher
Average rate: 20.210 Hz
Most recent transform: 1564.000 (0.000 sec old)
Buffer length: 4.354 sec

torso_lift_link

estop_link

laser_link

torso_fixed_link

l_wheel_link

r_wheel_link

Broadcaster: /robot_state_publisher
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Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 20.210 Hz
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Buffer length: 4.354 sec

Broadcaster: /robot_state_publisher
Average rate: 20.210 Hz
Most recent transform: 1564.000 (0.000 sec old)
Buffer length: 4.354 sec

Broadcaster: /robot_state_publisher
Average rate: 20.210 Hz
Most recent transform: 1564.000 (0.000 sec old)
Buffer length: 4.354 sec

bellows_link2

head_pan_link

bellows_link

shoulder_pan_link

Broadcaster: /robot_state_publisher
Average rate: 20.210 Hz
Most recent transform: 1564.000 (0.000 sec old)
Buffer length: 4.354 sec

Broadcaster: /robot_state_publisher
Average rate: 20.210 Hz
Most recent transform: 1564.000 (0.000 sec old)
Buffer length: 4.354 sec

head_tilt_link

shoulder_lift_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1564.000 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 20.210 Hz
Most recent transform: 1564.000 (0.000 sec old)
Buffer length: 4.354 sec

head_camera_link

upperarm_roll_link

Broadcaster: /robot_state_publisher
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Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
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Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
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Buffer length: 4.354 sec

head_camera_depth_frame

head_camera_rgb_frame

elbow_flex_link

Broadcaster: /robot_state_publisher
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Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
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Broadcaster: /robot_state_publisher
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Buffer length: 4.354 sec

head_camera_depth_optical_frame

head_camera_rgb_optical_frame

forearm_roll_link

Broadcaster: /robot_state_publisher
Average rate: 20.210 Hz
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wrist_flex_link

Broadcaster: /robot_state_publisher
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Buffer length: 4.354 sec

wrist_roll_link

Broadcaster: /robot_state_publisher
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Buffer length: 0.000 sec

gripper_link

Broadcaster: /robot_state_publisher
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Buffer length: 4.354 sec

Broadcaster: /robot_state_publisher
Average rate: 20.210 Hz
Most recent transform: 1564.000 (0.000 sec old)
Buffer length: 4.354 sec

l_gripper_finger_link

r_gripper_finger_link