view_frames Result Recorded at time: 48.550 odom world Broadcaster: /sim_ros_interface Broadcaster: /sim_ros_interface Broadcaster: /sim_ros_interface Broadcaster: /sim_ros_interface Broadcaster: /sim_ros_interface Average rate: 10000.000 Hz Average rate: 20.164 Hz Average rate: 20.164 Hz Average rate: 20.164 Hz Average rate: 20.164 Hz Most recent transform: 0.000 (48.550 sec old) Most recent transform: 48.550 (0.000 sec old) Most recent transform: 48.550 (0.000 sec old) \Most recent transform: 48.550 (0.000 sec old) \Most recent transform: 48.550 (0.000 sec old) Buffer length: 0.000 sec Buffer length: 6.100 sec Buffer length: 6.100 sec Buffer length: 6.100 sec Buffer length: 6.100 sec base_link bottle fetch_robot_link can hammer Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 20.166 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 20.166 Hz Average rate: 20.166 Hz Most recent transform: 48.500 (0.050 sec old) Most recent transform: 0.000 (48.550 sec old) | Most recent transform: 0.000 (48.550 sec old) | Most recent transform: 0.000 (48.550 sec old) | Most recent transform: 48.500 (0.050 sec old) Most recent transform: 48.500 (0.050 sec old) Buffer length: 6.050 sec Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 6.050 sec Buffer length: 6.050 sec torso_lift_link laser_link l_wheel_link r_wheel_link estop_link torso_fixed_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 20.166 Hz Average rate: 20.166 Hz Average rate: 10000.000 Hz Average rate: 20.166 Hz Most recent transform: 0.000 (48.550 sec old) Most recent transform: 48.500 (0.050 sec old) Most recent transform: 48.500 (0.050 sec old) Most recent transform: 48.500 (0.050 sec old) Buffer length: 0.000 sec Buffer length: 6.050 sec Buffer length: 6.050 sec Buffer length: 6.050 sec shoulder_pan_link head_pan_link bellows_link bellows_link2 Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 20.166 Hz Average rate: 20.166 Hz Most recent transform: 48.500 (0.050 sec old) Most recent transform: 48.500 (0.050 sec old) Buffer length: 6.050 sec Buffer length: 6.050 sec head_tilt_link shoulder_lift_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 20.166 Hz Most recent transform: 0.000 (48.550 sec old) Most recent transform: 48.500 (0.050 sec old) Buffer length: 0.000 sec Buffer length: 6.050 sec upperarm_roll_link head_camera_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: 20.166 Hz Most recent transform: 48.500 (0.050 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 6.050 sec elbow_flex_link head_camera_rgb_frame head_camera_depth_frame Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 20.166 Hz Most recent transform: 48.500 (0.050 sec old) Most recent transform: 0.000 (48.550 sec old) Most recent transform: 0.000 (48.550 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 6.050 sec forearm_roll_link head_camera_depth_optical_frame head_camera_rgb_optical_frame Broadcaster: /robot_state_publisher Average rate: 20.166 Hz Most recent transform: 48.500 (0.050 sec old) Buffer length: 6.050 sec wrist_flex_link Broadcaster: /robot_state_publisher Average rate: 20.166 Hz Most recent transform: 48.500 (0.050 sec old) Buffer length: 6.050 sec wrist_roll_link Broadcaster: /robot_state_publisher

Average rate: 10000.000 Hz

Most recent transform: 0.000 (48.550 sec old)

Buffer length: 0.000 sec

r_gripper_finger_link

Broadcaster: /robot_state_publisher

Average rate: 20.166 Hz

Buffer length: 6.050 sec

gripper_link

Broadcaster: /robot_state_publisher

Average rate: 20.166 Hz

Buffer length: 6.050 sec

l_gripper_finger_link

Broadcaster: /sim_ros_interface

Average rate: 20.164 Hz

Most recent transform: 48.550 (0.000 sec old)

Buffer length: 6.100 sec

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