view frames Result Recorded at time: 252.710 world Broadcaster: /robot state publisher Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz Average rate: $1\overline{0}000.\overline{0}0$ Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (252.710 sec old) Most recent transform: 0.000 (252.710 sec old) Most recent transform: 0.000 (252.710 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec table base_cylinder ground Broadcaster: /robot state publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (252.710 sec old) Buffer length: 0.000 sec base link Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz Average rate: 50.207 Hz Most recent transform: 252.682 (0.028 sec old) Most recent transform: 0.000 (252.710 sec old) Buffer length: 4.840 sec Buffer length: 0.000 sec base shoulder link Broadcaster: /robot state publisher Average rate: 50.207 Hz Most recent transform: 252.682 (0.028 sec old) Buffer length: 4.840 sec upper_arm_link Broadcaster: /robot state publisher Average rate: 50.207 Hz Most recent transform: 252.682 (0.028 sec old) Buffer length: 4.840 sec forearm_link Broadcaster: /robot state publisher Average rate: 50.207 Hz Most recent transform: 252.682 (0.028 sec old) Buffer length: 4.840 sec wrist_1_link Broadcaster: /robot_state_publisher Average rate: 50.207 Hz Most recent transform: 252.682 (0.028 sec old) Buffer length: 4.840 sec wrist_2_link Broadcaster: /robot_state_publisher Average rate: 50.207 Hz Most recent transform: 252.682 (0.028 sec old) Buffer length: 4.840 sec wrist_3_link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot state publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (252.710 sec old) Most recent transform: 0.000 (252.710 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec ee_link tool0 Broadcaster: /robot state publisher Average rate: 10000.000 Hz

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