```
view_frames Result

Recorded at time: 1607412682.422
```

yumi_base_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1607412682.422 sec old)
Buffer length: 0.000 sec

camera_link

Broadcaster: /camera/realsense2_camera_manager
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1607412682.422 sec old)
Buffer length: 0.000 sec

Broadcaster: /camera/realsense2_camera_manager
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1607412682.422 sec old)
Buffer length: 0.000 sec

yumi_body

Broadcaster: /robot_state_publisher
Average rate: 10.062 Hz
Most recent transform: 1607412682.343 (0.078 sec old)
Buffer length: 4.870 sec

Broadcaster: /robot_state_publisher
Average rate: 10.060 Hz
Most recent transform: 1607412682.360 (0.061 sec old)
Buffer length: 4.871 sec

camera_color_frame

Broadcaster: /camera/realsense2_camera_manager
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1607412682.422 sec old)
Buffer length: 0.000 sec

camera_depth_frame

Broadcaster: /camera/realsense2_camera_manager
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1607412682.422 sec old)
Buffer length: 0.000 sec

yumi_link_1_l

Broadcaster: /robot_state_publisher
Average rate: 10.062 Hz
Most recent transform: 1607412682.343 (0.078 sec old)
Buffer length: 4.870 sec

yumi_link_1_r

Broadcaster: /robot_state_publisher
Average rate: 10.060 Hz
Most recent transform: 1607412682.360 (0.061 sec old)
Buffer length: 4.871 sec

camera_color_optical_frame

Broadcaster: /aruco_tracker
Average rate: 29.980 Hz
Most recent transform: 1607412682.373 (0.049 sec old)
Buffer length: 4.937 sec

camera_depth_optical_frame

yumi_link_2_l

Broadcaster: /robot_state_publisher
Average rate: 10.062 Hz
Most recent transform: 1607412682.343 (0.078 sec old)
Buffer length: 4.870 sec

yumi_link_2_r

Broadcaster: /robot_state_publisher
Average rate: 10.060 Hz
Most recent transform: 1607412682.360 (0.061 sec old)
Buffer length: 4.871 sec

camera_marker

yumi_link_3_l

Broadcaster: /robot_state_publisher
Average rate: 10.062 Hz
Most recent transform: 1607412682.343 (0.078 sec old)
Buffer length: 4.870 sec

yumi_link_3_r

Broadcaster: /robot_state_publisher
Average rate: 10.060 Hz
Most recent transform: 1607412682.360 (0.061 sec old)
Buffer length: 4.871 sec

yumi_link_4_l

Broadcaster: /robot_state_publisher
Average rate: 10.062 Hz
Most recent transform: 1607412682.343 (0.078 sec old)
Buffer length: 4.870 sec

yumi_link_4_r

Broadcaster: /robot_state_publisher
Average rate: 10.060 Hz
Most recent transform: 1607412682.360 (0.061 sec old)
Buffer length: 4.871 sec

yumi_link_5_l

Broadcaster: /robot_state_publisher
Average rate: 10.062 Hz
Most recent transform: 1607412682.343 (0.078 sec old)
Buffer length: 4.870 sec

yumi_link_5_r

Broadcaster: /robot_state_publisher
Average rate: 10.060 Hz
Most recent transform: 1607412682.360 (0.061 sec old)
Buffer length: 4.871 sec

yumi_link_6_l

Broadcaster: /robot_state_publisher
Average rate: 10.062 Hz
Most recent transform: 1607412682.343 (0.078 sec old)
Buffer length: 4.870 sec

yumi_link_6_r

Broadcaster: /robot_state_publisher
Average rate: 10.060 Hz
Most recent transform: 1607412682.360 (0.061 sec old)
Buffer length: 4.871 sec

yumi_link_7_l

Broadcaster: /robot_state_publisher
Average rate: 10.062 Hz
Most recent transform: 1607412682.343 (0.078 sec old)
Buffer length: 4.870 sec

yumi_link_7_r

Broadcaster: /robot_state_publisher
Average rate: 10.060 Hz
Most recent transform: 1607412682.360 (0.061 sec old)
Buffer length: 4.871 sec

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1607412682.422 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1607412682.422 sec old)
Buffer length: 0.000 sec

gripper_l_base

gripper_r_base