```
view_frames Result

Recorded at time: 1720610157.386
```

odom   robot_stand

Broadcaster: /kinematic_simulation
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1720610157.386 sec old)
Buffer length: 0.000 sec

base_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1720610157.386 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1720610157.318 (0.067 sec old)
Buffer length: 4.900 sec

base

shoulder_link

Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1720610157.318 (0.067 sec old)
Buffer length: 4.900 sec

upper_arm_link

Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1720610157.318 (0.067 sec old)
Buffer length: 4.900 sec

forearm_link

Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1720610157.318 (0.067 sec old)
Buffer length: 4.900 sec

wrist_1_link

Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1720610157.318 (0.067 sec old)
Buffer length: 4.900 sec

wrist_2_link

Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1720610157.318 (0.067 sec old)
Buffer length: 4.900 sec

wrist_3_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1720610157.386 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1720610157.386 sec old)
Buffer length: 0.000 sec

ee_link

tool0

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1720610157.386 sec old)
Buffer length: 0.000 sec

camera_link