view_frames Result Recorded at time: 1379779862.670 /world_link Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 50.201 Hz Average rate: 50.201 Hz Most recent transform: -0.474 sec old Most recent transform: -0.474 sec old Buffer length: 4.960 sec Buffer length: 4.960 sec /table_link /torso_link Broadcaster: /robot state publisher Broadcaster: /robot_state_publisher Average rate: 50.201 Hz Average rate: 50.201 Hz Most recent transform: -0.474 sec old Most recent transform: -0.474 sec old Buffer length: 4.960 sec Buffer length: 4.960 sec /calib_leftArm_arm_base_link /calib_rightArm_arm_base_link Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10.208 Hz Average rate: 10.208 Hz Most recent transform: 0.103 sec old Most recent transform: 0.103 sec old Buffer length: 4.800 sec Buffer length: 4.800 sec /rightArm_arm_1_link /leftArm_arm_1_link Broadcaster: /robot state publisher Broadcaster: /robot_state_publisher Average rate: 10.208 Hz Average rate: 10.208 Hz Most recent transform: 0.103 sec old Most recent transform: 0.103 sec old Buffer length: 4.800 sec Buffer length: 4.800 sec /leftArm_arm_2_link /rightArm_arm_2_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10.208 Hz Average rate: 10.208 Hz Most recent transform: 0.103 sec old Most recent transform: 0.103 sec old Buffer length: 4.800 sec Buffer length: 4.800 sec /leftArm_arm_3_link /rightArm_arm_3_link Broadcaster: /robot state publisher Broadcaster: /robot_state_publisher Average rate: 10.208 Hz Average rate: 10.208 Hz Most recent transform: 0.103 sec old Most recent transform: 0.103 sec old Buffer length: 4.800 sec Buffer length: 4.800 sec /leftArm_arm_4_link /rightArm_arm_4_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10.208 Hz Average rate: 10.208 Hz Most recent transform: 0.103 sec old Most recent transform: 0.103 sec old Buffer length: 4.800 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