view frames Result Recorded at time: 1690331095.058 base_link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot state publisher Average rate: 10000.000 Hz Most recent transform: 1690331095.030 (0.028 sec old)
Buffer length: 4.900 sec Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 0.000 (1690331095.058 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec link_aruco_left_base link_aruco_right_base fake_link_x Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1690331095.058 sec old) Buffer length: 0.000 sec link_mast Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot state publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 1690331095.030 (0.028 sec old) Most recent transform: 0.000 (1690331095.058 sec old) Buffer length: 4.900 sec Buffer length: 0.000 sec Buffer length: 0.000 sec respeaker_base link_lift link_head Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 1690331095.030 (0.028 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 4.900 sec link_head_pan link_arm_l4 link_aruco_shoulder Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1690331095.030 (0.028 sec old) Most recent transform: 1690331095.030 (0.028 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec link_head_tilt link_arm_l3 Broadcaster: /robot_state_publisher Broadcaster: /robot state publisher Average rate: $10.20\overline{4}$ Hz Average rate: 10000.000 Hz Most recent transform: 1690331095.030 (0.028 sec old) Most recent transform: 0.000 (1690331095.058 sec old) Buffer length: 4.900 sec Buffer length: 0.000 sec link_arm_l2 camera_bottom_screw_frame Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz

Most recent transform: 0.000 (1690331095.058 sec old) Average rate: 10.204 Hz Most recent transform: 1690331095.030 (0.028 sec old) Buffer length: 4.900 sec Buffer length: 0.000 sec link_arm_l1 camera link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 0.000 (1690331095.058 sec old) \Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 1690331095.030 (0.028 sec old) \Most recent transform: 0.000 (1690331095.058 sec old) Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec link arm 10 camera_depth_frame camera_infra2_frame camera_color_frame camera_infra1_frame Broadcaster: /robot state publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 1690331095.030 (0.028 sec old) Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 0.000 (1690331095.058 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec link_wrist_yaw camera_color_optical_frame camera_infra2_optical_frame link_aruco_inner_wrist camera_depth_optical_frame camera_infra1_optical_frame link_aruco_top_wrist Broadcaster: /robot state publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1690331095.058 sec old) Buffer length: 0.000 sec link_wrist_yaw_bottom Broadcaster: /robot state publisher Average rate: 10.204 Hz Most recent transform: 1690331095.030 (0.028 sec old) Buffer length: 4.900 sec link_wrist_pitch Broadcaster: /robot state publisher Average rate: 10.204 Hz Most recent transform: 1690331095.030 (0.028 sec old) Buffer length: 4.900 sec link wrist roll Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1690331095.058 sec old) \Most recent transform: 0.000 (1690331095.058 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec link_straight_gripper link_raised_gripper Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 1690331095.030 (0.028 sec old) \Most recent transform: 1690331095.030 (0.028 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec link_gripper_finger_left link_gripper_finger_right Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz Average rate: $1\overline{0}000.\overline{00}0$ Hz Most recent transform: 0.000 (1690331095.058 sec old) Most recent transform: 0.000 (1690331095.058 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec

link_gripper_fingertip_left

link_gripper_fingertip_right