

view\_frames Result  
Recorded at time: 12.005

odom

Broadcaster: /gazebo  
Average rate: 40.247 Hz  
Most recent transform: 11.989 ( 0.016 sec old)  
Buffer length: 4.050 sec

ebot\_base

FUS1: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

FUS2: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

FUS3: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

FUS4: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

LHUS10: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

LHUS9: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

RHUS7: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

RHUS9: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

RUS5: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

RUS6: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

base\_link: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

camera\_link: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

imu\_link: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

laser: Broadcaster: /robot\_state\_publisher  
Average rate: 10000.000 Hz  
Most recent transform: 0.000 ( 12.005 sec old)  
Buffer length: 0.000 sec

FWL: Broadcaster: /robot\_state\_publisher  
Average rate: 10.250 Hz  
Most recent transform: 12.001 ( 0.004 sec old)  
Buffer length: 4.000 sec

FWR: Broadcaster: /robot\_state\_publisher  
Average rate: 10.250 Hz  
Most recent transform: 12.001 ( 0.004 sec old)  
Buffer length: 4.000 sec

RWL: Broadcaster: /robot\_state\_publisher  
Average rate: 10.250 Hz  
Most recent transform: 12.001 ( 0.004 sec old)  
Buffer length: 4.000 sec

RWR: Broadcaster: /robot\_state\_publisher  
Average rate: 10.250 Hz  
Most recent transform: 12.001 ( 0.004 sec old)  
Buffer length: 4.000 sec

base

shoulder\_link

camera\_depth\_frame

camera\_rgb\_frame

upper\_arm\_link

forearm\_link

wrist\_1\_link

wrist\_2\_link

wrist\_3\_link

camera\_link2

ce\_link

gripper\_base\_link

tool0

camera\_depth\_frame2

camera\_rgb\_frame2

gripper\_finger1\_knuckle\_link

gripper\_finger2\_knuckle\_link

gripper\_finger1\_inner\_knuckle\_link

gripper\_finger2\_inner\_knuckle\_link

gripper\_finger1\_finger\_link

gripper\_finger2\_finger\_link

gripper\_finger1\_finger\_tip\_link

gripper\_finger2\_finger\_tip\_link