view_frames Result

Recorded at time: 1571468672.664

```
map
```
Broadcaster: /map_base_tf
Average rate: 193.688 Hz
Most recent transform: 1571468672.664 (-0.001 sec old)
Buffer length: 4.993 sec

```
bot
```
Broadcaster: robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1571468672.664 sec old)
Buffer length: 0.000 sec

```
shoulder_yaw_motor
```
Broadcaster: robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1571468672.650 (0.014 sec old)
Buffer length: 4.900 sec

```
shoulder_bracket
```
Broadcaster: robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1571468672.650 (0.014 sec old)
Buffer length: 4.900 sec

```
shoulder_pitch_motor
```
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1571468672.664 sec old)
Buffer length: 0.000 sec

```
biscep
```
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1571468672.664 sec old)
Buffer length: 0.000 sec

```
elbow_bracket
```
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1571468672.650 (0.014 sec old)
Buffer length: 4.900 sec

```
elbow_motor
```
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1571468672.664 sec old)
Buffer length: 0.000 sec

```
forearm
```
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1571468672.664 sec old)
Buffer length: 0.000 sec

```
wrist_bracket
```
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1571468672.650 (0.014 sec old)
Buffer length: 4.900 sec

```
wrist_pitch_motor
```
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1571468672.664 sec old)
Buffer length: 0.000 sec

```
square_plate_1
```
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1571468672.664 sec old)
Buffer length: 0.000 sec

```
AXB2B_SQ_Y
```
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1571468672.664 sec old)
Buffer length: 0.000 sec

```
wrist_yaw_motor
```
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1571468672.650 (0.014 sec old)
Buffer length: 4.900 sec

```
AXBrak_Y_R
```
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1571468672.664 sec old)
Buffer length: 0.000 sec

```
wrist_roll_motor
```
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1571468672.650 (0.014 sec old)
Buffer length: 4.900 sec

```
roll_j_plate
```
Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1571468672.664 sec old)
Buffer length: 0.000 sec

```
gripper
```