```
┌─────────────────────────────────────┐
│           view_frames Result          │
│                                       │
│   Recorded at time: 1571220421.475    │
└─────────────────────────────────────┘

( map )        ( bot )
  │
  │   Broadcaster: /map_base_tf
  │   Average rate: 10000.000 Hz
  │   Most recent transform: 0.000 ( 1571220421.475 sec old)
  │   Buffer length: 0.000 sec
  ▼
( shoulder_yaw_motor )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10.204 Hz
  │   Most recent transform: 1571220421.426 ( 0.050 sec old)
  │   Buffer length: 4.900 sec
  ▼
( shoulder_bracket )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10.204 Hz
  │   Most recent transform: 1571220421.426 ( 0.050 sec old)
  │   Buffer length: 4.900 sec
  ▼
( shoulder_pitch_motor )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10000.000 Hz
  │   Most recent transform: 0.000 ( 1571220421.475 sec old)
  │   Buffer length: 0.000 sec
  ▼
( biscep )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10000.000 Hz
  │   Most recent transform: 0.000 ( 1571220421.475 sec old)
  │   Buffer length: 0.000 sec
  ▼
( elbow_bracket )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10.204 Hz
  │   Most recent transform: 1571220421.426 ( 0.050 sec old)
  │   Buffer length: 4.900 sec
  ▼
( elbow_motor )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10000.000 Hz
  │   Most recent transform: 0.000 ( 1571220421.475 sec old)
  │   Buffer length: 0.000 sec
  ▼
( forearm )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10000.000 Hz
  │   Most recent transform: 0.000 ( 1571220421.475 sec old)
  │   Buffer length: 0.000 sec
  ▼
( wrist_bracket )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10.204 Hz
  │   Most recent transform: 1571220421.426 ( 0.050 sec old)
  │   Buffer length: 4.900 sec
  ▼
( wrist_pitch_motor )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10000.000 Hz
  │   Most recent transform: 0.000 ( 1571220421.475 sec old)
  │   Buffer length: 0.000 sec
  ▼
( square_plate_1 )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10000.000 Hz
  │   Most recent transform: 0.000 ( 1571220421.475 sec old)
  │   Buffer length: 0.000 sec
  ▼
( AXB2B_SQ_Y )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10000.000 Hz
  │   Most recent transform: 0.000 ( 1571220421.475 sec old)
  │   Buffer length: 0.000 sec
  ▼
( wrist_yaw_motor )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10.204 Hz
  │   Most recent transform: 1571220421.426 ( 0.050 sec old)
  │   Buffer length: 4.900 sec
  ▼
( AXBrak_Y_R )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10000.000 Hz
  │   Most recent transform: 0.000 ( 1571220421.475 sec old)
  │   Buffer length: 0.000 sec
  ▼
( wrist_roll_motor )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10.204 Hz
  │   Most recent transform: 1571220421.426 ( 0.050 sec old)
  │   Buffer length: 4.900 sec
  ▼
( roll_j_plate )
  │
  │   Broadcaster: /robot_state_publisher
  │   Average rate: 10000.000 Hz
  │   Most recent transform: 0.000 ( 1571220421.475 sec old)
  │   Buffer length: 0.000 sec
  ▼
( gripper )
```