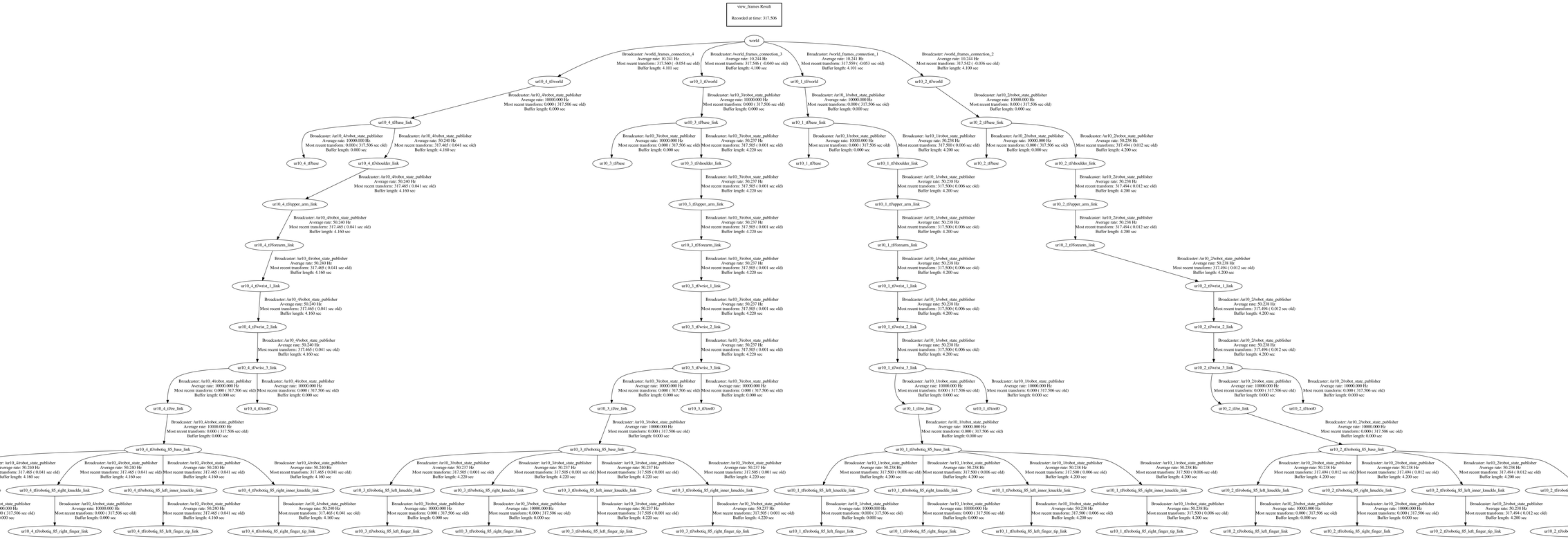
view_frames Result
Recorded at time: 317.506
world
Broadcaster: /world_frames_connection_4
Average rate: 10.241 Hz
Most recent transform: 317.506 (-0.054 sec old)
Buffer length: 4.101 sec
Broadcaster: /world_frames_connection_3
Average rate: 10.244 Hz
Most recent transform: 317.546 (-0.040 sec old)
Buffer length: 4.100 sec
Broadcaster: /world_frames_connection_1
Average rate: 10.241 Hz
Most recent transform: 317.559 (-0.053 sec old)
Buffer length: 4.101 sec
Broadcaster: /world_frames_connection_2
Average rate: 10.244 Hz
Most recent transform: 317.542 (-0.036 sec old)
Buffer length: 4.100 sec
ur10_4_tfworld
ur10_3_tfworld
ur10_1_tfworld
ur10_2_tfworld
Broadcaster: /ur10_4/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
Broadcaster: /ur10_3/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
Broadcaster: /ur10_1/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
Broadcaster: /ur10_2/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
ur10_4_tfbase_link
ur10_3_tfbase_link
ur10_1_tfbase_link
ur10_2_tfbase_link
Broadcaster: /ur10_4/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
Broadcaster: /ur10_4/robot_state_publisher
Average rate: 50.240 Hz
Most recent transform: 317.465 (0.041 sec old)
Buffer length: 4.160 sec
Broadcaster: /ur10_3/robot_state_publisher
Average rate: 50.237 Hz
Most recent transform: 317.505 (0.001 sec old)
Buffer length: 4.220 sec
Broadcaster: /ur10_1/robot_state_publisher
Average rate: 50.238 Hz
Most recent transform: 317.500 (0.006 sec old)
Buffer length: 4.200 sec
Broadcaster: /ur10_2/robot_state_publisher
Average rate: 50.238 Hz
Most recent transform: 317.494 (0.012 sec old)
Buffer length: 4.200 sec
ur10_4_tfbase
ur10_4_tfshoulder_link
ur10_3_tfbase
ur10_3_tfshoulder_link
ur10_1_tfbase
ur10_1_tfshoulder_link
ur10_2_tfbase
ur10_2_tfshoulder_link
ur10_4_tfupper_arm_link
ur10_3_tfupper_arm_link
ur10_1_tfupper_arm_link
ur10_2_tfupper_arm_link
ur10_4_tfforearm_link
ur10_3_tfforearm_link
ur10_1_tfforearm_link
ur10_2_tfforearm_link
ur10_4_tfwrist_1_link
ur10_3_tfwrist_1_link
ur10_1_tfwrist_1_link
ur10_2_tfwrist_1_link
ur10_4_tfwrist_2_link
ur10_3_tfwrist_2_link
ur10_1_tfwrist_2_link
ur10_2_tfwrist_2_link
ur10_4_tfwrist_3_link
ur10_3_tfwrist_3_link
ur10_1_tfwrist_3_link
ur10_2_tfwrist_3_link
ur10_4_tflee_link
ur10_4_tftool0
ur10_3_tflee_link
ur10_3_tftool0
ur10_1_tflee_link
ur10_1_tftool0
ur10_2_tflee_link
ur10_2_tftool0
Broadcaster: /ur10_4/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
Broadcaster: /ur10_3/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
Broadcaster: /ur10_1/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
Broadcaster: /ur10_2/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
ur10_4_tfrobotiq_85_base_link
ur10_3_tfrobotiq_85_base_link
ur10_1_tfrobotiq_85_base_link
ur10_2_tfrobotiq_85_base_link
Broadcaster: /ur10_4/robot_state_publisher
Average rate: 50.240 Hz
Most recent transform: 317.465 (0.041 sec old)
Buffer length: 4.160 sec
Broadcaster: /ur10_3/robot_state_publisher
Average rate: 50.237 Hz
Most recent transform: 317.505 (0.001 sec old)
Buffer length: 4.220 sec
Broadcaster: /ur10_1/robot_state_publisher
Average rate: 50.238 Hz
Most recent transform: 317.500 (0.006 sec old)
Buffer length: 4.200 sec
Broadcaster: /ur10_2/robot_state_publisher
Average rate: 50.238 Hz
Most recent transform: 317.494 (0.012 sec old)
Buffer length: 4.200 sec
ur10_4_tfrobotiq_85_left_knuckle_link
ur10_4_tfrobotiq_85_right_knuckle_link
ur10_4_tfrobotiq_85_left_inner_knuckle_link
ur10_4_tfrobotiq_85_right_inner_knuckle_link
ur10_3_tfrobotiq_85_left_knuckle_link
ur10_3_tfrobotiq_85_right_knuckle_link
ur10_3_tfrobotiq_85_left_inner_knuckle_link
ur10_3_tfrobotiq_85_right_inner_knuckle_link
ur10_1_tfrobotiq_85_left_knuckle_link
ur10_1_tfrobotiq_85_right_knuckle_link
ur10_1_tfrobotiq_85_left_inner_knuckle_link
ur10_1_tfrobotiq_85_right_inner_knuckle_link
ur10_2_tfrobotiq_85_left_knuckle_link
ur10_2_tfrobotiq_85_right_knuckle_link
ur10_2_tfrobotiq_85_left_inner_knuckle_link
ur10_2_tfrobotiq_85_right_inner_knuckle_link
Broadcaster: /ur10_4/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
Broadcaster: /ur10_3/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
Broadcaster: /ur10_1/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
Broadcaster: /ur10_2/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (317.506 sec old)
Buffer length: 0.000 sec
ur10_4_tfrobotiq_85_left_finger_link
ur10_4_tfrobotiq_85_right_finger_link
ur10_4_tfrobotiq_85_left_finger_tip_link
ur10_4_tfrobotiq_85_right_finger_tip_link
ur10_3_tfrobotiq_85_left_finger_link
ur10_3_tfrobotiq_85_right_finger_link
ur10_3_tfrobotiq_85_left_finger_tip_link
ur10_3_tfrobotiq_85_right_finger_tip_link
ur10_1_tfrobotiq_85_left_finger_link
ur10_1_tfrobotiq_85_right_finger_link
ur10_1_tfrobotiq_85_left_finger_tip_link
ur10_1_tfrobotiq_85_right_finger_tip_link
ur10_2_tfrobotiq_85_left_finger_link
ur10_2_tfrobotiq_85_right_finger_link
ur10_2_tfrobotiq_85_left_finger_tip_link
ur10_2_tfrobotiq_85_right_finger_tip_link