Recorded at time: 1550060497.905 world Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 4.900 sec Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 4.900 sec 12 Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 4.900 sec skiff Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 0.000 (1550060497.905 sec old) Most recent transform: 1550060497.855 (0.050 sec old) Most recent transform: 1550060497.855 (0.050 sec old) Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec port_rowlock_l footplate starboard_rowlock_l seat Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 4.900 sec back_low upperleg_2 lowerleg starboard_oar_1 port_oar_1 Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1550060497.855 (0.050 sec old) | Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 4.900 sec port_blade_l back_high handle_left_11 starboard_blade_l upperleg_1 Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 10.204 Hz Most recent transform: 0.000 (1550060497.905 sec old) Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 0.000 sec Buffer length: 4.900 sec shoulder_link handle_left_12 Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 0.000 (1550060497.905 sec old) Most recent transform: 1550060497.855 (0.050 sec old) Most recent transform: 1550060497.855 (0.050 sec old) Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec left_shoulder_xx_link right_shoulder_psi_link arm_l_lower_2 head Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Average rate: 10.204 Hz Average rate: 10000.000 Hz Most recent transform: 1550060497.855 (0.050 sec old) Most recent transform: 1550060497.855 (0.050 sec old) Most recent transform: 0.000 (1550060497.905 sec old) Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 4.900 sec left_shoulder_psi_link dummy_link_2 arm_r_upper Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 4.900 sec arm_l_upper Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 4.900 sec left_elbow_psi_link Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1550060497.855 (0.050 sec old) Buffer length: 4.900 sec arm_l_lower_1 Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1550060497.905 sec old) Buffer length: 0.000 sec dummy_link_1

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