view_frames Result Recorded at time: 1547112791.637 shoulder_yaw_motor map Broadcaster: /robot_state_publisher Broadcaster: /map_base_tf Average rate: 10.204 Hz Average rate: 20.137 Hz Most recent transform: 1547112791.652 (-0.015 sec old) Most recent transform: 1547112791.616 (0.021 sec old) Buffer length: 4.900 sec Buffer length: 4.867 sec shoulder_bracket bottom_link Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1547112791.616 (0.021 sec old) Buffer length: 4.900 sec shoulder_pitch_motor Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1547112791.637 sec old) Buffer length: 0.000 sec biscep Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1547112791.637 sec old) Buffer length: 0.000 sec elbow_bracket Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1547112791.616 (0.021 sec old) Buffer length: 4.900 sec elbow_motor Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1547112791.637 sec old) Buffer length: 0.000 sec forearm Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1547112791.637 sec old) Buffer length: 0.000 sec wrist_bracket Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1547112791.616 (0.021 sec old) Buffer length: 4.900 sec wrist_pitch_motor Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1547112791.637 sec old) Buffer length: 0.000 sec wrist_roll_motor Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1547112791.616 (0.021 sec old) Buffer length: 4.900 sec

end_effector