view frames Result Recorded at time: 51.489 world Broadcaster: /robot\_state\_publisher Average rate:  $1\overline{0}000.\overline{00}0$  Hz Most recent transform: 0.000 (51.489 sec old) Buffer length: 0.000 sec base link Broadcaster: /robot\_state\_publisher Broadcaster: /robot\_state\_publisher Average rate: 10000.000 Hz Average rate:  $1\overline{0}000.\overline{00}0$  Hz Most recent transform: 0.000 (51.489 sec old) Most recent transform: 0.000 (51.489 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec base\_link\_inertia base Broadcaster: /robot\_state\_publisher Average rate:  $\overline{2}38.5\overline{5}8$  Hz Most recent transform: 51.480 (0.009 sec old) Buffer length: 2.884 sec shoulder link Broadcaster: /robot\_state\_publisher Average rate: 238.558 Hz Most recent transform: 51.480 (0.009 sec old) Buffer length: 2.884 sec upper\_arm\_link Broadcaster: /robot state publisher Average rate:  $\overline{2}38.5\overline{5}8$  Hz Most recent transform: 51.480 (0.009 sec old) Buffer length: 2.884 sec forearm\_link Broadcaster: /robot state publisher Average rate:  $\overline{2}38.5\overline{5}8$  Hz Most recent transform: 51.480 (0.009 sec old) Buffer length: 2.884 sec wrist\_1\_link Broadcaster: /robot\_state\_publisher Average rate: 238.558 Hz
Most recent transform: 51.480 ( 0.009 sec old) Buffer length: 2.884 sec wrist\_2\_link Broadcaster: /robot\_state\_publisher Broadcaster: /robot\_state\_publisher Average rate: 238.558 Hz Average rate:  $1\overline{0}000.\overline{00}0$  Hz Most recent transform: 51.480 (0.009 sec old) Most recent transform: 0.000 (51.489 sec old) Buffer length: 0.000 sec Buffer length: 2.884 sec d435\_link wrist\_3\_link Broadcaster: /robot\_state\_publisher Average rate:  $1\overline{0}000.\overline{00}0$  Hz Most recent transform: 0.000 (51.489 sec old) Buffer length: 0.000 sec flange Broadcaster: /robot\_state\_publisher Average rate:  $1\overline{0}000.\overline{00}0$  Hz Most recent transform: 0.000 (51.489 sec old) Buffer length: 0.000 sec tool0 Broadcaster: /robot\_state\_publisher Broadcaster: /robot\_state\_publisher Broadcaster: /robot\_state\_publisher Average rate:  $1\overline{0}000.\overline{00}0$  Hz Average rate:  $1\overline{0}000.\overline{00}0$  Hz Average rate:  $1\overline{0}000.\overline{00}0$  Hz Most recent transform: 0.000 (51.489 sec old) Most recent transform: 0.000 (51.489 sec old) Most recent transform: 0.000 (51.489 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 0.000 sec robotiq\_arg2f\_base\_link tool0\_controller tool\_frame Broadcaster: /robot\_state\_publisher Average rate: 238.558 Hz Broadcaster: /robot\_state\_publisher Average rate: 238.558 Hz Broadcaster: /robot\_state\_publisher Broadcaster: /robot\_state\_publisher Average rate:  $\overline{2}38.5\overline{5}8$  Hz Average rate:  $\overline{2}38.5\overline{5}8$  Hz Most recent transform: 51.480 (0.009 sec old) Buffer length: 2.884 sec Buffer length: 2.884 sec Buffer length: 2.884 sec Buffer length: 2.884 sec left\_outer\_knuckle right\_outer\_knuckle left\_inner\_knuckle right\_inner\_knuckle Broadcaster: /robot state publisher Broadcaster: /robot state publisher Average rate: 10000.000 Hz Average rate:  $1\overline{0}000.\overline{00}0$  Hz Most recent transform: 0.000 (51.489 sec old) Most recent transform: 0.000 (51.489 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec left\_outer\_finger right\_outer\_finger Broadcaster: /robot\_state\_publisher Broadcaster: /robot state publisher Average rate: 238.558 Hz
Most recent transform: 51.480 ( 0.009 sec old) Average rate:  $\bar{2}38.5\bar{5}8$  Hz Most recent transform: 51.480 (0.009 sec old) Buffer length: 2.884 sec Buffer length: 2.884 sec left\_inner\_finger right\_inner\_finger Broadcaster: /robot state publisher Broadcaster: /robot\_state\_publisher Average rate:  $1\overline{0}000.\overline{00}0$  Hz Average rate:  $1\overline{0}000.\overline{00}0$  Hz Most recent transform: 0.000 (51.489 sec old) Most recent transform: 0.000 (51.489 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec left\_inner\_finger\_pad right\_inner\_finger\_pad