view_frames Result Recorded at time: 1437601656.259 odom Broadcaster: /graft Average rate: 50.195 Hz Most recent transform: 1437601656.247 (0.011 sec old) Buffer length: 4.981 sec base_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 25.250 Hz Average rate: 50.200 Hz Average rate: 50.200 Hz Average rate: 50.200 Hz Average rate: 25.250 Hz Average rate: 25.250 Hz Most recent transform: 1437601656.245 (0.014 sec old) Most recent transform: 1437601656.743 (-0.484 sec old) Most recent transform: 1437601656.245 (0.014 sec old) Most recent transform: 1437601656.245 (0.014 sec old) Most recent transform: 1437601656.743 (-0.484 sec old) Most recent transform: 1437601656.743 (-0.484 sec old) Buffer length: 4.980 sec Buffer length: 4.990 sec Buffer length: 4.980 sec Buffer length: 4.980 sec Buffer length: 4.990 sec Buffer length: 4.990 sec torso_lift_link laser_link torso_fixed_link l_wheel_link r_wheel_link estop_link Broadcaster: /robot_state_publisher Average rate: 25.250 Hz Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 25.250 Hz Average rate: 25.250 Hz Average rate: 50.200 Hz Most recent transform: 1437601656.743 (-0.484 sec old) Most recent transform: 1437601656.245 (0.014 sec old) Most recent transform: 1437601656.245 (0.014 sec old) Most recent transform: 1437601656.245 (0.014 sec old) Buffer length: 4.980 sec Buffer length: 4.990 sec Buffer length: 4.990 sec Buffer length: 4.990 sec head_pan_link bellows_link shoulder_pan_link bellows_link2 Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 25.250 Hz Average rate: 25.250 Hz Most recent transform: 1437601656.245 (0.014 sec old) Most recent transform: 1437601656.245 (0.014 sec old) Buffer length: 4.990 sec Buffer length: 4.990 sec head_tilt_link shoulder_lift_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 50.200 Hz Average rate: 25.250 Hz Most recent transform: 1437601656.743 (-0.484 sec old) Most recent transform: 1437601656.245 (0.014 sec old) Buffer length: 4.980 sec Buffer length: 4.990 sec upperarm_roll_link head_camera_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 50.200 Hz Average rate: 25.250 Hz Average rate: 50.200 Hz Most recent transform: 1437601656.743 (-0.484 sec old) Most recent transform: 1437601656.743 (-0.484 sec old) Most recent transform: 1437601656.245 (0.014 sec old) Buffer length: 4.980 sec Buffer length: 4.980 sec Buffer length: 4.990 sec elbow_flex_link head_camera_depth_frame head_camera_rgb_frame Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 50.200 Hz Average rate: 25.250 Hz Average rate: 50.200 Hz Most recent transform: 1437601656.743 (-0.484 sec old) Most recent transform: 1437601656.743 (-0.484 sec old) Most recent transform: 1437601656.245 (0.014 sec old) Buffer length: 4.980 sec Buffer length: 4.980 sec Buffer length: 4.990 sec head_camera_depth_optical_frame head_camera_rgb_optical_frame forearm_roll_link Broadcaster: /robot_state_publisher Average rate: 25.250 Hz Most recent transform: 1437601656.245 (0.014 sec old) Buffer length: 4.990 sec wrist_flex_link Broadcaster: /robot_state_publisher Average rate: 25.250 Hz Most recent transform: 1437601656.245 (0.014 sec old) Buffer length: 4.990 sec wrist_roll_link Broadcaster: /robot_state_publisher Average rate: 50.200 Hz Most recent transform: 1437601656.743 (-0.484 sec old) Buffer length: 4.980 sec gripper_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 39.156 Hz Average rate: 39.156 Hz Most recent transform: 1437601656.257 (0.001 sec old) Most recent transform: 1437601656.257 (0.001 sec old) Buffer length: 4.980 sec Buffer length: 4.980 sec l_gripper_finger_link r_gripper_finger_link