view_frames Result

Recorded at time: 1634940190.601

world

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1634940190.601 sec old)
Buffer length: 0.000 sec

base_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1634940190.601 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 41.872 Hz
Most recent transform: 1634940190.563 (0.038 sec old)
Buffer length: 4.896 sec

base

shoulder_link

Broadcaster: /ur_driver
Average rate: 125.199 Hz
Most recent transform: 1634940190.595 (0.006 sec old)
Buffer length: 4.944 sec

Broadcaster: /robot_state_publisher
Average rate: 41.872 Hz
Most recent transform: 1634940190.563 (0.038 sec old)
Buffer length: 4.896 sec

tool0_controller

upper_arm_link

Broadcaster: /robot_state_publisher
Average rate: 41.872 Hz
Most recent transform: 1634940190.563 (0.038 sec old)
Buffer length: 4.896 sec

forearm_link

Broadcaster: /robot_state_publisher
Average rate: 41.872 Hz
Most recent transform: 1634940190.563 (0.038 sec old)
Buffer length: 4.896 sec

wrist_1_link

Broadcaster: /robot_state_publisher
Average rate: 41.872 Hz
Most recent transform: 1634940190.563 (0.038 sec old)
Buffer length: 4.896 sec

wrist_2_link

Broadcaster: /robot_state_publisher
Average rate: 41.872 Hz
Most recent transform: 1634940190.563 (0.038 sec old)
Buffer length: 4.896 sec

wrist_3_link

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1634940190.601 sec old)
Buffer length: 0.000 sec

Broadcaster: /robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1634940190.601 sec old)
Buffer length: 0.000 sec

ee_link

tool0