Recorded at time: 2171.717 map Broadcaster: /amcl Average rate: 15.142 Hz Most recent transform: 2172.190 (-0.473 sec old) Buffer length: 4.623 sec odom Broadcaster: /gazebo Average rate: 100.214 Hz Most recent transform: 2171.714 (0.003 sec old) Buffer length: 4.670 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: 100.214 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 100.214 Hz Average rate: 100.214 Hz Most recent transform: 2171.713 (0.004 sec old) Most recent transform: 2171.713 (0.004 sec old) Most recent transform: 0.000 (2171.717 sec old) Most recent transform: 0.000 (2171.717 sec old) Most recent transform: 0.000 (2171.717 sec old) Most recent transform: 2171.713 (0.004 sec old) Buffer length: 4.670 sec Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 4.670 sec Buffer length: 0.000 sec Buffer length: 4.670 sec torso_lift_link torso_fixed_link l_wheel_link r_wheel_link estop_link laser_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 100.214 Hz Average rate: 100.214 Hz Average rate: 100.214 Hz Most recent transform: 2171.713 (0.004 sec old) Most recent transform: 0.000 (2171.717 sec old) Most recent transform: 2171.713 (0.004 sec old) Most recent transform: 2171.713 (0.004 sec old) Buffer length: 4.670 sec Buffer length: 0.000 sec Buffer length: 4.670 sec Buffer length: 4.670 sec bellows_link shoulder_pan_link bellows_link2 head_pan_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 100.214 Hz Average rate: 100.214 Hz Most recent transform: 2171.713 (0.004 sec old) Most recent transform: 2171.713 (0.004 sec old) Buffer length: 4.670 sec Buffer length: 4.670 sec head_tilt_link shoulder_lift_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 100.214 Hz Most recent transform: 0.000 (2171.717 sec old) Most recent transform: 2171.713 (0.004 sec old) Buffer length: 0.000 sec Buffer length: 4.670 sec upperarm_roll_link head_camera_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 100.214 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (2171.717 sec old) Most recent transform: 0.000 (2171.717 sec old) Most recent transform: 2171.713 (0.004 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 4.670 sec head_camera_depth_frame head_camera_rgb_frame elbow_flex_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 100.214 Hz Average rate: 10000.000 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (2171.717 sec old) Most recent transform: 2171.713 (0.004 sec old) Most recent transform: 0.000 (2171.717 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec Buffer length: 4.670 sec head_camera_depth_optical_frame head_camera_rgb_optical_frame forearm_roll_link Broadcaster: /robot_state_publisher Average rate: 100.214 Hz Most recent transform: 2171.713 (0.004 sec old) Buffer length: 4.670 sec wrist_flex_link Broadcaster: /robot_state_publisher Average rate: 100.214 Hz Most recent transform: 2171.713 (0.004 sec old) Buffer length: 4.670 sec wrist_roll_link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (2171.717 sec old) Buffer length: 0.000 sec gripper_link Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 100.214 Hz Average rate: 100.214 Hz Most recent transform: 2171.713 (0.004 sec old) Most recent transform: 2171.713 (0.004 sec old) Buffer length: 4.670 sec Buffer length: 4.670 sec l_gripper_finger_link r_gripper_finger_link

view_frames Result