world
xyz: 0 0 0
rpy: 0 -0 0
world_platform_joint
platform_base
xyz: 0 0.53 0.095
rpy: 0 -0 0
xyz: 0 0.53 0.455
rpy: 0 -0 0
xyz: -0.31 0.13 1.455
rpy: 0 -0 0
xyz: -0.31 0.285 1.305
rpy: -0.523599 0 0
xyz: -0.31 0.55 0.975
rpy: 1.5708 -0 0
xyz: 0.155 0 0.095
rpy: 0 -0 0
xyz: 0.155 0 0.455
rpy: 0 -0 0
xyz: -0.155 0 0.095
rpy: 0 -0 0
xyz: -0.155 0 0.455
rpy: 0 -0 0
xyz: 0 -0.53 0.095
rpy: 0 -0 0
xyz: 0 -0.53 0.455
rpy: 0 -0 0
xyz: 0.31 0 0.095
rpy: 0 -0 0
xyz: 0.31 0 0.455
rpy: 0 -0 0
xyz: 0 0 0.095
rpy: 0 -0 0
xyz: 0 0 0.455
rpy: 0 -0 0
xyz: -0.31 0 0.095
rpy: 0 -0 0
xyz: -0.31 0 0.455
rpy: 0 -0 0
xyz: 0.31 0.53 0.275
rpy: 0 -0 0
xyz: -0.31 0.53 0.275
rpy: 0 -0 0
xyz: 0.31 -0.53 0.275
rpy: 0 -0 0
xyz: -0.31 -0.53 0.275
rpy: 0 -0 0
xyz: 0 0.225 0.275
rpy: 0 -0 0
xyz: 0 0.225 0.55
rpy: 0 -0 0
xyz: 0 -0.27 0.5
rpy: 0 -0 0
platform_base_beam_back_bottom_joint
platform_base_beam_back_top_joint
platform_base_beam_camera_horizontal_joint
platform_base_beam_camera_tilt_joint
platform_base_beam_camera_vertical_joint
platform_base_beam_connect_left_bottom_joint
platform_base_beam_connect_left_top_joint
platform_base_beam_connect_right_bottom_joint
platform_base_beam_connect_right_top_joint
platform_base_beam_front_bottom_joint
platform_base_beam_front_top_joint
platform_base_beam_left_bottom_joint
platform_base_beam_left_top_joint
platform_base_beam_middle_bottom_joint
platform_base_beam_middle_top_joint
platform_base_beam_right_bottom_joint
platform_base_beam_right_top_joint
platform_base_beam_support_back_left_joint
platform_base_beam_support_back_right_joint
platform_base_beam_support_front_left_joint
platform_base_beam_support_front_right_joint
platform_base_beam_support_robot_bottom_joint
platform_base_beam_support_robot_top_joint
platform_base_operation_surface_joint
beam_back_bottom
beam_back_top
beam_camera_horizontal
beam_camera_tilt
beam_camera_vertical
beam_connect_left_bottom
beam_connect_left_top
beam_connect_right_bottom
beam_connect_right_top
beam_front_bottom
beam_front_top
beam_left_bottom
beam_left_top
beam_middle_bottom
beam_middle_top
beam_right_bottom
beam_right_top
beam_support_back_left
beam_support_back_right
beam_support_front_left
beam_support_front_right
beam_support_robot_bottom
beam_support_robot_top
operation_surface
xyz: 0 0 0.0825
rpy: 0 -0 0
platform_base_robot_install_plate_joint
robot_install_plate
xyz: 0 0 0.0075
rpy: 0 -0 -3.14159
platform_base_link_joint
base_link
xyz: 0 0 0
rpy: 0 0 3.14159
xyz: 0 0 0.089159
rpy: 0 -0 0
base_link-base_fixed_joint
shoulder_pan_joint
base
shoulder_link
xyz: 0 0.13585 0
rpy: 0 1.5708 -0
shoulder_lift_joint
upper_arm_link
xyz: 0 -0.1197 0.425
rpy: 0 -0 0
elbow_joint
forearm_link
xyz: 0 0 0.39225
rpy: 0 1.5708 -0
wrist_1_joint
wrist_1_link
xyz: 0 0.093 0
rpy: 0 -0 0
wrist_2_joint
wrist_2_link
xyz: 0 0 0.09465
rpy: 0 -0 0
wrist_3_joint
wrist_3_link
xyz: 0 0.0823 0
rpy: 0 -0 1.5708
xyz: 0 0.0823 0
rpy: -1.5708 0 0
ee_fixed_joint
wrist_3_link-tool0_fixed_joint
ee_link
tool0
xyz: 0 0 0
rpy: 0 -0 0.785398
tool0_hitbot_joint
hitbot_base
xyz: 0 -0.01 0.114
rpy: 0 -0 0
xyz: 0 0.004 0.114
rpy: 0 -0 0
xyz: 0 0 0.006
rpy: 0 -0 0
hitbot_base_finger0_joint
hitbot_base_finger1_joint
hitbot_base_mask_joint
hitbot_finger0
hitbot_finger1
hitbot_mask
xyz: 0 0 0.01
rpy: -1.5708 -1.26218e-29 -3.14159
xyz: 0 0.0055 0.01
rpy: -1.5708 0 0
hitbot_finger0_tip_joint
hitbot_finger1_tip_joint
hitbot_finger0_tip
hitbot_finger1_tip