view_frames Result Recorded at time: 1600929865.021 world Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1600929865.021 sec old) Buffer length: 0.000 sec elfin_base_link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1600929865.021 sec old) Buffer length: 0.000 sec elfin_base Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1600929864.991 (0.029 sec old) Buffer length: 4.900 sec elfin_link1 Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1600929864.991 (0.029 sec old) Buffer length: 4.900 sec elfin_link2 Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1600929864.991 (0.029 sec old) Buffer length: 4.900 sec elfin_link3 Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1600929864.991 (0.029 sec old) Buffer length: 4.900 sec elfin_link4 Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1600929864.991 (0.029 sec old) Buffer length: 4.900 sec elfin_link5 Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Most recent transform: 1600929864.991 (0.029 sec old) Buffer length: 4.900 sec elfin_link6 Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Most recent transform: 0.000 (1600929865.021 sec old) Most recent transform: 0.000 (1600929865.021 sec old) Buffer length: 0.000 sec Buffer length: 0.000 sec elfin_dummy_gripper elfin_end_link Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Most recent transform: 0.000 (1600929865.021 sec old) Buffer length: 0.000 sec robotiq_palm Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10000.000 Hz Average rate: 10000.000 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 0.000 (1600929865.021 sec old) Most recent transform: 0.000 (1600929865.021 sec old) Most recent transform: 1600929864.991 (0.029 sec old) Most recent transform: 1600929864.991 (0.029 sec old) Buffer length: 0.000 sec Buffer length: 4.900 sec Buffer length: 0.000 sec Buffer length: 4.900 sec robotiq_finger_1_link_0 robotiq_finger_middle_link_0 robotiq_tool0 robotiq_finger_2_link_0 Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 1600929864.991 (0.029 sec old) Most recent transform: 1600929864.991 (0.029 sec old) Most recent transform: 1600929864.991 (0.029 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec robotiq_finger_middle_link_1 robotiq_finger_1_link_1 robotiq_finger_2_link_1 Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 1600929864.991 (0.029 sec old) Most recent transform: 1600929864.991 (0.029 sec old) Most recent transform: 1600929864.991 (0.029 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec robotiq_finger_middle_link_2 robotiq_finger_1_link_2 robotiq_finger_2_link_2 Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Broadcaster: /robot_state_publisher Average rate: 10.204 Hz Average rate: 10.204 Hz Average rate: 10.204 Hz Most recent transform: 1600929864.991 (0.029 sec old) Most recent transform: 1600929864.991 (0.029 sec old) Most recent transform: 1600929864.991 (0.029 sec old) Buffer length: 4.900 sec Buffer length: 4.900 sec Buffer length: 4.900 sec robotiq_finger_2_link_3 robotiq_finger_middle_link_3 robotiq_finger_1_link_3