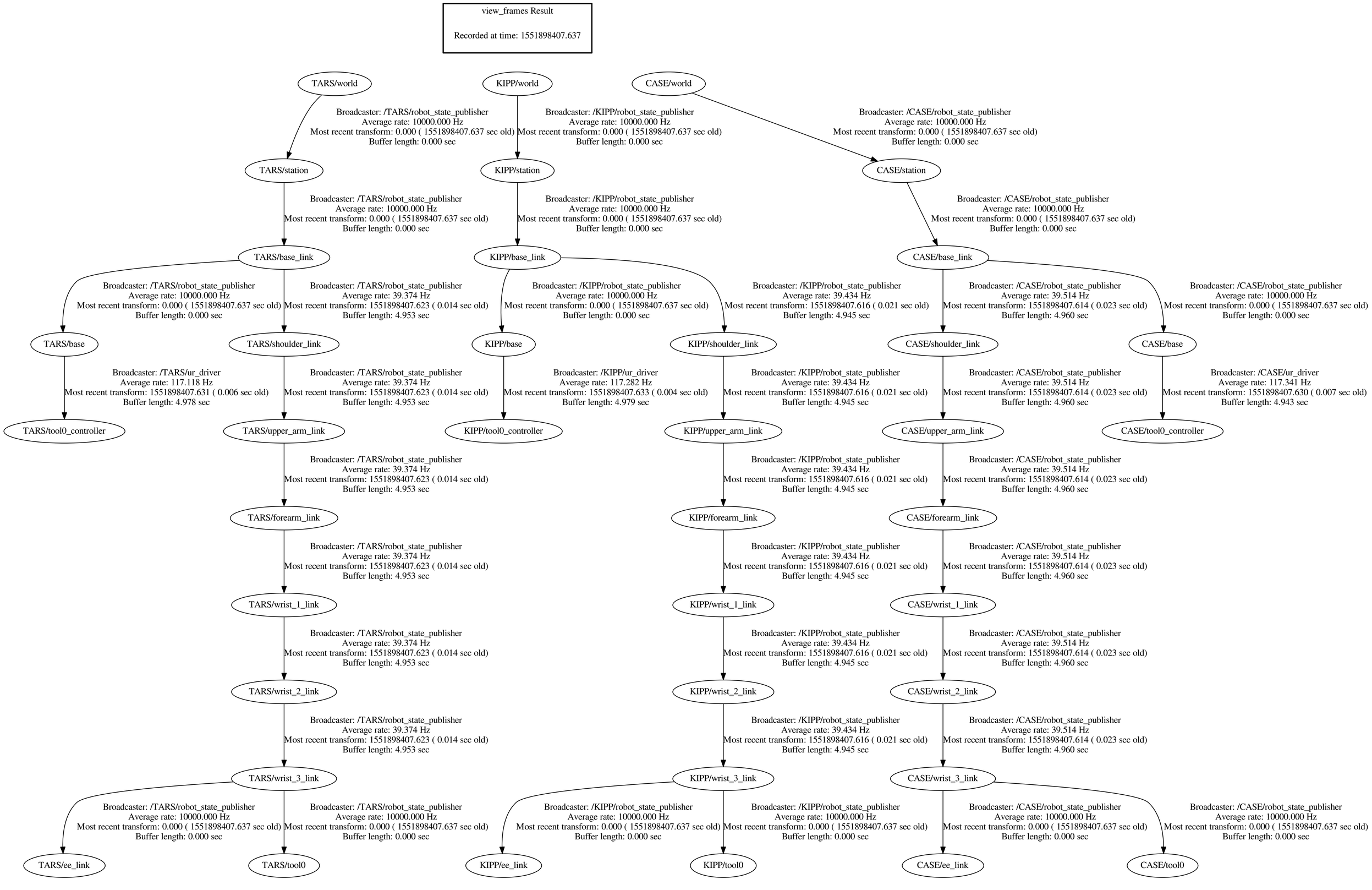
view_frames Result
Recorded at time: 1551898407.637
TARS/world
KIPP/world
CASE/world
Broadcaster: /TARS/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
TARS/station
KIPP/station
CASE/station
Broadcaster: /TARS/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
TARS/base_link
KIPP/base_link
CASE/base_link
Broadcaster: /TARS/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /TARS/robot_state_publisher
Average rate: 39.374 Hz
Most recent transform: 1551898407.623 (0.014 sec old)
Buffer length: 4.953 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 39.434 Hz
Most recent transform: 1551898407.616 (0.021 sec old)
Buffer length: 4.945 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 39.514 Hz
Most recent transform: 1551898407.614 (0.023 sec old)
Buffer length: 4.960 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
TARS/base
TARS/shoulder_link
KIPP/base
KIPP/shoulder_link
CASE/shoulder_link
CASE/base
Broadcaster: /TARS/ur_driver
Average rate: 117.118 Hz
Most recent transform: 1551898407.631 (0.006 sec old)
Buffer length: 4.978 sec
Broadcaster: /TARS/robot_state_publisher
Average rate: 39.374 Hz
Most recent transform: 1551898407.623 (0.014 sec old)
Buffer length: 4.953 sec
Broadcaster: /KIPP/ur_driver
Average rate: 117.282 Hz
Most recent transform: 1551898407.633 (0.004 sec old)
Buffer length: 4.979 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 39.434 Hz
Most recent transform: 1551898407.616 (0.021 sec old)
Buffer length: 4.945 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 39.514 Hz
Most recent transform: 1551898407.614 (0.023 sec old)
Buffer length: 4.960 sec
Broadcaster: /CASE/ur_driver
Average rate: 117.341 Hz
Most recent transform: 1551898407.630 (0.007 sec old)
Buffer length: 4.943 sec
TARS/tool0_controller
TARS/upper_arm_link
KIPP/tool0_controller
KIPP/upper_arm_link
CASE/upper_arm_link
CASE/tool0_controller
Broadcaster: /TARS/robot_state_publisher
Average rate: 39.374 Hz
Most recent transform: 1551898407.623 (0.014 sec old)
Buffer length: 4.953 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 39.434 Hz
Most recent transform: 1551898407.616 (0.021 sec old)
Buffer length: 4.945 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 39.514 Hz
Most recent transform: 1551898407.614 (0.023 sec old)
Buffer length: 4.960 sec
TARS/forearm_link
KIPP/forearm_link
CASE/forearm_link
Broadcaster: /TARS/robot_state_publisher
Average rate: 39.374 Hz
Most recent transform: 1551898407.623 (0.014 sec old)
Buffer length: 4.953 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 39.434 Hz
Most recent transform: 1551898407.616 (0.021 sec old)
Buffer length: 4.945 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 39.514 Hz
Most recent transform: 1551898407.614 (0.023 sec old)
Buffer length: 4.960 sec
TARS/wrist_1_link
KIPP/wrist_1_link
CASE/wrist_1_link
Broadcaster: /TARS/robot_state_publisher
Average rate: 39.374 Hz
Most recent transform: 1551898407.623 (0.014 sec old)
Buffer length: 4.953 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 39.434 Hz
Most recent transform: 1551898407.616 (0.021 sec old)
Buffer length: 4.945 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 39.514 Hz
Most recent transform: 1551898407.614 (0.023 sec old)
Buffer length: 4.960 sec
TARS/wrist_2_link
KIPP/wrist_2_link
CASE/wrist_2_link
Broadcaster: /TARS/robot_state_publisher
Average rate: 39.374 Hz
Most recent transform: 1551898407.623 (0.014 sec old)
Buffer length: 4.953 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 39.434 Hz
Most recent transform: 1551898407.616 (0.021 sec old)
Buffer length: 4.945 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 39.514 Hz
Most recent transform: 1551898407.614 (0.023 sec old)
Buffer length: 4.960 sec
TARS/wrist_3_link
KIPP/wrist_3_link
CASE/wrist_3_link
Broadcaster: /TARS/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /TARS/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /KIPP/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
Broadcaster: /CASE/robot_state_publisher
Average rate: 10000.000 Hz
Most recent transform: 0.000 (1551898407.637 sec old)
Buffer length: 0.000 sec
TARS/ee_link
TARS/tool0
KIPP/ee_link
KIPP/tool0
CASE/ee_link
CASE/tool0