

world

xyz: 0 0 0  
rpy: 0 -0 0

world\_fixed

link1

xyz: 0 0 0.126  
rpy: 0 -0 0

joint1

link2

xyz: 0 0.069 0.033  
rpy: 0 -0 0

joint2

link3

xyz: 0.03 -0.0115 0.264  
rpy: 0 -0 0

joint3

link4

xyz: 0.195 -0.0575 0.03  
rpy: 0 -0 0

joint4

link5

xyz: 0.063 0.045 0  
rpy: 0 -0 0

joint5

link6

xyz: 0.123 -0.045 0  
rpy: 0 -0 0

joint6

end\_link

xyz: 0.007 0 0  
rpy: 0 -0 0

end\_link\_fixed

gripper\_main\_link

xyz: 0.07 0.032 0.052  
rpy: 0 -0 0

xyz: 0.14 0 0  
rpy: 0 -0 0

xyz: 0.0552 -0.04 0  
rpy: 0 0 -0.4

xyz: 0.0552 0.04 0  
rpy: 0 -0 0.4

camera\_joint

end\_effector\_joint

gripper

gripper\_sub

camera\_link

end\_effector\_link

gripper\_link

gripper\_sub\_link