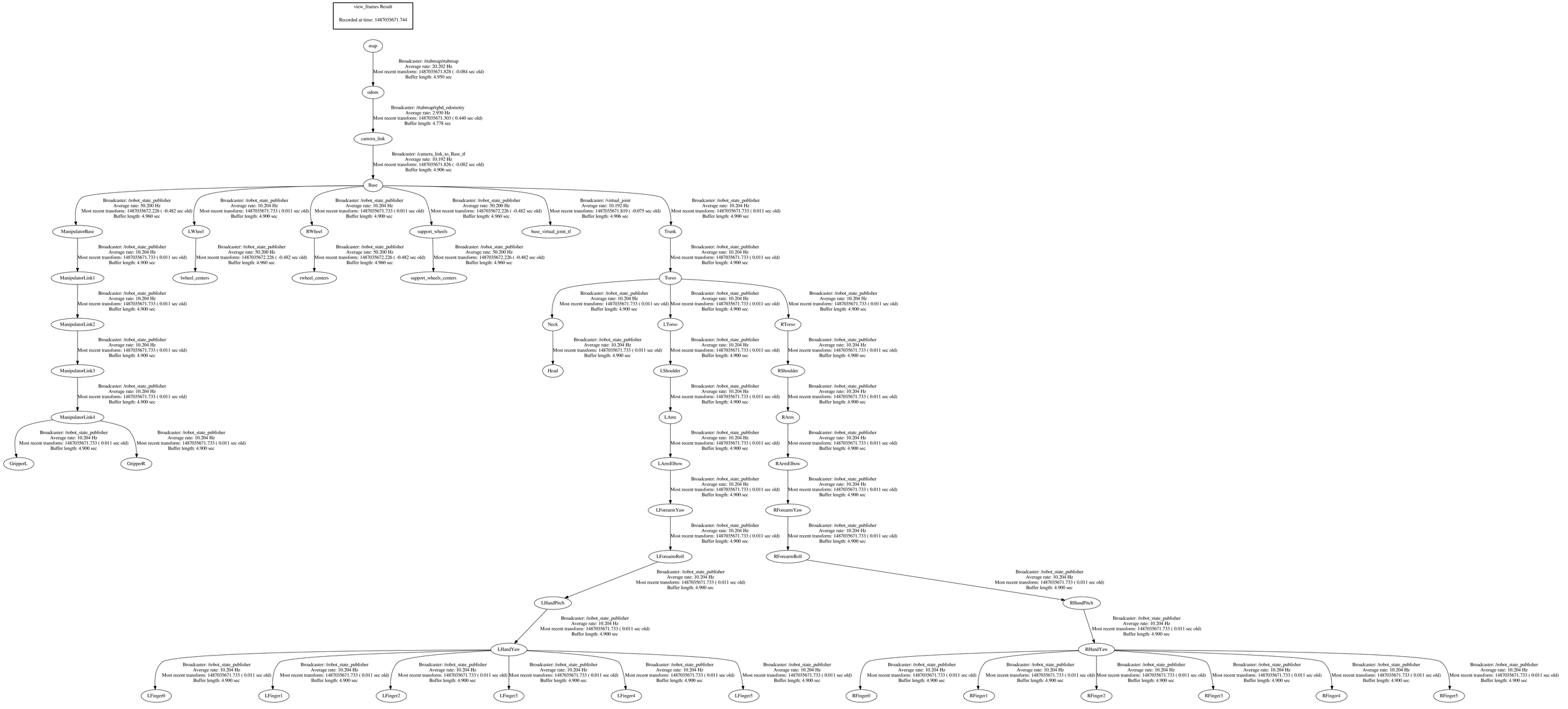
view_frames Result
Recorded at time: 1487035671.744
map
Broadcaster: /rtabmap/rtabmap
Average rate: 20.202 Hz
Most recent transform: 1487035671.826 (-0.084 sec old)
Buffer length: 4.950 sec
odom
Broadcaster: /rtabmap/rgbd_odometry
Average rate: 2.930 Hz
Most recent transform: 1487035671.303 (0.440 sec old)
Buffer length: 4.778 sec
camera_link
Broadcaster: /camera_link_to_Base_tf
Average rate: 10.192 Hz
Most recent transform: 1487035671.826 (-0.082 sec old)
Buffer length: 4.906 sec
Base
Broadcaster: /robot_state_publisher
Average rate: 50.200 Hz
Most recent transform: 1487035672.226 (-0.482 sec old)
Buffer length: 4.960 sec
ManipulatorBase
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
ManipulatorLink1
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
ManipulatorLink2
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
ManipulatorLink3
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
ManipulatorLink4
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
GripperL
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
GripperR
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LWheel
Broadcaster: /robot_state_publisher
Average rate: 50.200 Hz
Most recent transform: 1487035672.226 (-0.482 sec old)
Buffer length: 4.960 sec
lwheel_centers
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RWheel
Broadcaster: /robot_state_publisher
Average rate: 50.200 Hz
Most recent transform: 1487035672.226 (-0.482 sec old)
Buffer length: 4.960 sec
rwheel_centers
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
support_wheels
Broadcaster: /robot_state_publisher
Average rate: 50.200 Hz
Most recent transform: 1487035672.226 (-0.482 sec old)
Buffer length: 4.960 sec
support_wheels_centers
Broadcaster: /robot_state_publisher
Average rate: 50.200 Hz
Most recent transform: 1487035672.226 (-0.482 sec old)
Buffer length: 4.960 sec
base_virtual_joint_tf
Broadcaster: /virtual_joint
Average rate: 10.192 Hz
Most recent transform: 1487035671.819 (-0.075 sec old)
Buffer length: 4.906 sec
Trunk
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
Torso
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
Neck
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
Head
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LTorso
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LShoulder
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LArm
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LArmElbow
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LForearmYaw
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LForearmRoll
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LHandPitch
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LHandYaw
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LFinger0
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LFinger1
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LFinger2
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LFinger3
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LFinger4
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
LFinger5
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RTorso
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RShoulder
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RArm
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RArmElbow
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RForearmYaw
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RForearmRoll
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RHandPitch
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RHandYaw
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RFinger0
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RFinger1
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RFinger2
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RFinger3
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RFinger4
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec
RFinger5
Broadcaster: /robot_state_publisher
Average rate: 10.204 Hz
Most recent transform: 1487035671.733 (0.011 sec old)
Buffer length: 4.900 sec