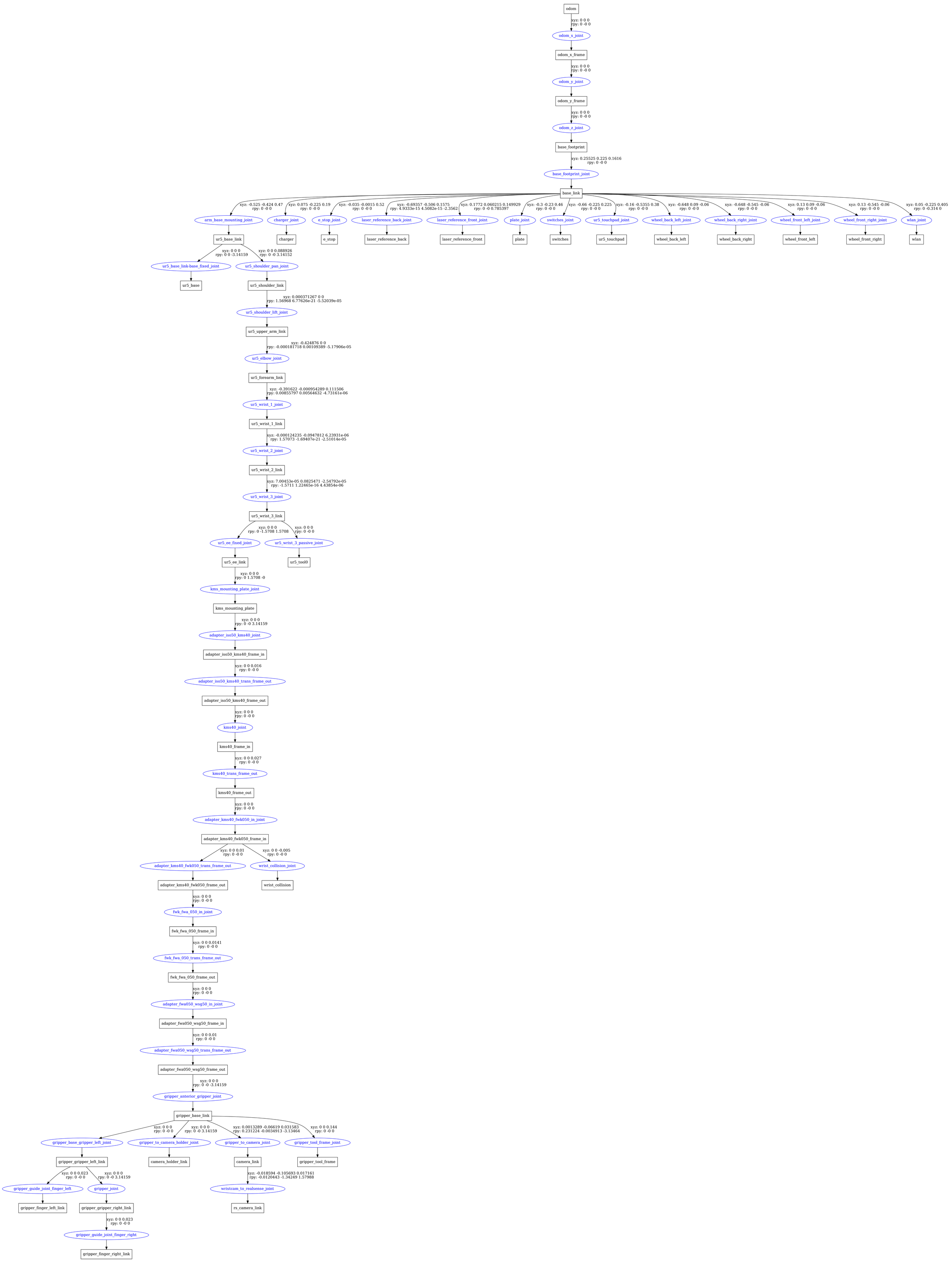
odom
xyz: 0 0 0
rpy: 0 -0 0
odom_x_joint
odom_x_frame
xyz: 0 0 0
rpy: 0 -0 0
odom_y_joint
odom_y_frame
xyz: 0 0 0
rpy: 0 -0 0
odom_z_joint
base_footprint
xyz: 0.25525 0.225 0.1616
rpy: 0 -0 0
base_footprint_joint
base_link
xyz: -0.525 -0.424 0.47
rpy: 0 -0 0
arm_base_mounting_joint
ur5_base_link
xyz: 0 0 0
rpy: 0 0 -3.14159
ur5_base_link-base_fixed_joint
ur5_base
xyz: 0 0 0.088926
rpy: 0 -0 3.14152
ur5_shoulder_pan_joint
ur5_shoulder_link
xyz: 0.000371267 0 0
rpy: 1.56968 6.77626e-21 -5.52039e-05
ur5_shoulder_lift_joint
ur5_upper_arm_link
xyz: -0.424876 0 0
rpy: -0.000181718 0.00109389 -5.17906e-05
ur5_elbow_joint
ur5_forearm_link
xyz: -0.391622 -0.000954289 0.111506
rpy: 0.00855797 0.00564632 -4.73161e-06
ur5_wrist_1_joint
ur5_wrist_1_link
xyz: -0.000124235 -0.0947812 6.23931e-06
rpy: 1.57073 -1.69407e-21 -2.51014e-05
ur5_wrist_2_joint
ur5_wrist_2_link
xyz: 7.00453e-05 0.0825471 -2.54792e-05
rpy: -1.5711 1.22465e-16 4.43854e-06
ur5_wrist_3_joint
ur5_wrist_3_link
xyz: 0 0 0
rpy: 0 -1.5708 1.5708
ur5_ee_fixed_joint
ur5_ee_link
xyz: 0 0 0
rpy: 0 1.5708 -0
kms_mounting_plate_joint
kms_mounting_plate
xyz: 0 0 0
rpy: 0 -0 3.14159
adapter_iso50_kms40_joint
adapter_iso50_kms40_frame_in
xyz: 0 0 0.016
rpy: 0 -0 0
adapter_iso50_kms40_trans_frame_out
adapter_iso50_kms40_frame_out
xyz: 0 0 0
rpy: 0 -0 0
kms40_joint
kms40_frame_in
xyz: 0 0 0.027
rpy: 0 -0 0
kms40_trans_frame_out
kms40_frame_out
xyz: 0 0 0
rpy: 0 -0 0
adapter_kms40_fwk050_in_joint
adapter_kms40_fwk050_frame_in
xyz: 0 0 0.01
rpy: 0 -0 0
adapter_kms40_fwk050_trans_frame_out
adapter_kms40_fwk050_frame_out
xyz: 0 0 0
rpy: 0 -0 0
fwk_fwa_050_in_joint
fwk_fwa_050_frame_in
xyz: 0 0 0.0141
rpy: 0 -0 0
fwk_fwa_050_trans_frame_out
fwk_fwa_050_frame_out
xyz: 0 0 0
rpy: 0 -0 0
adapter_fwa050_wsg50_in_joint
adapter_fwa050_wsg50_frame_in
xyz: 0 0 0.01
rpy: 0 -0 0
adapter_fwa050_wsg50_trans_frame_out
adapter_fwa050_wsg50_frame_out
xyz: 0 0 0
rpy: 0 -0 -3.14159
gripper_anterior_gripper_joint
gripper_base_link
xyz: 0 0 0
rpy: 0 -0 0
gripper_base_gripper_left_joint
gripper_gripper_left_link
xyz: 0 0 0.023
rpy: 0 -0 0
gripper_guide_joint_finger_left
gripper_finger_left_link
xyz: 0 0 0
rpy: 0 -0 3.14159
gripper_joint
gripper_gripper_right_link
xyz: 0 0 0.023
rpy: 0 -0 0
gripper_guide_joint_finger_right
gripper_finger_right_link
xyz: 0 0 0
rpy: 0 -0 3.14159
gripper_to_camera_holder_joint
camera_holder_link
xyz: 0.0013289 -0.06619 0.031583
rpy: 0.231224 -0.0034913 -3.13464
gripper_to_camera_joint
camera_link
xyz: -0.018594 -0.105693 0.017161
rpy: -0.0120443 -1.34249 1.57988
wristcam_to_realsense_joint
rs_camera_link
xyz: 0 0 0.144
rpy: 0 -0 0
gripper_tool_frame_joint
gripper_tool_frame
xyz: 0.075 -0.225 0.19
rpy: 0 -0 0
charger_joint
charger
xyz: -0.035 -0.0015 0.52
rpy: 0 -0 0
e_stop_joint
e_stop
xyz: -0.69357 -0.506 0.1575
rpy: 4.9333e-15 4.5082e-15 -2.3562
laser_reference_back_joint
laser_reference_back
xyz: 0.1772 0.060215 0.149929
rpy: 0 -0 0.785397
laser_reference_front_joint
laser_reference_front
xyz: -0.3 -0.23 0.46
rpy: 0 -0 0
plate_joint
plate
xyz: -0.66 -0.225 0.225
rpy: 0 -0 0
switches_joint
switches
xyz: -0.16 -0.5355 0.38
rpy: 0 -0 0
ur5_touchpad_joint
ur5_touchpad
xyz: -0.648 0.09 -0.06
rpy: 0 -0 0
wheel_back_left_joint
wheel_back_left
xyz: -0.648 -0.545 -0.06
rpy: 0 -0 0
wheel_back_right_joint
wheel_back_right
xyz: 0.13 0.09 -0.06
rpy: 0 -0 0
wheel_front_left_joint
wheel_front_left
xyz: 0.13 -0.545 -0.06
rpy: 0 -0 0
wheel_front_right_joint
wheel_front_right
xyz: 0.05 -0.225 0.405
rpy: 0 -0.314 0
wlan_joint
wlan