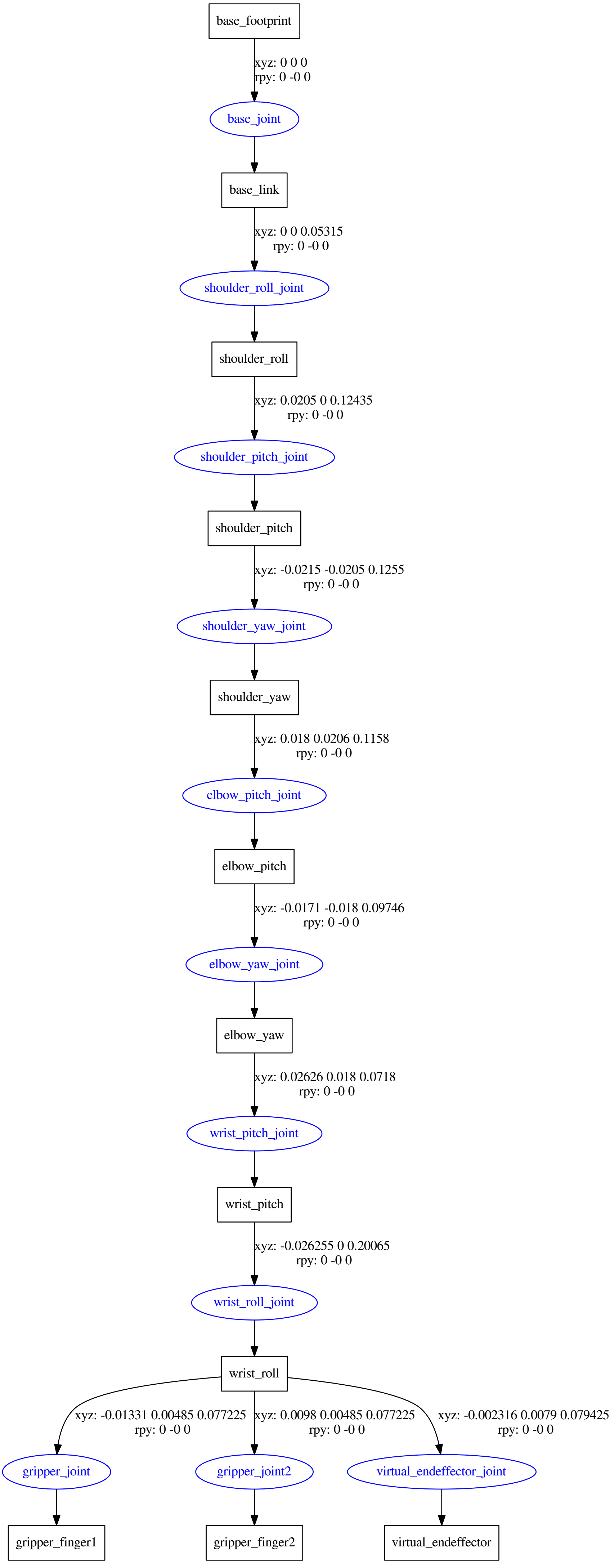
base_footprint
xyz: 0 0 0
rpy: 0 -0 0
base_joint
base_link
xyz: 0 0 0.05315
rpy: 0 -0 0
shoulder_roll_joint
shoulder_roll
xyz: 0.0205 0 0.12435
rpy: 0 -0 0
shoulder_pitch_joint
shoulder_pitch
xyz: -0.0215 -0.0205 0.1255
rpy: 0 -0 0
shoulder_yaw_joint
shoulder_yaw
xyz: 0.018 0.0206 0.1158
rpy: 0 -0 0
elbow_pitch_joint
elbow_pitch
xyz: -0.0171 -0.018 0.09746
rpy: 0 -0 0
elbow_yaw_joint
elbow_yaw
xyz: 0.02626 0.018 0.0718
rpy: 0 -0 0
wrist_pitch_joint
wrist_pitch
xyz: -0.026255 0 0.20065
rpy: 0 -0 0
wrist_roll_joint
wrist_roll
xyz: -0.01331 0.00485 0.077225
rpy: 0 -0 0
xyz: 0.0098 0.00485 0.077225
rpy: 0 -0 0
xyz: -0.002316 0.0079 0.079425
rpy: 0 -0 0
gripper_joint
gripper_joint2
virtual_endeffector_joint
gripper_finger1
gripper_finger2
virtual_endeffector