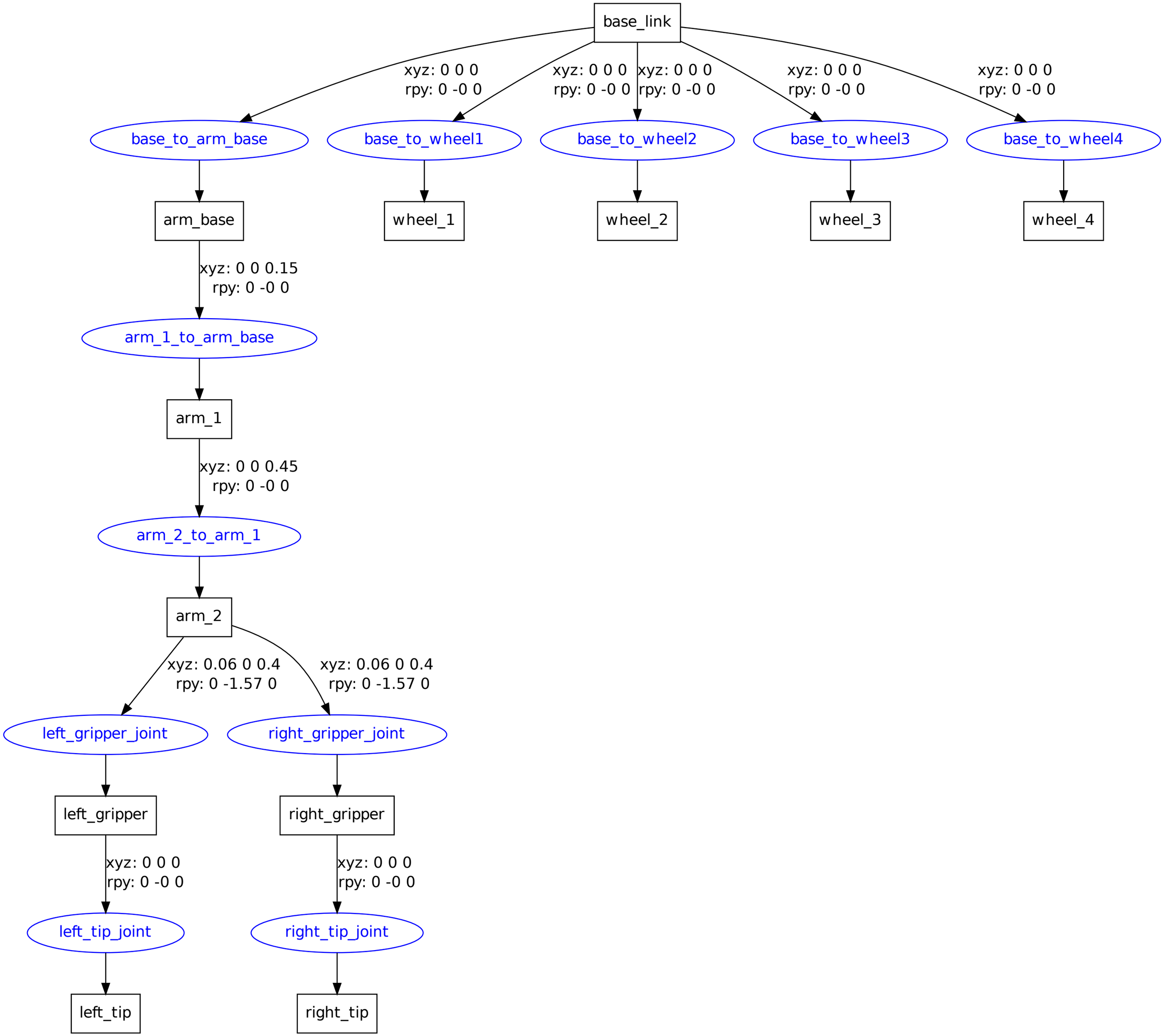
base_link
xyz: 0 0 0
rpy: 0 -0 0
xyz: 0 0 0
rpy: 0 -0 0
xyz: 0 0 0
rpy: 0 -0 0
xyz: 0 0 0
rpy: 0 -0 0
xyz: 0 0 0
rpy: 0 -0 0
base_to_arm_base
base_to_wheel1
base_to_wheel2
base_to_wheel3
base_to_wheel4
arm_base
wheel_1
wheel_2
wheel_3
wheel_4
xyz: 0 0 0.15
rpy: 0 -0 0
arm_1_to_arm_base
arm_1
xyz: 0 0 0.45
rpy: 0 -0 0
arm_2_to_arm_1
arm_2
xyz: 0.06 0 0.4
rpy: 0 -1.57 0
xyz: 0.06 0 0.4
rpy: 0 -1.57 0
left_gripper_joint
right_gripper_joint
left_gripper
right_gripper
xyz: 0 0 0
rpy: 0 -0 0
xyz: 0 0 0
rpy: 0 -0 0
left_tip_joint
right_tip_joint
left_tip
right_tip