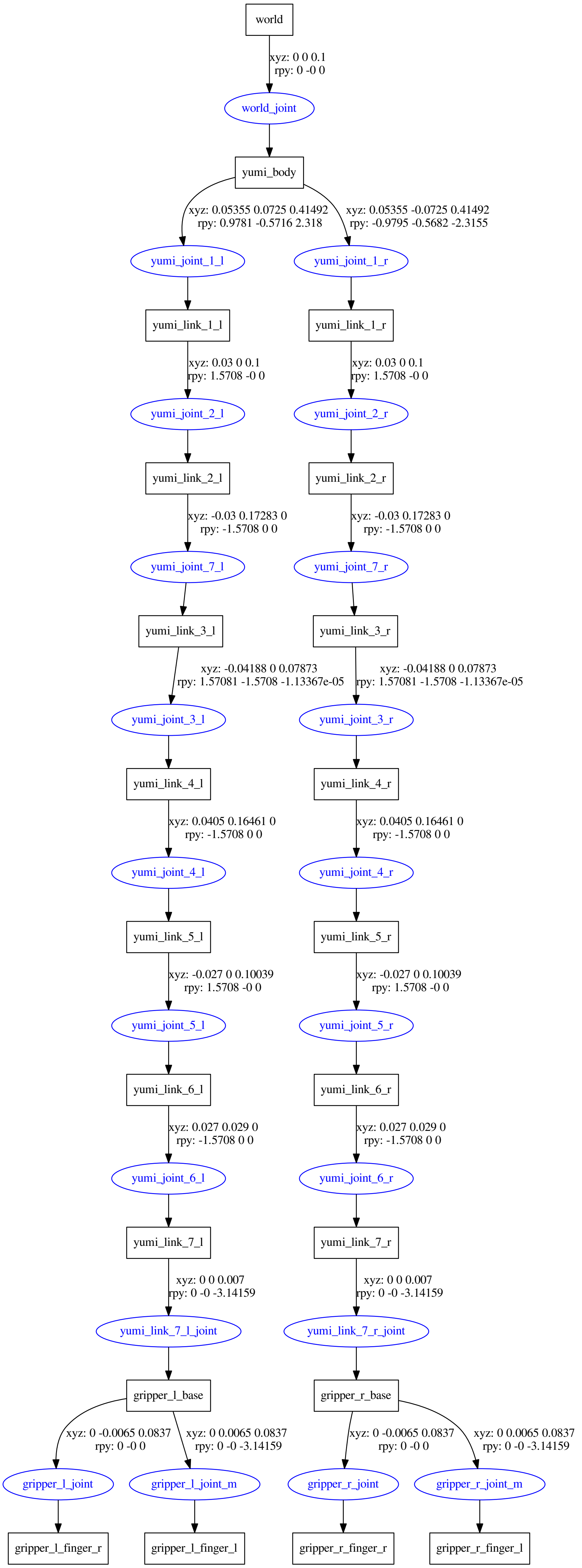
world
xyz: 0 0 0.1
rpy: 0 -0 0
world_joint
yumi_body
xyz: 0.05355 0.0725 0.41492
rpy: 0.9781 -0.5716 2.318
xyz: 0.05355 -0.0725 0.41492
rpy: -0.9795 -0.5682 -2.3155
yumi_joint_1_l
yumi_joint_1_r
yumi_link_1_l
yumi_link_1_r
xyz: 0.03 0 0.1
rpy: 1.5708 -0 0
xyz: 0.03 0 0.1
rpy: 1.5708 -0 0
yumi_joint_2_l
yumi_joint_2_r
yumi_link_2_l
yumi_link_2_r
xyz: -0.03 0.17283 0
rpy: -1.5708 0 0
xyz: -0.03 0.17283 0
rpy: -1.5708 0 0
yumi_joint_7_l
yumi_joint_7_r
yumi_link_3_l
yumi_link_3_r
xyz: -0.04188 0 0.07873
rpy: 1.57081 -1.5708 -1.13367e-05
xyz: -0.04188 0 0.07873
rpy: 1.57081 -1.5708 -1.13367e-05
yumi_joint_3_l
yumi_joint_3_r
yumi_link_4_l
yumi_link_4_r
xyz: 0.0405 0.16461 0
rpy: -1.5708 0 0
xyz: 0.0405 0.16461 0
rpy: -1.5708 0 0
yumi_joint_4_l
yumi_joint_4_r
yumi_link_5_l
yumi_link_5_r
xyz: -0.027 0 0.10039
rpy: 1.5708 -0 0
xyz: -0.027 0 0.10039
rpy: 1.5708 -0 0
yumi_joint_5_l
yumi_joint_5_r
yumi_link_6_l
yumi_link_6_r
xyz: 0.027 0.029 0
rpy: -1.5708 0 0
xyz: 0.027 0.029 0
rpy: -1.5708 0 0
yumi_joint_6_l
yumi_joint_6_r
yumi_link_7_l
yumi_link_7_r
xyz: 0 0 0.007
rpy: 0 -0 -3.14159
xyz: 0 0 0.007
rpy: 0 -0 -3.14159
yumi_link_7_l_joint
yumi_link_7_r_joint
gripper_l_base
gripper_r_base
xyz: 0 -0.0065 0.0837
rpy: 0 -0 0
xyz: 0 0.0065 0.0837
rpy: 0 -0 -3.14159
xyz: 0 -0.0065 0.0837
rpy: 0 -0 0
xyz: 0 0.0065 0.0837
rpy: 0 -0 -3.14159
gripper_l_joint
gripper_l_joint_m
gripper_r_joint
gripper_r_joint_m
gripper_l_finger_r
gripper_l_finger_l
gripper_r_finger_r
gripper_r_finger_l