

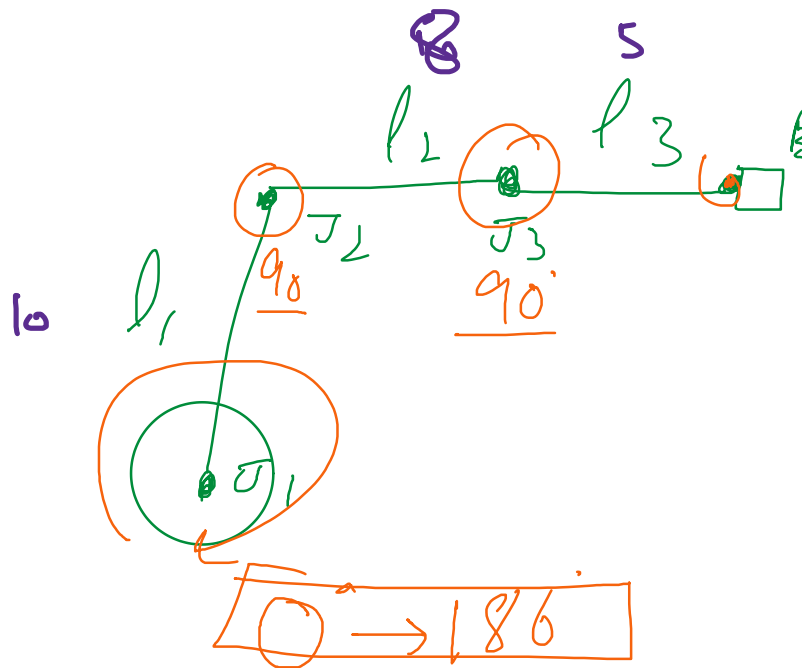
# Custom Robotic Arm

## Design into URDF

Tuesday, 23 September 2025 10:47 AM

### Questions ?

- Type of arm  
Serial
- Degree of freedoms  
3
- Joint Types  
Revolute S, e
- Links Lengths  
10, 8, 5
- Total Reachable Space



```
<mass value="2.0"/>
<inertia ixx="0.107" ixy="0.0" ixz="0.0" iyy="0.107" iyz="0.0" izx="0.0" izy="0.0" izz="0.107"/>
</inertia>
</link>

<joint name="joint_1" type="continuous">
  <axis xyz="0 0 1"/>
  <parent link="base_link"/>
  <child link="link_1"/>
  <origin rpy="0 0 0" xyz="0.0 0.0 0.05"/>
</joint>

<link name="link_2">
  <inertia>
    <origin rpy="0 0 0" xyz="0 0 0.2"/>
    <mass value="2.0"/>
    <inertia ixx="0.027" ixy="0.0" ixz="0.0" iyy="0.027" iyz="0.0" izx="0.0" izy="0.0" izz="0.027"/>
  </inertia>
  <visual>
    <geometry>
      <cylinder length="0.1" radius="0.08"/>
    </geometry>
    <material name="Red">
```

