Documentation for Solidworks to Mujoco:

1. Exporting from Solidworks using SW2URDF:
   1. Download SW2URDF
      1. Repo:
   2. Be careful about:
      1. Aligning the frame of ref (xyz) and the axis of revolution
         1. This can be generated automatically by the extension, but it’s not perfect and can be revised.
         2. How to revise after generation:
            1. Create more axes and frame of ref as needed, name them meticulously and strategically for easy access -- Important
            2. Edit the linked 3D sketch and adding axes and frames
2. Accessing the URDF:
   1. Add the mujoco extension after robot name
      1. Ref: <https://mujoco.readthedocs.io/en/latest/modeling.html#curdf>
   2. Check collision
      1. If there are internal collision even though nothing seems off
         1. Convex hull collision – in the urdf, replace the collision mesh with something else.
   3. Be careful about:
      1. File directory – make sure they are correct; if things doesn’t load, check first