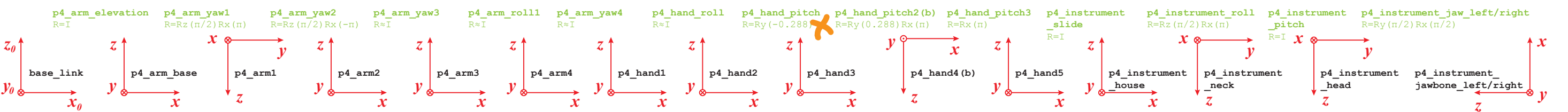
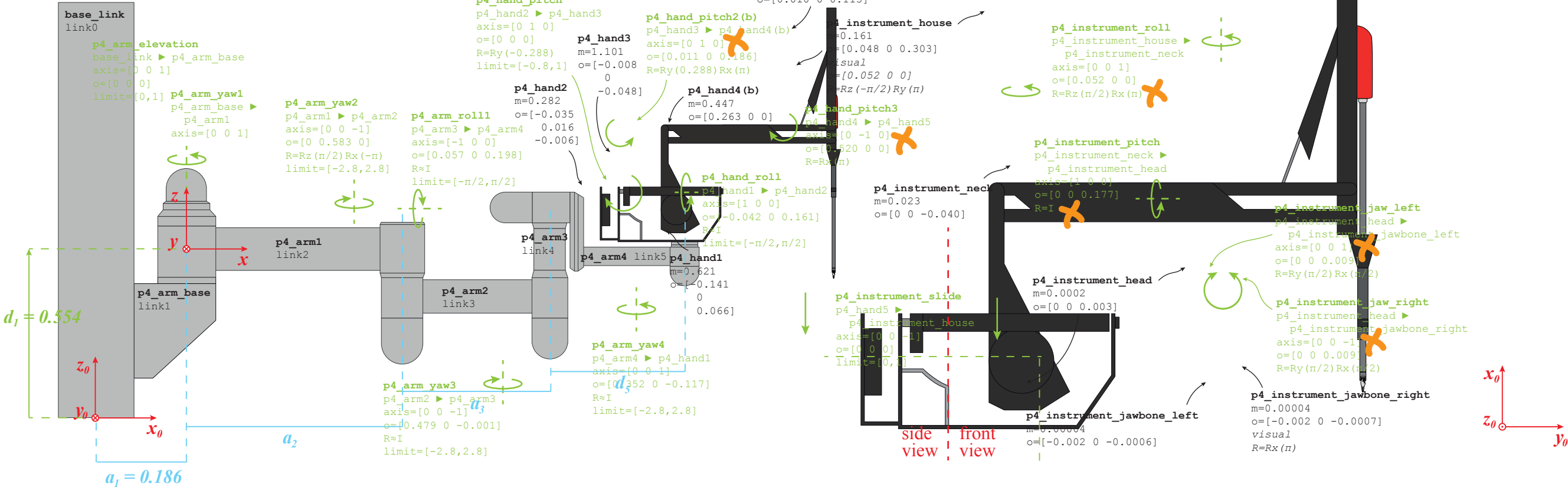


tower.xacro



```
% Robot joints
p4_arm_elevation = [0 0 0]';
p4_arm_yaw1 = [0.186 0 0.5544]';
p4_arm_yaw2 = [0 0.58285 0]';
p4_arm_yaw3 = [0.47985 0 -0.001]';
p4_arm_roll1 = [0.05699999999999999 0 0.19825]';
p4_arm_yaw4 = [0.35225 0 -0.117]';
p4_hand_roll = [-0.04249999999999998 0 0.1609999999999999]';
p4_hand_pitch = [0 0 0]';
p4_hand_pitch2 = [0.0108229214977171 0 0.186426149539229]';
p4_hand_pitch2b = [0 0 0.15]';
p4_hand_pitch3 = [0.52 0 0]';
p4_instrument_slide = [0 0 0]';
p4_instrument_roll = [0.05250000000003168 0 0]';
p4_instrument_pitch = [0 0 0.177]';
p4_instrument_jaw_left = [0 0 0.009000000000000001]';
p4_instrument_jaw_right = [0 0 0.009000000000000001]';
joints = [p4_arm_elevation p4_arm_yaw1 p4_arm_yaw2 p4_arm_yaw3 p4_arm_roll1 p4_arm_yaw4 ...
          p4_hand_roll p4_hand_pitch p4_hand_pitch2 p4_hand_pitch2b p4_hand_pitch3 ...
          p4_instrument_slide p4_instrument_roll p4_instrument_pitch ...
          p4_instrument_jaw_left p4_instrument_jaw_right];
```