**My main tasks include three parts:**

1. Parse the existing URDF files to extract the robot’s static structure and parameters as the basis for building Submodels. (1 month )
2. Design and define multiple Submodels according to the IDTA standard. These Submodels are like classes in C++, used to describe the robot’s structure and motion status, forming the robot’s digital identity (AAS). ( 2 month )
3. Implement the robot’s digital twin visualization in Unity by combining the URDF model and Submodel data to achieve dynamic display and interaction. ( 2 month )