URDF spare code

<robot name="Left\_Arm\_Robot">

<link name="Link00">

<inertial>

<mass value="0">

<origin rpy="0 0 0"xyz="0 0 0"/>

<inertia ixx="0.00381666666667" ixy="0" ixz="0" iyy="0.0036" iyz="0" izz="0.00381666666667"/>

</inertial>

<visual>

<origin rpy="0 0 0"xyz="0 0 0"/>

<geometry>

<mesh filename="Link00.stl">

</geometry>

</visual>

<collision>

<origin rpy="0 0 0" xyz="180 0 -24"/>

<geometry>

<mesh filename="Link00.stl"

</geometry>

</collision>

</link>

<joint name="joint0" type="revolute">

<origin rpy="0 0 0" xyz="0 0 0.11"/>

<axis xyz="0 0 1"/>

<limit effort="204" lower="-2.96705972839" upper="2.96705972839" velocity="1.91986217719"/>

<dynamics damping="0.1"/>

<parent link="Link00"/>

<child link="Link01"/>

</joint>

<link name="Link01">

<inertial>

<mass value="0">

<origin rpy="1.5707963267948966 0 0"xyz="0 0 0"/>

<inertia ixx="0.00381666666667" ixy="0" ixz="0" iyy="0.0036" iyz="0" izz="0.00381666666667"/>

</inertial>

<visual>

<origin rpy="1.5707963267948966 0 0"xyz="0 0 0"/>

<geometry>

<mesh filename="Link01.stl">

</geometry>

</visual>

<collision>

<origin rpy="1.5707963267948966 0 0" xyz="180 0 -24"/>

<geometry>

<mesh filename="Link01.stl"

</geometry>

</collision>

</link>

<joint name="joint1" type="revolute">

<origin rpy="1.5707963267948966 0 0" xyz="0 0 0"/>

<axis xyz="0 0 1"/>

<limit effort="204" lower="-2.96705972839" upper="2.96705972839" velocity="1.91986217719"/>

<dynamics damping="0.1"/>

<parent link="Link01"/>

<child link="Link02"/>

</joint>