

安装

[Windows系统下安装mujoco环境的教程【原创】_windows安装mujoco-CSDN博客](https://blog.csdn.net/qq_54900679/article/details/140907420)

Python安装3.2.0版本

```
pip install mujoco==3.2.0
pip install dm-control==1.0.21
```

模型

先修改URDF

修改前

```
<?xml version="1.0" encoding="utf-8"?>
<!-- This URDF was automatically created by Solidworks to URDF Exporter!
Originally created by Stephen Brawner (brawner@gmail.com)
      Commit Version: 1.6.0-1-g15f4949   Build Version: 1.6.7594.29634
      For more information, please see http://wiki.ros.org/sw_urdf_exporter -->
<robot
  name="mini_mec_six_arm">

  <link
    name="base_link">
    <inertial>
      <origin
        xyz="-0.0126930979005275 0.00191328701604972 0.138027242309266"
        rpy="0 0 0" />
```

修改后

```
<?xml version="1.0" encoding="utf-8"?>
<!-- This URDF was automatically created by Solidworks to URDF Exporter!
Originally created by Stephen Brawner (brawner@gmail.com)
      Commit Version: 1.6.0-1-g15f4949   Build Version: 1.6.7594.29634
      For more information, please see http://wiki.ros.org/sw_urdf_exporter -->
<robot
  name="mini_mec_six_arm">
  <mujoco>
    <compiler
      meshdir="."
      balanceinertia="true"
      discardvisual="false" />
  </mujoco>
  <link
    name="base_link">
    <inertial>
      <origin
        xyz="-0.0126930979005275 0.00191328701604972 0.138027242309266"
        rpy="0 0 0" />
```

增加

```
<mujoco>
  <compiler
    meshdir="./"
    balanceinertia="true"
    discardvisual="false" />
</mujoco>
```

在安装路径的bin目录 进入cmd

```
compile \path\to\mini_mec_six_arm.urdf \path\to\mini_mec_six_arm.xml
```

可视化

[Mujoco \(dm-control渲染问题\) - 知乎\(zhihu.com\)](#)