



```

<?xml version="1.0" ?>
<robot name="turtlebot3_burger" xmlns:xacro="http://ros.org/wiki/xacro">
  <link name="base_footprint"/>

  <joint name="base_joint" type="fixed">
    <parent link="base_footprint"/>
    <child link="base_link"/>
    <origin xyz="0.0 0.0 0.020" rpy="0 0 0"/>
  </joint>

  <link name="base_link">
  </link>

  <joint name="imu_joint" type="fixed">
    <parent link="base_link"/>
    <child link="imu_link"/>
    <origin xyz="-0.007 0 0.05" rpy="0 0 0"/>
  </joint>

  <link name="imu_link"/>

  <joint name="scan_joint" type="fixed">
    <parent link="base_link"/>
    <child link="base_scan"/>
    <origin xyz="-0.04 0 0.095" rpy="0 0 0"/>
  </joint>

  <link name="base_scan">
  </link>

  <joint name="wheel_left_joint" type="continuous">
    <parent link="base_link"/>
    <child link="wheel_left_link"/>
    <origin xyz="0.0 0.08 0.023" rpy="-1.57 0 0"/>
    <axis xyz="0 0 1"/>
  </joint>

  <link name="wheel_left_link">
  </link>

  <joint name="wheel_right_joint" type="continuous">
    <parent link="base_link"/>
    <child link="wheel_right_link"/>
    <origin xyz="0.0 -0.080 0.023" rpy="-1.57 0 0"/>
    <axis xyz="0 0 1"/>
  </joint>

  <link name="wheel_right_link">
  </link>

  <joint name="caster_back_joint" type="fixed">
    <parent link="base_link"/>
    <child link="caster_back_link"/>
    <origin xyz="-0.081 0 -0.004" rpy="-1.57 0 0"/>
  </joint>

  <link name="caster_back_link">
  </link>
</robot>

```

Location of base_link

Location of IMU

Location of LiDAR