

```
<?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"/> Location of base link
  </ioint>
  k 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"/> Location of IMU
  </ioint>
 <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"/> Location of LiDAR
  </ioint>
 <link name="base scan">
 </link>
 <joint name="wheel_left_joint" type="continuous">
    <parent link="base_link"/>
   <child link="wheel_left_link"/>
   <origin xvz="0.0 0.08 0.023" rpv="-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 -\overline{0}.080 \ \overline{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"/>
 </ioint>
 <link name="caster_back_link">
 </link>
</robot>
```