

world

xyz: 0 0 0
rpy: 0 -0 0

single_rrbot_fixed

single_rrbot_link1

xyz: 0 0.1 1.95
rpy: 0 -0 0

single_rrbot_joint1

single_rrbot_link2

xyz: 0 0.1 0.9
rpy: 0 -0 0

single_rrbot_joint2

single_rrbot_link3