What I did is a symmetrical robot with two limbs and arm like structures that tries to imitate the human limb movement.

The cylinder (base link) represents the torso of a human.

The big sphere above the cylinder represents a head. It also translates into and out of the cylinder to represent head movement.

The boxes next to it represent the upper arm and are fixed.

The joints next to it (the 2 small spheres) represent the elbow which rotates along the e3 axis.

The cylinder holding the spheres are fixed and act as holders.

The lower arm is divided into 2 cylinders; one is fixed and the other is attached to a wide cylinder (that represents a wrist), this rotates in the e2 direction.

The left and right sides of the robot are the same and has 3 lines of symmetry

The movement is first done one joint at a time and all at once.

I expanded the axis limits given by default because I want the full motion of the limbs to be seen.

The parent limb parts are named normally (i.e. original_link_name) while the corresponding links on the other side are named as original_link_name_2.