<robot

name="URDF\_Sivia">

<link

name="torso">

<inertial>

<origin

xyz="-1.04106597957722E-10 -0.000333377345534058 -0.0356225494375101"

rpy="0 0 0" />

<mass

value="1.94003184723439" />

<inertia

ixx="0.0329620085295692"

ixy="3.99647383329121E-11"

ixz="3.103929241657E-12"

iyy="0.0329644601488204"

iyz="-4.67786132113573E-06"

izz="0.0628117714849608" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

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</geometry>

<material

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rgba="0.752941176470588 0.752941176470588 0.752941176470588 1" />

</material>

</visual>

<collision>

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xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/torso.STL" />

</geometry>

</collision>

</link>

<link

name="RF\_Coxa">

<inertial>

<origin

xyz="0.0285 0 0"

rpy="0 0 0" />

<mass

value="0.06196" />

<inertia

ixx="8.8248E-05"

ixy="0"

ixz="0"

iyy="6.265E-05"

iyz="0"

izz="6.265E-05" />

</inertial>

<visual>

<origin

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rpy="0 0 0" />

<geometry>

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</geometry>

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</geometry>

</collision>

</link>

<joint

name="RF\_Coxa"

type="revolute">

<origin

xyz="0.1104 0.19121 -0.0411"

rpy="6.7145E-16 -1.0108E-15 1.0472" />

<parent

link="torso" />

<child

link="RF\_Coxa" />

<axis

xyz="0 0 1" />

<limit

effort="0"

velocity="0" />

</joint>

<link

name="RF\_Femur">

<inertial>

<origin

xyz="0.10825 -0.0059319 0"

rpy="0 0 0" />

<mass

value="0.36917" />

<inertia

ixx="0.0003031"

ixy="0.00016794"

ixz="0"

iyy="0.0031035"

iyz="0"

izz="0.0029635" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/RF\_Femur.STL" />

</geometry>

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<collision>

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rpy="0 0 0" />

<geometry>

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/RF\_Femur.STL" />

</geometry>

</collision>

</link>

<joint

name="RF\_Femur"

type="revolute">

<origin

xyz="0.0569999999999997 0.000499999999999889 0"

rpy="1.5707963267949 2.89167808056098E-16 -1.0547118733939E-14" />

<parent

link="RF\_Coxa" />

<child

link="RF\_Femur" />

<axis

xyz="0 0 1" />

</joint>

<link

name="RF\_Tibia">

<inertial>

<origin

xyz="0 -0.16811 0"

rpy="0 0 0" />

<mass

value="0.11462" />

<inertia

ixx="0.0022169"

ixy="0"

ixz="0"

iyy="5.0466E-05"

iyz="0"

izz="0.0021771" />

</inertial>

<visual>

<origin

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rpy="0 0 0" />

<geometry>

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</geometry>

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</material>

</visual>

<collision>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/RF\_Tibia.STL" />

</geometry>

</collision>

</link>

<joint

name="RF\_Tibia"

type="revolute">

<origin

xyz="0.197499999999995 -0.0264999999999869 -0.000500000000000185"

rpy="-1.72578136476748E-18 3.88578058618805E-16 4.44089209850062E-16" />

<parent

link="RF\_Femur" />

<child

link="RF\_Tibia" />

<axis

xyz="0 0 1" />

</joint>

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name="RM\_Coxa">

<inertial>

<origin

xyz="0.0285 0 0"

rpy="0 0 0" />

<mass

value="0.06196" />

<inertia

ixx="8.8248E-05"

ixy="0"

ixz="0"

iyy="6.265E-05"

iyz="0"

izz="6.265E-05" />

</inertial>

<visual>

<origin

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rpy="0 0 0" />

<geometry>

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</geometry>

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<collision>

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rpy="0 0 0" />

<geometry>

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/RM\_Coxa.STL" />

</geometry>

</collision>

</link>

<joint

name="RM\_Coxa"

type="revolute">

<origin

xyz="0.221136515003529 -0.000204145205102327 -0.0411"

rpy="0 0 0" />

<parent

link="torso" />

<child

link="RM\_Coxa" />

<axis

xyz="0 0 1" />

</joint>

<link

name="RM\_Femur">

<inertial>

<origin

xyz="0.10825 -0.0059319 0"

rpy="0 0 0" />

<mass

value="0.36917" />

<inertia

ixx="0.0003031"

ixy="0.00016794"

ixz="0"

iyy="0.0031035"

iyz="0"

izz="0.0029635" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/RM\_Femur.STL" />

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<collision>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/RM\_Femur.STL" />

</geometry>

</collision>

</link>

<joint

name="RM\_Femur"

type="revolute">

<origin

xyz="0.0569999999999997 0.000499999999995754 0"

rpy="1.5707963267949 -1.57609902476415E-16 -2.55351295663786E-14" />

<parent

link="RM\_Coxa" />

<child

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<axis

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</joint>

<link

name="RM\_Tibia">

<inertial>

<origin

xyz="0 -0.16811 0"

rpy="0 0 0" />

<mass

value="0.11462" />

<inertia

ixx="0.0022169"

ixy="0"

ixz="0"

iyy="5.0466E-05"

iyz="0"

izz="0.0021771" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/RM\_Tibia.STL" />

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</material>

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<collision>

<origin

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rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/RM\_Tibia.STL" />

</geometry>

</collision>

</link>

<joint

name="RM\_Tibia"

type="revolute">

<origin

xyz="0.197499999999995 -0.0264999999999869 -0.000500000000000022"

rpy="2.48971021378027E-17 5.55111512312988E-17 -1.58902539658756E-16" />

<parent

link="RM\_Femur" />

<child

link="RM\_Tibia" />

<axis

xyz="0 0 1" />

</joint>

<link

name="RR\_Coxa">

<inertial>

<origin

xyz="0.0285 0 0"

rpy="0 0 0" />

<mass

value="0.06196" />

<inertia

ixx="8.8248E-05"

ixy="0"

ixz="0"

iyy="6.265E-05"

iyz="0"

izz="6.265E-05" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/RR\_Coxa.STL" />

</geometry>

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<collision>

<origin

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rpy="0 0 0" />

<geometry>

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/RR\_Coxa.STL" />

</geometry>

</collision>

</link>

<joint

name="RR\_Coxa"

type="revolute">

<origin

xyz="0.110741462568083 -0.191813984894186 -0.0411"

rpy="1.04921130408763E-15 -4.03562942076964E-16 -1.04719755119661" />

<parent

link="torso" />

<child

link="RR\_Coxa" />

<axis

xyz="0 0 1" />

</joint>

<link

name="RR\_Femur">

<inertial>

<origin

xyz="0.10825 -0.0059319 0"

rpy="0 0 0" />

<mass

value="0.36917" />

<inertia

ixx="0.0003031"

ixy="0.00016794"

ixz="0"

iyy="0.0031035"

iyz="0"

izz="0.0029635" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

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</geometry>

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<collision>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/RR\_Femur.STL" />

</geometry>

</collision>

</link>

<joint

name="RR\_Femur"

type="revolute">

<origin

xyz="0.0569999999999997 0.000499999999999959 0"

rpy="1.5707963267949 5.70096395770726E-16 -1.02695629777827E-14" />

<parent

link="RR\_Coxa" />

<child

link="RR\_Femur" />

<axis

xyz="0 0 1" />

</joint>

<link

name="RR\_Tibia">

<inertial>

<origin

xyz="0 -0.16811 0"

rpy="0 0 0" />

<mass

value="0.11462" />

<inertia

ixx="0.0022169"

ixy="0"

ixz="0"

iyy="5.0466E-05"

iyz="0"

izz="0.0021771" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/RR\_Tibia.STL" />

</geometry>

<material

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xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/RR\_Tibia.STL" />

</geometry>

</collision>

</link>

<joint

name="RR\_Tibia"

type="revolute">

<origin

xyz="0.197499999999995 -0.0264999999999869 -0.000500000000000141"

rpy="-7.43708407166633E-18 2.77555756156289E-16 5.55111512312576E-17" />

<parent

link="RR\_Femur" />

<child

link="RR\_Tibia" />

<axis

xyz="0 0 1" />

</joint>

<link

name="LR\_Coxa">

<inertial>

<origin

xyz="0.0285 0 0"

rpy="0 0 0" />

<mass

value="0.06196" />

<inertia

ixx="8.8248E-05"

ixy="0"

ixz="0"

iyy="6.265E-05"

iyz="0"

izz="6.265E-05" />

</inertial>

<visual>

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/LR\_Coxa.STL" />

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<material

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<collision>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

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</geometry>

</collision>

</link>

<joint

name="LR\_Coxa"

type="revolute">

<origin

xyz="-0.110395052406575 -0.192013984860853 -0.0411000000000001"

rpy="2.90792643314256E-16 4.75788027754703E-18 -2.09439510239319" />

<parent

link="torso" />

<child

link="LR\_Coxa" />

<axis

xyz="0 0 1" />

</joint>

<link

name="LR\_Femur">

<inertial>

<origin

xyz="0.10825 -0.0059319 0"

rpy="0 0 0" />

<mass

value="0.36917" />

<inertia

ixx="0.0003031"

ixy="0.00016794"

ixz="0"

iyy="0.0031035"

iyz="0"

izz="0.0029635" />

</inertial>

<visual>

<origin

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<origin

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rpy="0 0 0" />

<geometry>

<mesh

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</geometry>

</collision>

</link>

<joint

name="LR\_Femur"

type="revolute">

<origin

xyz="0.0569999999999998 0.000499999999999891 0"

rpy="1.5707963267949 4.9484248080377E-16 -1.03805852802452E-14" />

<parent

link="LR\_Coxa" />

<child

link="LR\_Femur" />

<axis

xyz="0 0 1" />

</joint>

<link

name="LR\_Tibia">

<inertial>

<origin

xyz="0 -0.16811 0"

rpy="0 0 0" />

<mass

value="0.11462" />

<inertia

ixx="0.0022169"

ixy="0"

ixz="0"

iyy="5.0466E-05"

iyz="0"

izz="0.0021771" />

</inertial>

<visual>

<origin

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<geometry>

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</geometry>

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<collision>

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xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

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</geometry>

</collision>

</link>

<joint

name="LR\_Tibia"

type="revolute">

<origin

xyz="0.197499999999995 -0.0264999999999869 -0.000500000000000223"

rpy="-1.18850271367683E-17 3.88578058618805E-16 2.77555756156289E-16" />

<parent

link="LR\_Femur" />

<child

link="LR\_Tibia" />

<axis

xyz="0 0 1" />

</joint>

<link

name="LM\_Coxa">

<inertial>

<origin

xyz="0.0285 0 0"

rpy="0 0 0" />

<mass

value="0.06196" />

<inertia

ixx="8.8248E-05"

ixy="0"

ixz="0"

iyy="6.265E-05"

iyz="0"

izz="6.265E-05" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/LM\_Coxa.STL" />

</geometry>

<material

name="">

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rgba="0.75294 0.75294 0.75294 1" />

</material>

</visual>

<collision>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/LM\_Coxa.STL" />

</geometry>

</collision>

</link>

<joint

name="LM\_Coxa"

type="revolute">

<origin

xyz="-0.221136515003529 -0.000604145171771042 -0.0411"

rpy="3.13661300568136E-16 -5.44033853633042E-16 -3.14159265358976" />

<parent

link="torso" />

<child

link="LM\_Coxa" />

<axis

xyz="0 0 1" />

</joint>

<link

name="LM\_Femur">

<inertial>

<origin

xyz="0.10825 -0.0059319 0"

rpy="0 0 0" />

<mass

value="0.36917" />

<inertia

ixx="0.0003031"

ixy="0.00016794"

ixz="0"

iyy="0.0031035"

iyz="0"

izz="0.0029635" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/LM\_Femur.STL" />

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<material

name="">

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rgba="0.75294 0.75294 0.75294 1" />

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<collision>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/LM\_Femur.STL" />

</geometry>

</collision>

</link>

<joint

name="LM\_Femur"

type="revolute">

<origin

xyz="0.0569999999999996 0.000499999999999929 0"

rpy="1.5707963267949 4.67101421341748E-16 -1.0380585280246E-14" />

<parent

link="LM\_Coxa" />

<child

link="LM\_Femur" />

<axis

xyz="0 0 1" />

</joint>

<link

name="LM\_Tibia">

<inertial>

<origin

xyz="0 -0.16811 0"

rpy="0 0 0" />

<mass

value="0.11462" />

<inertia

ixx="0.0022169"

ixy="0"

ixz="0"

iyy="5.0466E-05"

iyz="0"

izz="0.0021771" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/LM\_Tibia.STL" />

</geometry>

<material

name="">

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rgba="0.75294 0.75294 0.75294 1" />

</material>

</visual>

<collision>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/LM\_Tibia.STL" />

</geometry>

</collision>

</link>

<joint

name="LM\_Tibia"

type="revolute">

<origin

xyz="0.197499999999994 -0.0264999999999876 -0.000499999999986901"

rpy="2.07109947580838E-17 1.6653345369371E-16 -1.58902539658993E-16" />

<parent

link="LM\_Femur" />

<child

link="LM\_Tibia" />

<axis

xyz="0 0 1" />

</joint>

<link

name="LF\_Coxa">

<inertial>

<origin

xyz="0.0285 0 0"

rpy="0 0 0" />

<mass

value="0.06196" />

<inertia

ixx="8.8248E-05"

ixy="0"

ixz="0"

iyy="6.265E-05"

iyz="0"

izz="6.265E-05" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/LF\_Coxa.STL" />

</geometry>

<material

name="">

<color

rgba="0.75294 0.75294 0.75294 1" />

</material>

</visual>

<collision>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/LF\_Coxa.STL" />

</geometry>

</collision>

</link>

<joint

name="LF\_Coxa"

type="revolute">

<origin

xyz="-0.11074 0.19101 -0.0411"

rpy="3.9175E-16 -9.3367E-16 2.0944" />

<parent

link="torso" />

<child

link="LF\_Coxa" />

<axis

xyz="0 0 1" />

<limit

effort="0"

velocity="0" />

</joint>

<link

name="LF\_Femur">

<inertial>

<origin

xyz="0.10825 -0.0059319 0"

rpy="0 0 0" />

<mass

value="0.36917" />

<inertia

ixx="0.0003031"

ixy="0.00016794"

ixz="0"

iyy="0.0031035"

iyz="0"

izz="0.0029635" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

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filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/LF\_Femur.STL" />

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<material

name="">

<color

rgba="0.75294 0.75294 0.75294 1" />

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<collision>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/LF\_Femur.STL" />

</geometry>

</collision>

</link>

<joint

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type="revolute">

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rpy="1.5707963267949 3.78561680455341E-16 -1.0325074129014E-14" />

<parent

link="LF\_Coxa" />

<child

link="LF\_Femur" />

<axis

xyz="0 0 1" />

</joint>

<link

name="LF\_Tibia">

<inertial>

<origin

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rpy="0 0 0" />

<mass

value="0.11462" />

<inertia

ixx="0.0022169"

ixy="0"

ixz="0"

iyy="5.0466E-05"

iyz="0"

izz="0.0021771" />

</inertial>

<visual>

<origin

xyz="0 0 0"

rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes/LF\_Tibia.STL" />

</geometry>

<material

name="">

<color

rgba="0.75294 0.75294 0.75294 1" />

</material>

</visual>

<collision>

<origin

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rpy="0 0 0" />

<geometry>

<mesh

filename="/home/romelahex/Desktop/URDF\_Sivia/meshes\_collision/LF\_Tibia.STL" />

</geometry>

</collision>

</link>

<joint

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type="revolute">

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<parent

link="LF\_Femur" />

<child

link="LF\_Tibia" />

<axis

xyz="0 0 1" />

</joint>

</robot>