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 name="torso">

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 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>

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 rpy="0 0 0" />

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 value="0.06196" />

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 ixx="8.8248E-05"

 ixy="0"

 ixz="0"

 iyy="6.265E-05"

 iyz="0"

 izz="6.265E-05" />

 </inertial>

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 </collision>

 </link>

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 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">

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 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>

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 </collision>

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

 <parent

 link="RF\_Coxa" />

 <child

 link="RF\_Femur" />

 <axis

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 <inertial>

 <origin

 xyz="0 -0.16811 0"

 rpy="0 0 0" />

 <mass

 value="0.11462" />

 <inertia

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 ixy="0"

 ixz="0"

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 </inertial>

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 </collision>

 </link>

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 type="revolute">

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 xyz="0.197499999999995 -0.0264999999999869 -0.000500000000000185"

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

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 link="RF\_Femur" />

 <child

 link="RF\_Tibia" />

 <axis

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 rpy="0 0 0" />

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 ixz="0"

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 </inertial>

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 </collision>

 </link>

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 type="revolute">

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 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>

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 rpy="0 0 0" />

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 value="0.36917" />

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 ixy="0.00016794"

 ixz="0"

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 iyz="0"

 izz="0.0029635" />

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 </collision>

 </link>

 <joint

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 type="revolute">

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 xyz="0.0569999999999997 0.000499999999995754 0"

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

 <parent

 link="RM\_Coxa" />

 <child

 link="RM\_Femur" />

 <axis

 xyz="0 0 1" />

 </joint>

 <link

 name="RM\_Tibia">

 <inertial>

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 rpy="0 0 0" />

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 ixz="0"

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 izz="0.0021771" />

 </inertial>

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 </collision>

 </link>

 <joint

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 type="revolute">

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 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">

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 <origin

 xyz="0.0285 0 0"

 rpy="0 0 0" />

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 value="0.06196" />

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 izz="6.265E-05" />

 </inertial>

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 type="revolute">

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 xyz="0.110741462568083 -0.191813984894186 -0.0411"

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

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 link="torso" />

 <child

 link="RR\_Coxa" />

 <axis

 xyz="0 0 1" />

 </joint>

 <link

 name="RR\_Femur">

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 xyz="0.10825 -0.0059319 0"

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 value="0.36917" />

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 ixy="0.00016794"

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 izz="0.0029635" />

 </inertial>

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 </collision>

 </link>

 <joint

 name="RR\_Femur"

 type="revolute">

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 xyz="0.0569999999999997 0.000499999999999959 0"

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

 <parent

 link="RR\_Coxa" />

 <child

 link="RR\_Femur" />

 <axis

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 rpy="0 0 0" />

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 ixz="0"

 iyy="5.0466E-05"

 iyz="0"

 izz="0.0021771" />

 </inertial>

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 </collision>

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 <joint

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 type="revolute">

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 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

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 name="LR\_Coxa">

 <inertial>

 <origin

 xyz="0.0285 0 0"

 rpy="0 0 0" />

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 value="0.06196" />

 <inertia

 ixx="8.8248E-05"

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 ixz="0"

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 izz="6.265E-05" />

 </inertial>

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 </collision>

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 type="revolute">

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 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">

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 ixy="0.00016794"

 ixz="0"

 iyy="0.0031035"

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 izz="0.0029635" />

 </inertial>

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 </collision>

 </link>

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 type="revolute">

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

 <parent

 link="LR\_Coxa" />

 <child

 link="LR\_Femur" />

 <axis

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 <inertial>

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 xyz="0 -0.16811 0"

 rpy="0 0 0" />

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 ixz="0"

 iyy="5.0466E-05"

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 izz="0.0021771" />

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 </collision>

 </link>

 <joint

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 type="revolute">

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 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"

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 ixz="0"

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 izz="6.265E-05" />

 </inertial>

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 rpy="0 0 0" />

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 <origin

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 rpy="0 0 0" />

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 </collision>

 </link>

 <joint

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 type="revolute">

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 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" />

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 ixy="0.00016794"

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 izz="0.0029635" />

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 </collision>

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 <joint

 name="LM\_Femur"

 type="revolute">

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 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>

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 xyz="0 -0.16811 0"

 rpy="0 0 0" />

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 value="0.11462" />

 <inertia

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 </geometry>

 </collision>

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 <joint

 name="LM\_Tibia"

 type="revolute">

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 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">

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 <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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 </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/LF\_Coxa.STL" />

 </geometry>

 </collision>

 </link>

 <joint

 name="LF\_Coxa"

 type="revolute">

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 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" />

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 value="0.36917" />

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 ixy="0.00016794"

 ixz="0"

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 iyz="0"

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 <visual>

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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/LF\_Femur.STL" />

 </geometry>

 </collision>

 </link>

 <joint

 name="LF\_Femur"

 type="revolute">

 <origin

 xyz="0.0569999999999997 0.00049999999999994 0"

 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

 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/LF\_Tibia.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\_Tibia.STL" />

 </geometry>

 </collision>

 </link>

 <joint

 name="LF\_Tibia"

 type="revolute">

 <origin

 xyz="0.197499999999995 -0.0264999999999869 -0.00050000000000011"

 rpy="-2.83996459892448E-16 3.88578058618805E-16 3.33066907387547E-16" />

 <parent

 link="LF\_Femur" />

 <child

 link="LF\_Tibia" />

 <axis

 xyz="0 0 1" />

 </joint>

</robot>