```
_{d} e sign. PNG [fig. gaze bo Structure] GAZE BOGAZE BOF ig GAZE BO system diagram
    \begin{array}{l} {}_{r}obot"><\\ linkname='\\ chassis'><\\ pose>\\ 00.1000<\\ \end{array}
         /pose > <
  /pose ><
collisionname ='
collision' ><
geometry ><
box ><
size >
.4.2.1 <
/size ><
           box > <
         /geometry > <
         /collision >
\begin{array}{l} collision' > <\\ pose > \\ -0.150 -\\ 0.05000 <\\ /pose > <\\ geometry > <\\ sphere > <\\ radius >\\ .05 <\\ /radius > <\\ /enhage > <\\ \end{array}
           /sphere ><
         /geometry >
  visual' > < pose > < -0.150 - < 0.05000 < < pose > < po
      geometry ><
    geometry > sphere > < radius > .05 < / radius > < //radius > < / representations / sphere > <
         /geometry > <
           /visual > <
             /link > <
\begin{array}{l} |link><\\ linkname =\\ "left_wheel"><\\ pose>\\ 0.10.130.101.57071.5707<\\ /pose><\\ collisionname =\\ "collision"><\\ geometry><\\ cylinder><\\ radius>\\ \end{array}
      r_1^{\circ}adjus>
             /radius > <
      length >
      .05 < /length > <
         /cylinder > <
           /geometry><
         /collision ><
    visualname = "visual" >< geometry >< cylinder ><
    radius > 1 < rad
         .05 < /length > <
           /cylinder > <
           /geometry > <
           /visual > <
         /link >
      box{wheel} ><
  pose > 0.1-
0.130.101.57071.5707 < /pose > < collisionname = "collision" > < geometry > < cylinder > <
    radius >
             radius > <
```

length > 0.05 < 0.05 < 0.05