

base_link

xyz: 0 -0.10478 -0.0002
rpy: 2.3309 -0 -3.14159

joint_1

link_1

xyz: -0.02165 0 -0.16328
rpy: 1.5892 -0 0

joint_2

link_2

xyz: 0.02595 0 -0.16537
rpy: 2.3631 -0 0

joint_3

link_3