



robot.urdf

```
<robot name="robot">
  <link> ... </link>
  <link> ... </link>
  <link> ... </link>
  <joint> .... </joint>
  <joint> .... </joint>
  <joint> .... </joint>
</robot>
```

```
<link name="link_name">
  <visual>
    <geometry>
      <mesh filename="mesh.dae"/>
    </geometry>
  </visual>
  <collision>
    <geometry>
      <cylinder length="0.6" radius="0.2"/>
    </geometry>
  </collision>
  <inertial>
    <mass value="10"/>
    <inertia ixx="0.4" ixy="0.0" .../>
  </inertial>
</link>
```

```
<joint name="joint_name" type="revolute">
  <axis xyz="0 0 1"/>
  <limit effort="1000.0" upper="0.548" ... />
  <origin rpy="0 0 0" xyz="0.2 0.01 0"/>
  <parent link="parent_link_name"/>
  <child link="child_link_name"/>
</joint>
```