

To do write a URDF file with these link details

Link name	Geometry		origin
Base_link	Cylinder	0.6, 0.2	
right_leg	box	0.6, 0.1, 0.2	rpy = 0 1.57075 0 xyz = 0 0 -0.3
right_base	Box	0.4, 0.1, 0.1	
right_front_wheel	Cylinder	0.1, 0.035	rpy=1.57075 0 0 xyz=0 0 0
right_back_wheel	Cylinder	0.1, 0.035	rpy=1.57075 0 0 xyz=0 0 0
left_leg	box	0.6, 0.1, 0.2	rpy = 0 1.57075 0 xyz = 0 0 -0.3
left_base	Box	0.4, 0.1, 0.1	
left_front_wheel	Cylinder	0.1, 0.035	rpy=1.57075 0 0 xyz=0 0 0
left_back_wheel	Cylinder	0.1, 0.035	rpy=1.57075 0 0 xyz=0 0 0
gripper_pole	Cylinder	0.2,0.01	rpy=1.57075 0 0 xyz=0.1 0 0
left_gripper	<mesh filename=package://urdf_tutorial/meshes/l_finger.dae/>		rpy=0.0 0 0 xyz=0 0 0
left_tip	<mesh filename=package://urdf_tutorial/meshes/l_finger_tip.dae/>		rpy=0.0 0 0 xyz=0.09137 0.00495 0
right_gripper	<mesh filename=package://urdf_tutorial/meshes/l_finger.dae/>		rpy=-3.1415 0 0 xyz=0 0 0
right_tip	<mesh filename=package://urdf_tutorial/meshes/l_finger_tip.dae/>		rpy=-3.1415 0 0 xyz=0.09137 0.00495 0
head	sphere	0.2	
box	box	0.08, 0.08, 0.08	

Write a URDF file with these joint details

Joint name	type	Parent link	Child link	origin
base_to_right_leg	fixed	base_link	right_leg	xyz=0 -0.22 0.25
right_base_joint	fixed	right_leg	right_base	xyz=0 0 -0.6
right_front_wheel_joint	fixed	right_base	right_front_wheel	rpy=0 0 0 xyz=0.133333333333 0 -0.085
right_back_wheel_joint	fixed	right_base	right_back_wheel	rpy=0 0 0 xyz=-0.133333333333 0 -0.085
base_to_left_leg	fixed	base_link	left_leg	xyz=0 0.22 0.25
left_base_joint	fixed	left_leg	left_base	xyz=0 0 -0.6
left_front_wheel_joint	fixed	left_base	left_front_wheel	rpy=0 0 0 xyz=0.133333333333 0 -0.085
left_back_wheel_joint	fixed	left_base	left_back_wheel	rpy=0 0 0 xyz=-0.133333333333 0 -0.085
gripper_extension	fixed	base_link	gripper_pole	rpy=0 0 0 xyz=0.19 0 0.2
left_gripper_joint	fixed	gripper_pole	left_gripper	rpy=0 0 0 xyz=0.2 0.01 0
left_tip_joint	fixed	left_gripper	left_tip	
right_gripper_joint	fixed	gripper_pole	right_gripper	rpy=0 0 0 xyz=0.2 -0.01 0
right_tip_joint	fixed	right_gripper	right_tip	
head_swivel	fixed	base_link	head	xyz=0 0 0.3
tobox	fixed	head	box	xyz=0.1814 0 0.1414