robot name="Robot1"

link name="base\_link">

box size="0.2 .3 .1"

origin rpy="0 0 0" xyz="0 0 0.05"

material name="white" rgba="1 1 1 1"

link name="wheel\_1"

cylinder length="0.05" radius="0.05"

origin rpy="0 1.5 0" xyz="0.1 0.1 0"

material name="black" rgba="0 0 0 1"

link name="wheel\_2"

origin rpy="0 1.5 0" xyz="-0.1 0.1 0"

link name="wheel\_3"

origin rpy="0 1.5 0" xyz="0.1 -0.1 0"

link name="wheel\_4"

origin rpy="0 1.5 0" xyz="-0.1 -0.1 0"

joint name="base\_to\_wheel1" type="fixed"

joint name="base\_to\_wheel2" type="fixed"

joint name="base\_to\_wheel3" type="fixed"

joint name="base\_to\_wheel4" type="fixed"

origin xyz="0 0 0"