

```

<mujoco model="turmellbot">
  <compiler coordinate="local"/>
  <default>
    <geom rgba=".8 .6 .4 1"/>
  </default>
  <asset>
    <texture type="skybox" builtin="gradient" rgb1="1 1 1" rgb2=".6 .8 1" width="256" height="256"/>
    <mesh file="a-foot.stl" refpos="-10.84427 0.1037934 -17.62868" refquat="0.99619 0.034862 0.00000 0.00000"/>
  </asset>
  <worldbody>
    <light pos="10 -10 50" dir="-10 10 -50" diffuse="1 1 1"/>
    <site name="reference" pos="5.938405e-19 -0.09110710 17.62735"/>
    <body>
      <geom name="base" type="cylinder" fromto="-0.4000000 -0.09110710 17.62735 5.938405e-19 -0.09110710 17.62735"
size="12.032592"/>
      <site name="b1" pos="-6.093131e-16 6.659522 7.666812" size="0.2"/>
      <site name="b2" pos="6.105008e-16 -6.841736 27.58788" size="0.2"/>
      <site name="b3" pos="4.139506e-16 9.869429 24.37798" size="0.2"/>
      <site name="b4" pos="-4.127630e-16 -10.05164 10.87672" size="0.2"/>
      <geom name="leg" type="capsule" fromto="5.938405e-19 -0.09110710 17.62735 10.84427 -0.1037934 17.62868" size="0.3"/>
      <site name="shnk" pos="10.84427 -0.1037934 17.62868"/>
      <body>
        <geom name="comp" type="capsule" fromto="10.84427 -0.1037934 17.62868 11.19642 -0.01170672 17.90907" size="0.3"/>
        <joint name="TC" type="hinge" pos="10.84427 -0.1037934 17.62868" axis="-0.1740000 0.9790000 -0.1030000" limited="true"
range="-20 20"/>
        <body>
          <geom name="b-foot" type="capsule" fromto="11.19642 -0.01170672 17.90907 17.61765 -0.09110710 17.62735" size="0.3"/>
          <joint name="ST" type="hinge" pos="11.19642 -0.01170672 17.90907" axis="-0.6420000 0.2080000 0.7380000" limited="true"
range="-15 15"/>
          <geom name="ptfm" type="cylinder" fromto="17.61765 -0.09110710 17.627 18.01765 -0.09110710 17.62735" size="9.25584"/>
          <site name="ptfmc" pos="18.01765 -0.09110710 17.62735" size="0.3"/>
          <geom name="s-foot" type="mesh" mesh="a-foot" rgba=".85 .79 .72 0.7" density="0.01"/>
          <site name="p1" pos="17.61765 5.101684 9.965397" size="0.2"/>
          <site name="p2" pos="17.61765 -5.283899 25.28930" size="0.2"/>
          <site name="p3" pos="17.61765 7.570844 22.82014" size="0.2"/>
          <site name="p4" pos="17.61765 -7.753058 12.43456" size="0.2"/>
        </body>
      </body>
    </worldbody>
    <tendon>
      <spatial name="t1" limited="true" range="13.3005 13.3015" width="0.05" stiffness="100" damping="100000">
        <site site="b1"/>
        <site site="p1"/>
      </spatial>
      <spatial name="t2" limited="true" range="21.9404 21.9414" width="0.05" stiffness="100" damping="100000">
        <site site="b2"/>
        <site site="p2"/>
      </spatial>
      <spatial name="t3" limited="true" range="18.2678 18.2688" width="0.05" stiffness="100" damping="100000">
        <site site="b3"/>
        <site site="p3"/>
      </spatial>
      <spatial name="t4" limited="true" range="16.8570 16.8580" width="0.05" stiffness="100" damping="100000">
        <site site="b4"/>
        <site site="p4"/>
      </spatial>
    </tendon>
    <actuator>
      <muscle name="t1" tendon="t1"/>
      <muscle name="t2" tendon="t2"/>
      <muscle name="t3" tendon="t3"/>
      <muscle name="t4" tendon="t4"/>
    </actuator>
    <sensor>
      <accelerometer name="ptfacc" site="ptfmc"/>
      <gyro name="ptfgyro" site="ptfmc"/>
      <tendonpos name="t1pos" tendon="t1"/>
      <tendonpos name="t2pos" tendon="t2"/>
      <tendonpos name="t3pos" tendon="t3"/>
      <tendonpos name="t4pos" tendon="t4"/>
      <jointpos name="TCpos" joint="ST"/>
      <jointpos name="STpos" joint="TC"/>
    </sensor>
  </mujoco>

```