```xml
<?xml version="1.0"?>
<robot name="min_kinematic">
    <!--All links of our model.-->
    <!--The root frame in ROS is called the base_link and represents the root frame (B_0) in
    our system. -->
    <link name="base_link"/>
    <!--The link 1 of our model. -->
    <link name="link_1"/>
    <!-- The working frame of our model is represented as a link.-->
    <link name="work_frame"/>

    <!--All joints of our model.-->
    <!--The revolute joint 1, which couples the base link (parent link) with the link 1
    (child link) is modeled here.
    The joint is located at the origin of the child link.-->
    <joint name="joint_1" type="revolute">
        <parent link="base_link"/>
        <child link="link_1"/>
        <!-- Selection of rotation axis, in our case around the joint is around the z-axis in
        positive direction.-->
        <axis xyz="0 0 1"/>
        <!-- The transformation between the parent and child link is given here.-->
        <!-- The translational components (xyz) are given in meters. -->
        <!-- The rotation is expressed by the Euler angles (rpy) in radians according to the
        following
         notation (r)oll (rot. x-axis), (p)itch (rot. y-axis), and (y)aw (rot. z-axis). -->
        <origin xyz="0 0 0.4" rpy="1.57079632679 0.0 0.0"/>
        <!-- The model of a movable joint must include further physical properties. -->
        <limit effort="100" lower="-0.175" upper="3.1416" velocity="0.5"/>
    </joint>

    <!-- The work frame lies at the end of link 1, hence in ROS this connection is modelled
    as a fixed joint. -->
    <joint name="joint_work_frame" type="fixed">
        <parent link="link_1"/>
        <child link="work_frame"/>
        <origin rpy="-1.57079632679 0.0 -1.57079632679" xyz="0.8 0 0.0"/>
    </joint>
</robot>
```