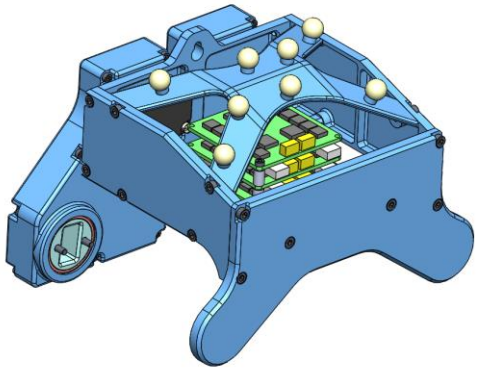
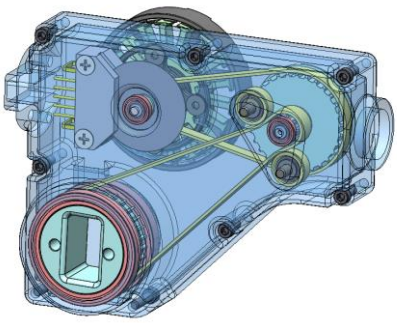
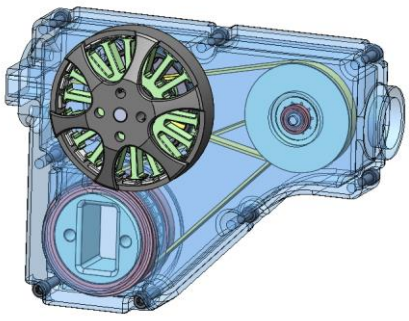
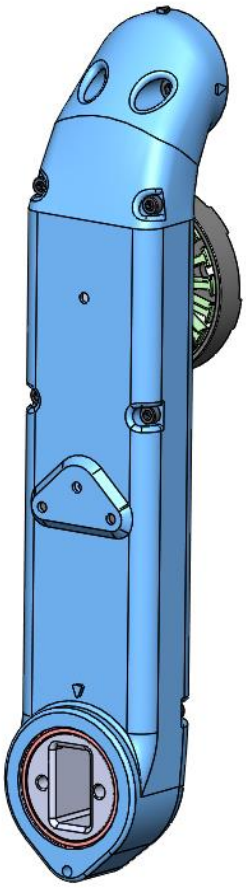
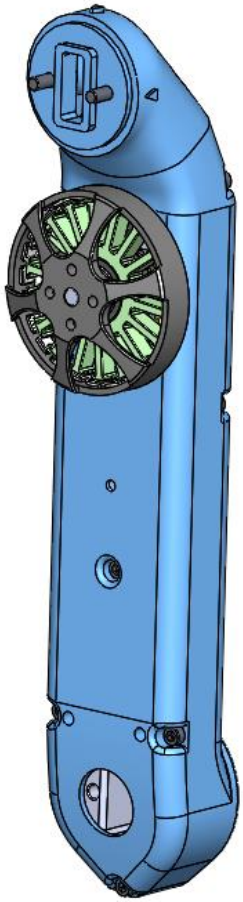
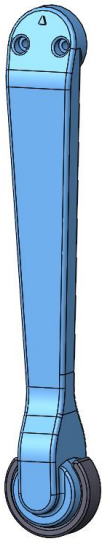
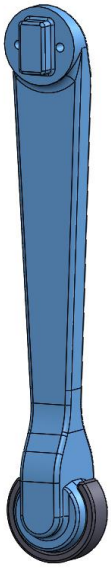
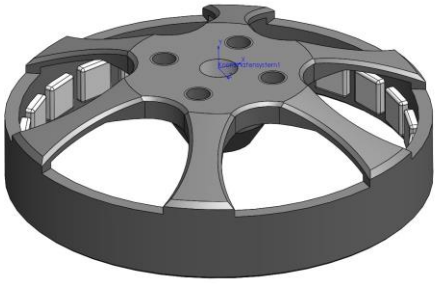
Biped Inertia Parameters

	Biped Body
Mass [kg]	0.61436936
Center of Mass Position [m] with respect to the URDF coordinate system.	X = -0.00245656 Y = -0.00078880 Z = 0.03308090
Inertia [kg*m^2] with respect to the center of mass aligned to the URDF coordinate system.	Lxx = 0.00132170 Lxy = 0.00000117 Lxz = 0.00025115 Lyx = 0.00000117 Lyy = 0.00144035 Lyz = -0.00001139 Lzx = 0.00025115 Lzy = -0.00001139 Lzz = 0.00198196
Screenshot	

	Hip FE Right Side	Hip FE Left Side
Mass [kg]	0.14004412	0.14004265
Center of Mass Position [m] with respect to the URDF coordinate system.	X = 0.01708233 Y = 0.00447099 Z = -0.01095846	X = 0.01708256 Y = -0.00446892 Z = -0.01095830
Inertia [kg*m^2] with respect to the center of mass aligned to the URDF coordinate system.	Lxx = 0.00007442 Lxy = -0.00000148 Lxz = 0.00002154 Lyx = -0.00000148 Lyy = 0.00013848 Lyz = 0.00001095 Lzx = 0.00002154 Lzy = 0.00001095 Lzz = 0.00009001	Lxx = 0.00007443 Lxy = 0.00000148 Lxz = 0.00002154 Lyx = 0.00000148 Lyy = 0.00013847 Lyz = -0.00001096 Lzx = 0.00002154 Lzy = -0.00001096 Lzz = 0.00009002
Screenshot		

	Upper Leg Right Side	Upper Leg Left Side
Mass [kg]	0.14853845	0.14853845
Center of Mass Position [m] with respect to the URDF coordinate system.	X = -0.00001377 Y = -0.01935853 Z = -0.07870700	X = 0.00001377 Y = 0.01935853 Z = -0.07870700
Inertia [kg*m^2] with respect to the center of mass aligned to the URDF coordinate system.	Lxx = 0.00041107 Lxy = 0.00000000 Lxz = -0.00000009 Lyx = 0.00000000 Lyy = 0.00041193 Lyz = 0.00004671 Lzx = -0.00000009 Lzy = 0.00004671 Lzz = 0.00003024	Lxx = 0.00041107 Lxy = 0.00000000 Lxz = 0.00000009 Lyx = 0.00000000 Lyy = 0.00041193 Lyz = -0.00004671 Lzx = 0.00000009 Lzy = -0.00004671 Lzz = 0.00003024
Screenshot		

	Lower Leg Right Side	Lower Leg Left Side
Mass [kg]	0.03117243	0.03117243
Center of Mass Position [m] with respect to the URDF coordinate system.	X = 0.00000000 Y = -0.00836718 Z = -0.09591877	X = 0.00000000 Y = 0.00836718 Z = -0.09591877
Inertia [kg*m^2] with respect to the center of mass aligned to the URDF coordinate system.	Lxx = 0.00011487 Lxy = 0.00000000 Lxz = 0.00000000 Lyx = 0.00000000 Lyy = 0.00011556 Lyz = 0.00000190 Lzx = 0.00000000 Lzy = 0.00000190 Lzz = 0.00000220	Lxx = 0.00011487 Lxy = 0.00000000 Lxz = 0.00000000 Lyx = 0.00000000 Lyy = 0.00011556 Lyz = -0.00000190 Lzx = 0.00000000 Lzy = -0.00000190 Lzz = 0.00000220
Screenshot		

Motor Rotor Antigravity 4004	Inertia [kg*m^2]
	Lxx = 0.00000245 Lxy = 0.00000000 Lxz = 0.00000000 Lyx = 0.00000000 **Lyy = 0.00000447** Lyz = 0.00000000 Lzx = 0.00000000 Lzy = 0.00000000 Lzz = 0.00000245 The reflected inertia at the output joint is 81 times higher compared to the inertia of the motor rotor. For rotation around the motor axis only the Lyy value should be relevant.