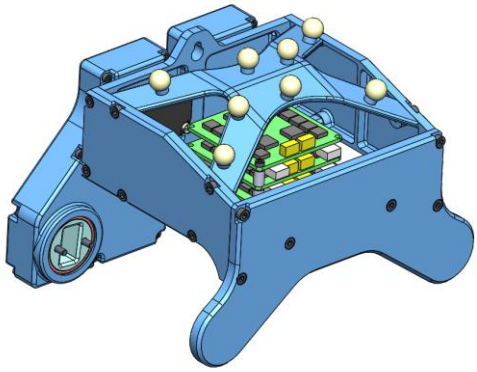
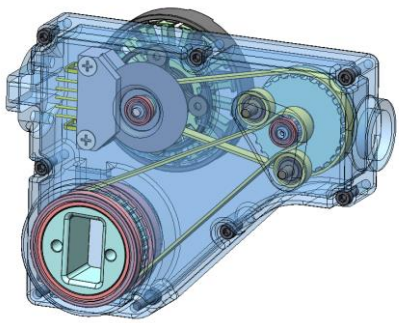
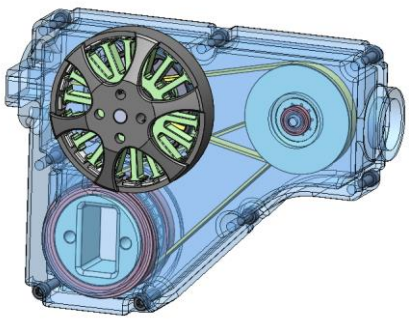
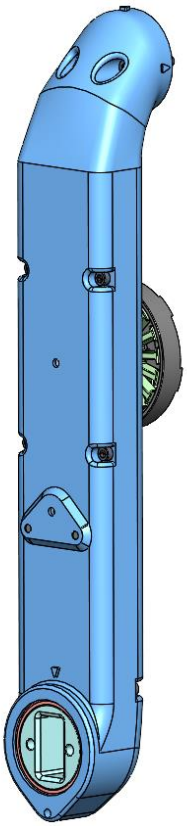
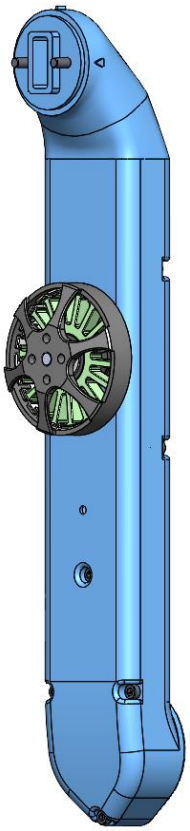
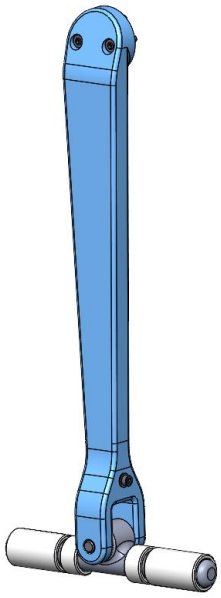
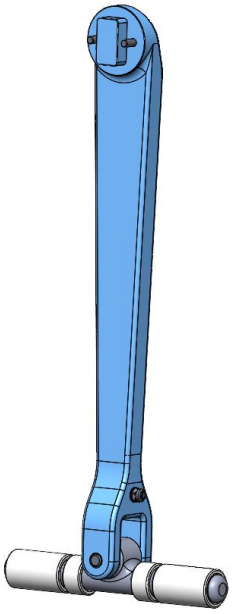
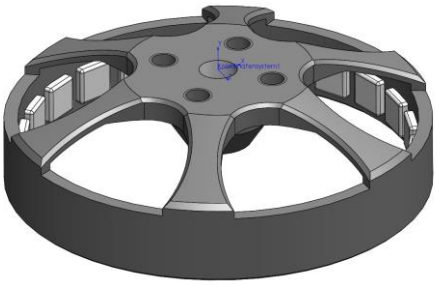
Biped 6dof v1 Inertia Parameters 20.5.2021

	Biped Body
Mass [kg]	0.63446156
Center of Mass Position [m] with respect to the URDF coordinate system.	X = -0.00052262 Y = -0.00076382 Z = 0.03367157
Inertia [kg*m^2] with respect to the center of mass aligned to the URDF coordinate system.	Lxx = 0.00134972 Lxy = 0.00000210 Lxz = 0.00027137 Lyx = 0.00000210 Lyy = 0.00151870 Lyz = -0.00001110 Lzx = 0.00027137 Lzy = -0.00001110 Lzz = 0.00207283
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]	0.15627530	0.15627530
Center of Mass Position [m] with respect to the URDF coordinate system.	X = -0.00001312 Y = -0.01949046 Z = -0.11145002	X = 0.00001312 Y = 0.01949046 Z = -0.11145002
Inertia [kg*m^2] with respect to the center of mass aligned to the URDF coordinate system.	Lxx = 0.00054578 Lxy = 0.00000000 Lxz = -0.00000007 Lyx = 0.00000000 Lyy = 0.00054759 Lyz = 0.00004703 Lzx = -0.00000007 Lzy = 0.00004703 Lzz = 0.00003216	Lxx = 0.00054578 Lxy = 0.00000000 Lxz = 0.00000007 Lyx = 0.00000000 Lyy = 0.00054759 Lyz = -0.00004703 Lzx = 0.00000007 Lzy = -0.00004703 Lzz = 0.00003216
Screenshot		

	Lower Leg Right Side	Lower Leg Left Side
Mass [kg]	0.05746831	0.05746831
Center of Mass Position [m] with respect to the URDF coordinate system.	X = -0.00005422 Y = -0.00837604 Z = -0.13202657	X = 0.00005422 Y = 0.00837604 Z = -0.13202657
Inertia [kg*m^2] with respect to the center of mass aligned to the URDF coordinate system.	Lxx = 0.00035375 Lxy = 0.00000000 Lxz = 0.00000013 Lyx = 0.00000000 Lyy = 0.00036756 Lyz = 0.00000474 Lzx = 0.00000013 Lzy = 0.00000474 Lzz = 0.00001657	Lxx = 0.00035375 Lxy = 0.00000000 Lxz = -0.00000013 Lyx = 0.00000000 Lyy = 0.00036756 Lyz = -0.00000474 Lzx = -0.00000013 Lzy = -0.00000474 Lzz = 0.00001657
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.