

Polyeder

? 1 Kästchen $\equiv 1 \text{ m} = 10 \text{ cm}$

Quader 0,5 tief

Kleiner Quader 0,3 tief

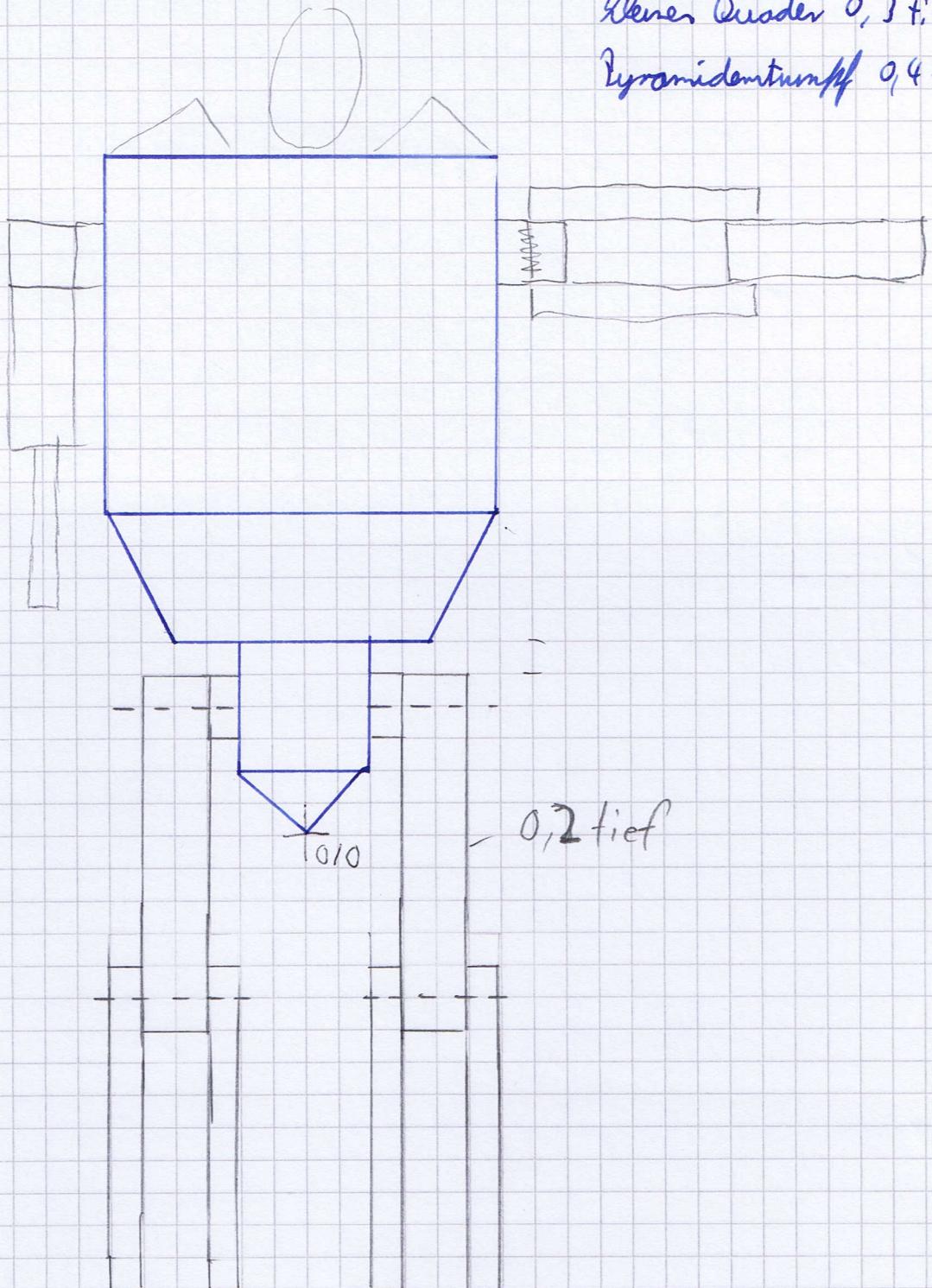
Pyramidenumlauf 0,4 tief

2m

1,75m

0,10

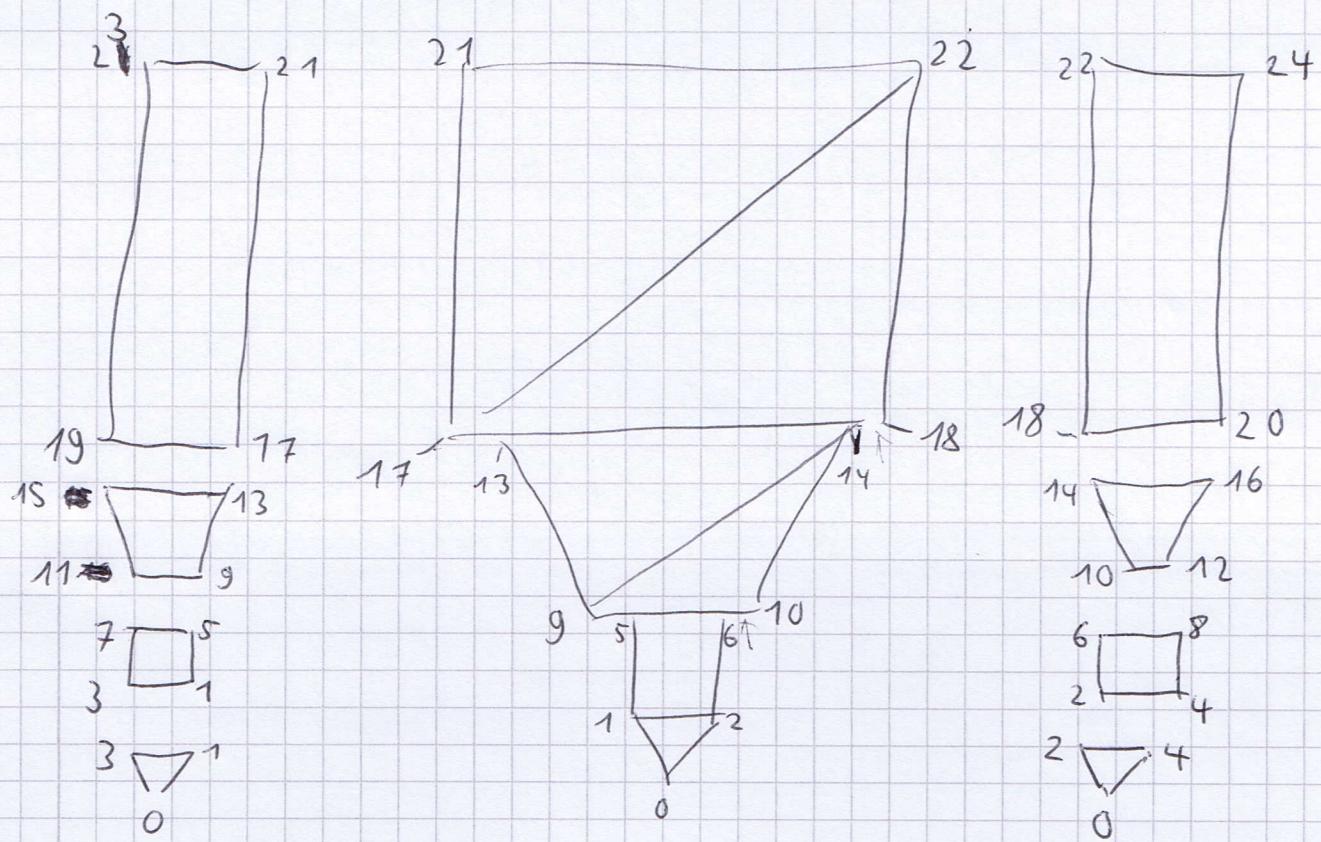
0,2 tief



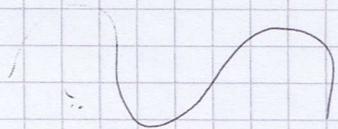
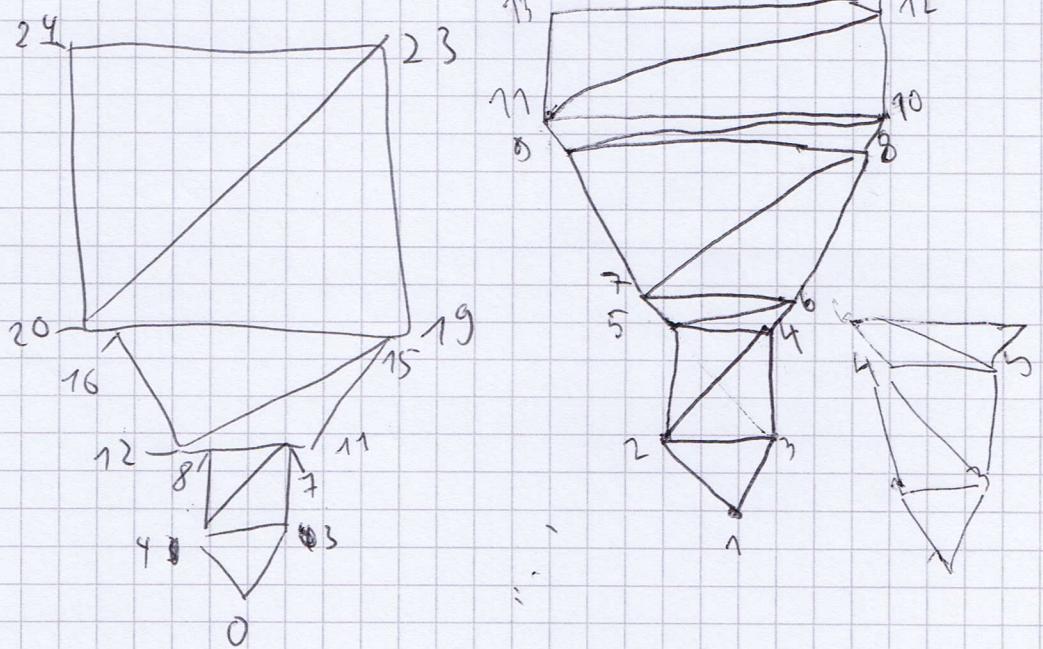
L

V

R

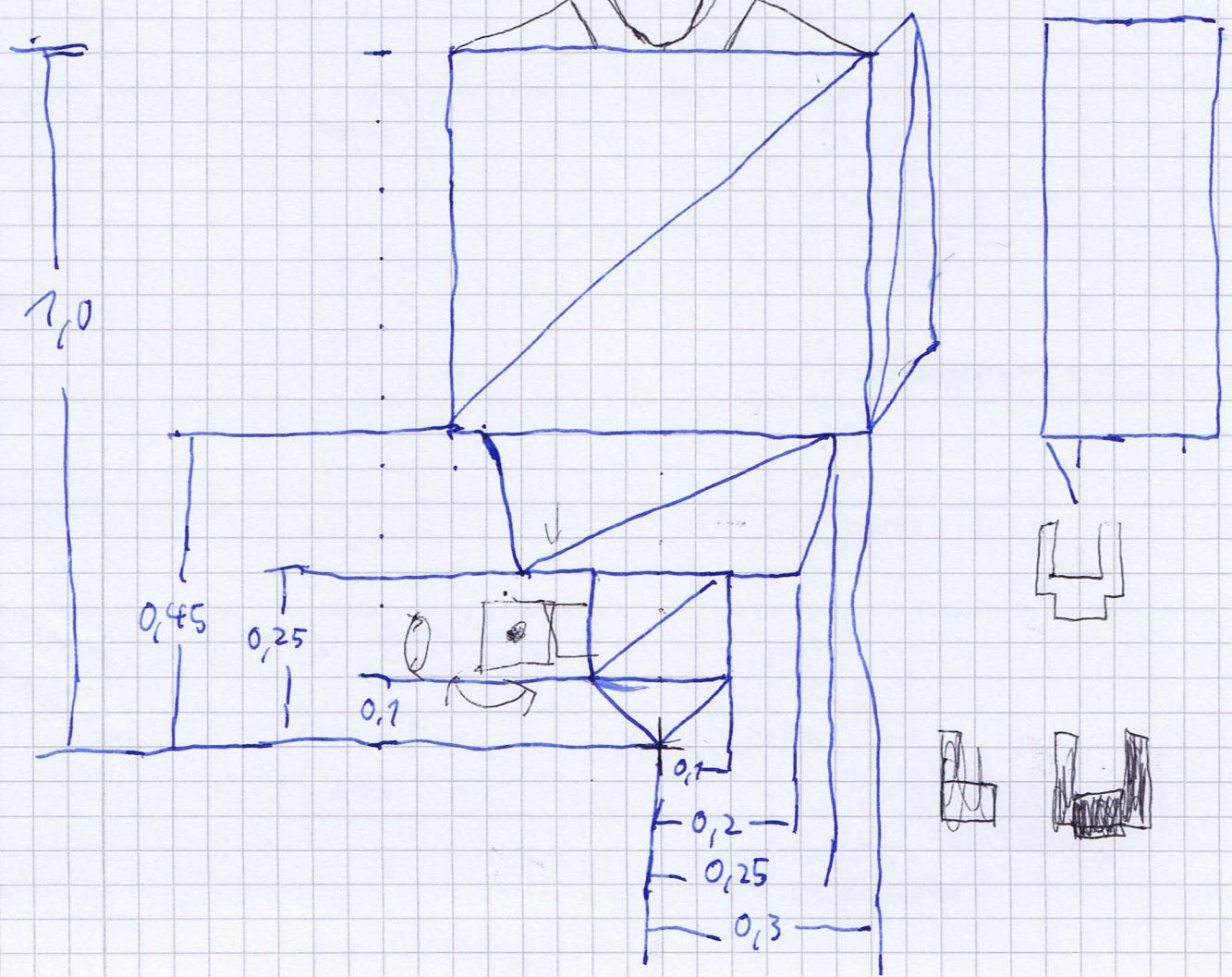
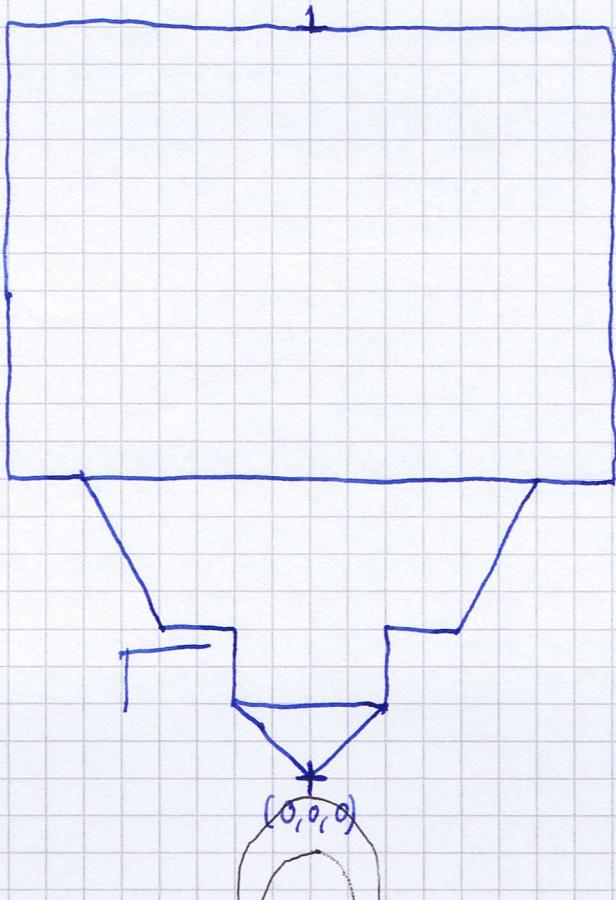


H wie V nur Tiefe -

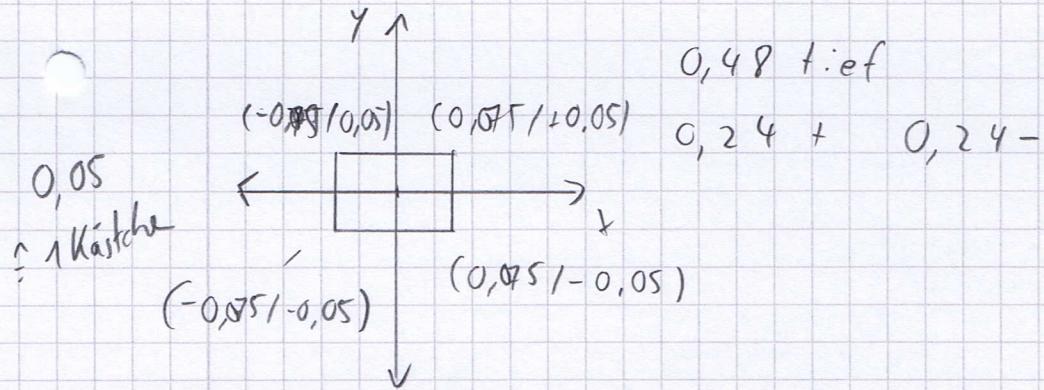


Torso

20 Kästchen $\stackrel{?}{=} 7\text{m}$; 7 Kästchen $\stackrel{?}{=} 5\text{cm} = 0,05\text{m}$

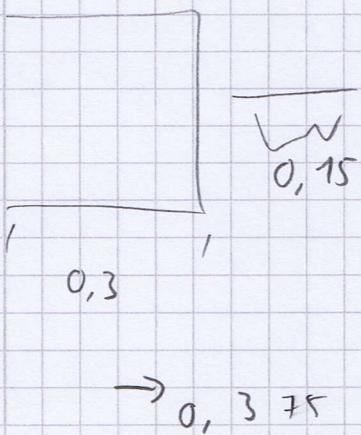


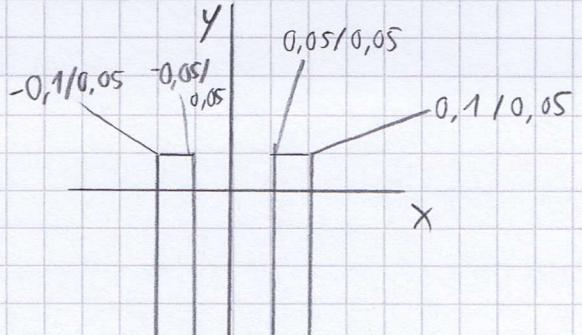
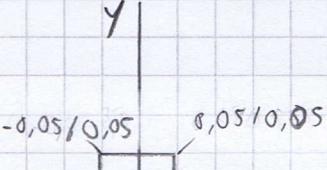
foot



linder Oberarm scale $0,5 / 0,9 / 0,7$
 $0,0375 / 0,45 / 0,112$

y Unterarm





4 Kästchen
0,05/0,05

1 Kästchen
0,05

$-0,05/-0,5$

$0,05/-0,5$

$-0,1/-0,45$

$-0,05/-0,45$

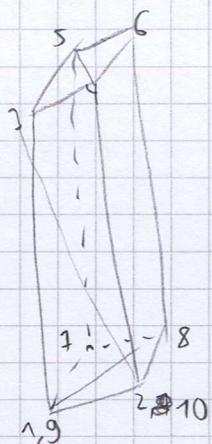
$0,1/-0,45$

$0,1, 4, 5, 6, 7, 2, 3, 0, 1$

$1, 3, 5, 7$ night

left

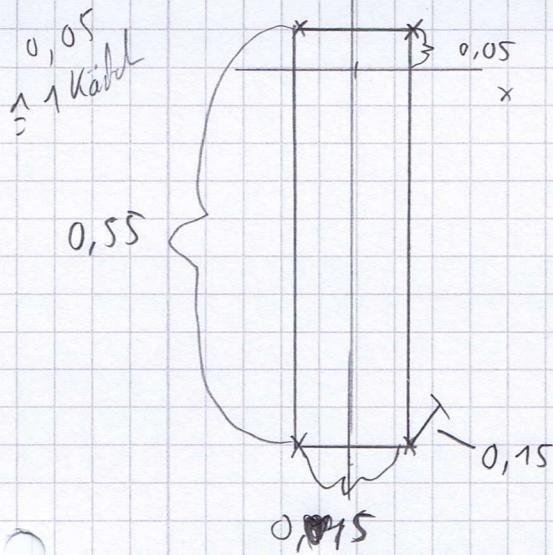
$0, 2, 4, 6$



Textur

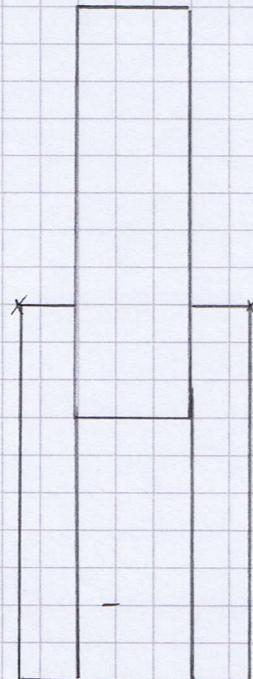
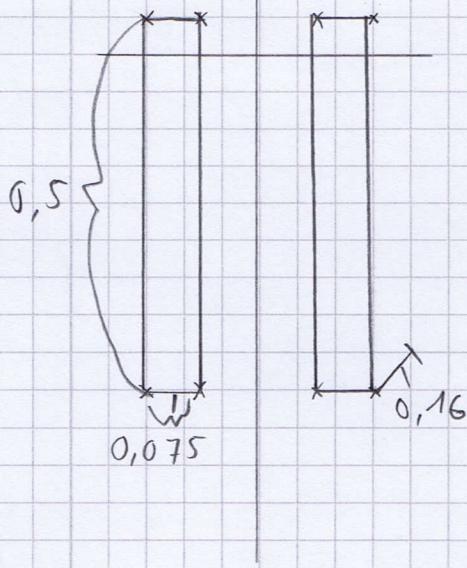
27.4

Fuß Berechnung



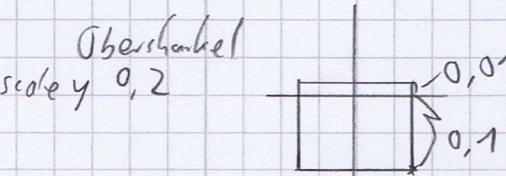
Ziel 0,1 Höhe $0,1 = x \cdot 0,55 \Leftrightarrow$

Unterschenkel - 0,4 y 0,15 Überstand



$$\text{Oberschenkel} \times \frac{5}{8} = 0,45$$

$$2 \cdot 3 = 0,45$$



0,11 ges

-0,46 Sindig

0,11
-0,35 passt

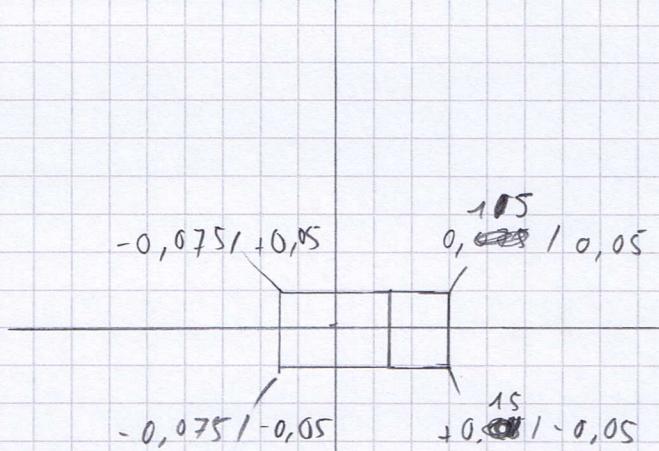
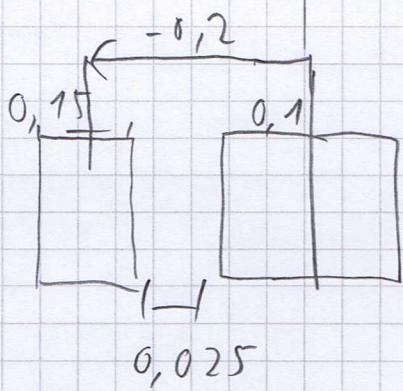
90° Reckung ?

Fuß 0,15 hoch

VG

Thigh Joint

3.05.15

Back $z^- + 0,075$ Front $z^- + 0,1$ 

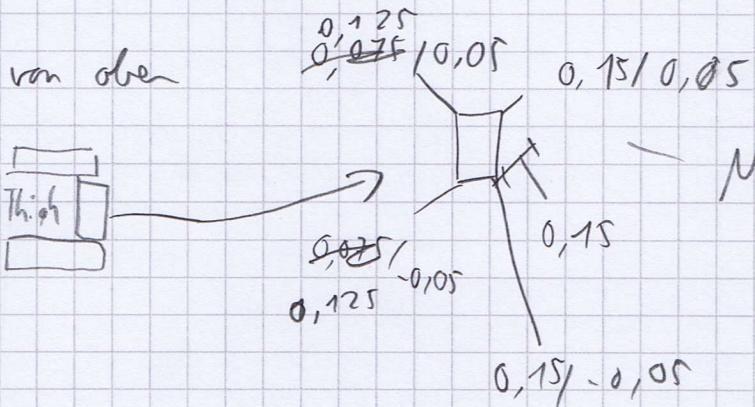
H/G

z

Front

~~Back~~ = $-0,075$ Back = $-0,1$

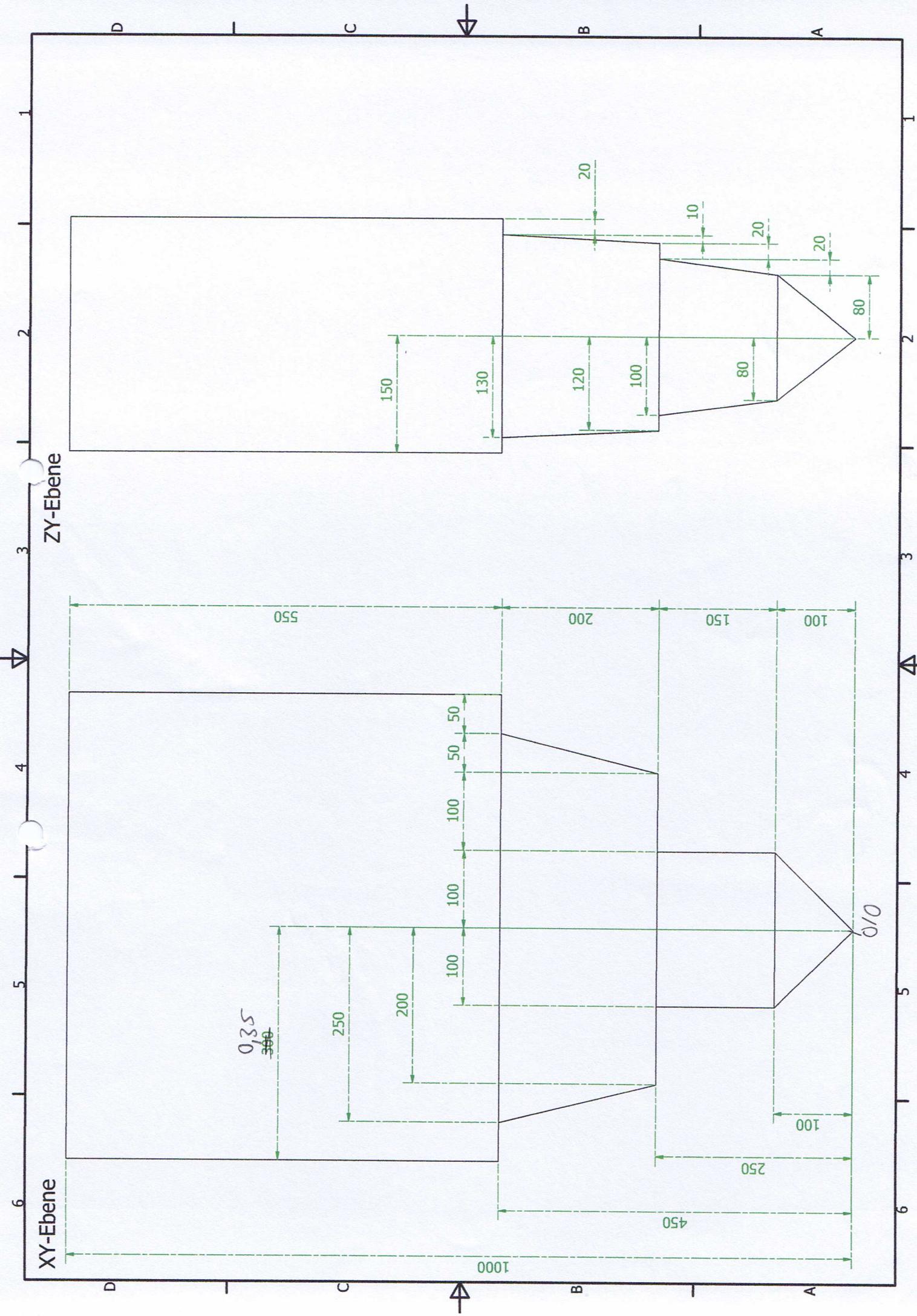
von oben



Mittelfüch

Rechts 90° y

~~d. 0,05~~
d. (es 0,05 dick)

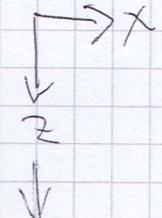


hill (nied, 18)



rotation Front
rotation Lateral

rotation ~~Upper~~ arm/lower



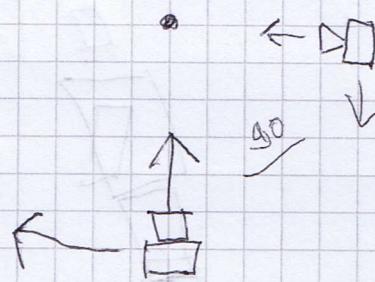
rechts vor
vorne betrachtet

lateral
mit links

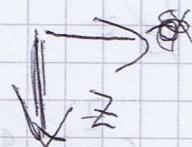
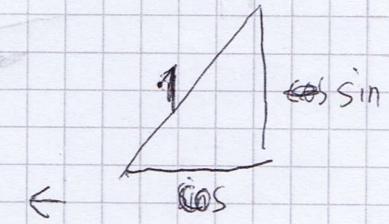
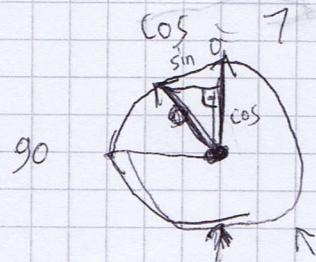
rotation Front

Strength

rotation Lateral



$$\sin = 0$$



in sehr vor -1 0 +1

max null rotation lateral

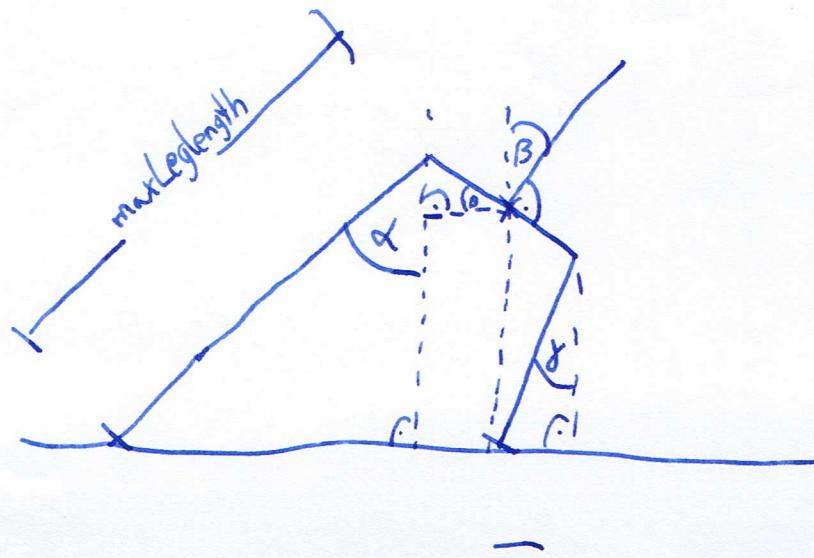
0 - -0,5

Robot.cpp

heightOuterThigh

Unprung

in cap ta
GAGA
HHAG



$$\alpha = 7,7 \cdot \beta$$

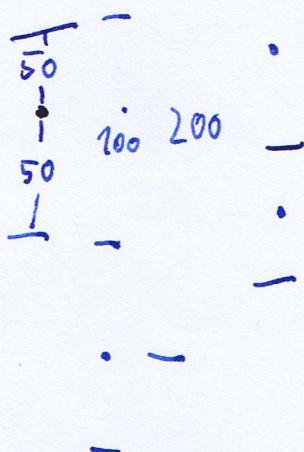
$$\gamma = 0,9\beta$$

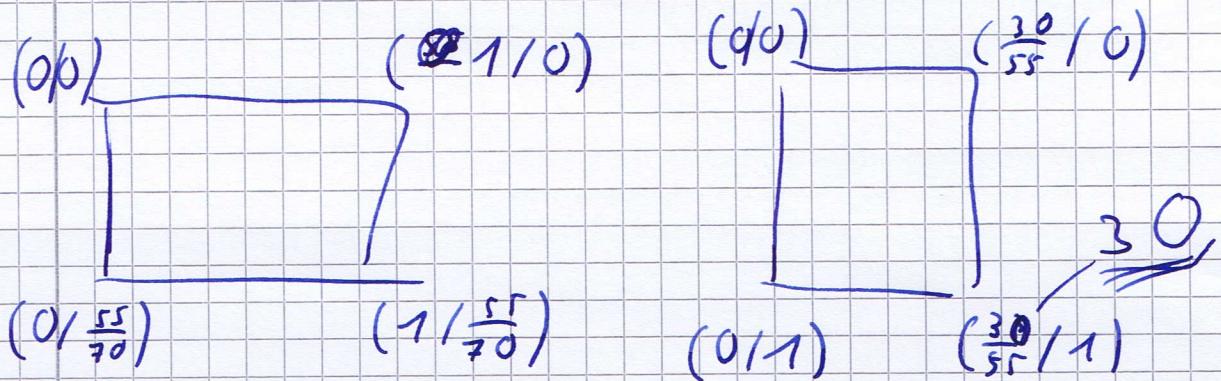
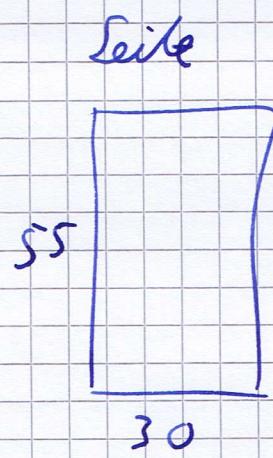
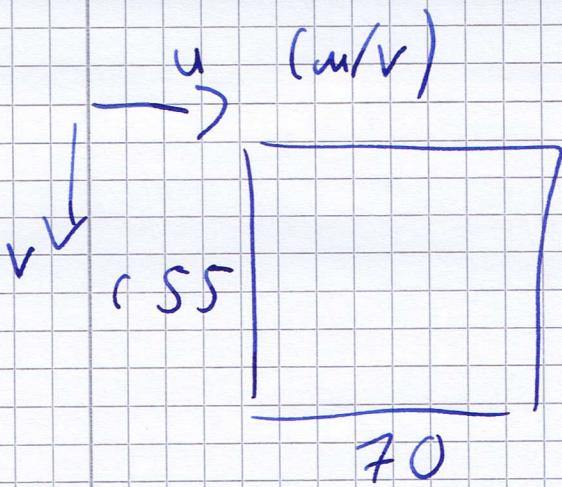
$$\sin \beta = \frac{\text{detted}}{x\text{Diff}}$$

$$\text{eos}(\gamma) = \frac{\text{HeightInner}}{\text{LegInn}}$$

$$\text{LegInn} = \frac{\text{HeightInn}}{\cos}$$

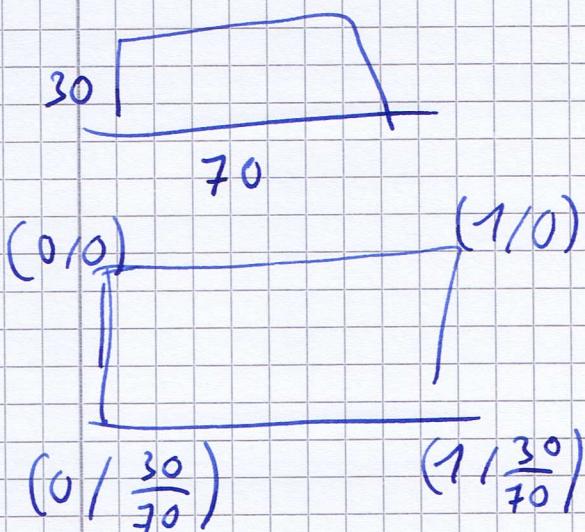
- - - -





Front Back

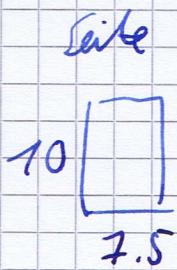
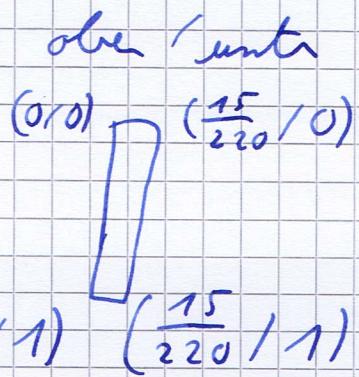
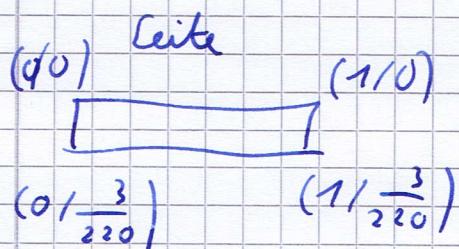
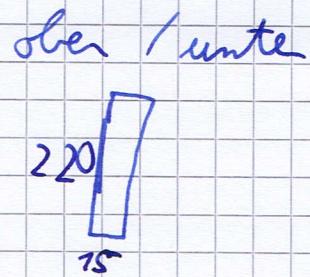
Ober / unter



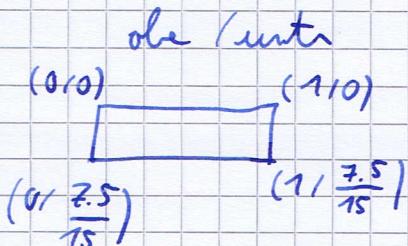
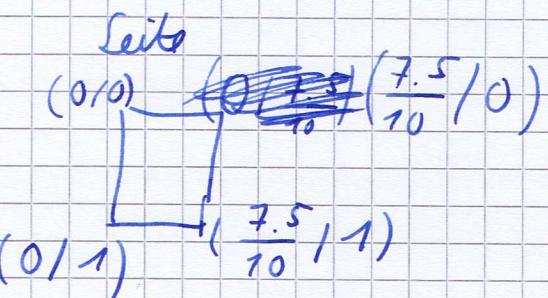
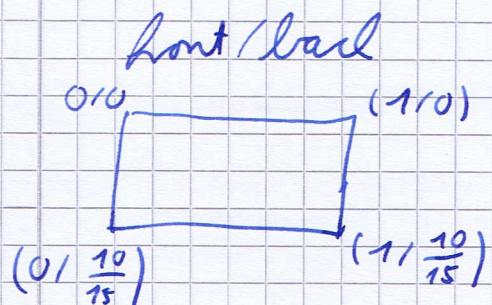
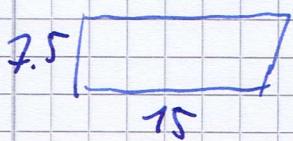
Toro diutor Quadra

front/back
wird nicht gezeichnet

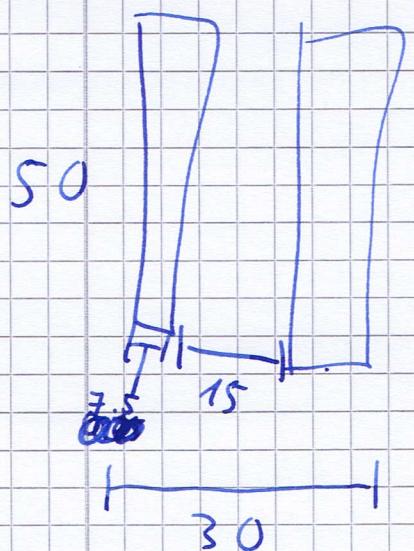
Shi ohne Saiten



Shoulder Joint



front / back

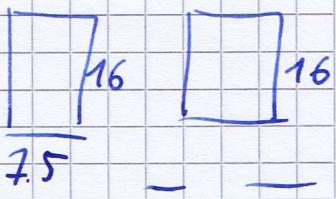


Seite

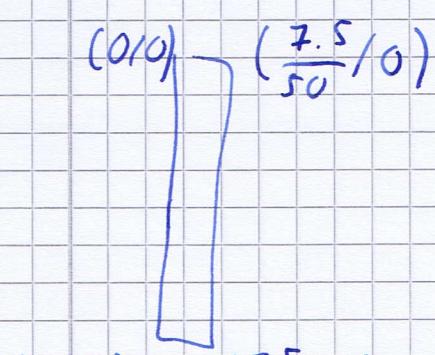


Chanc

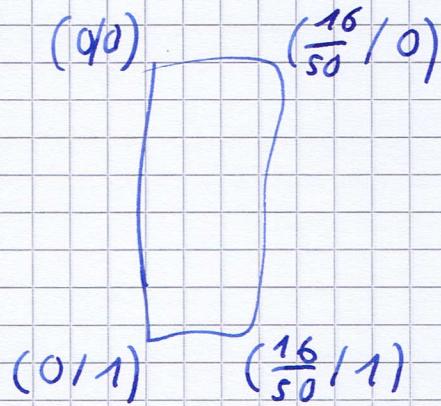
oben/unten



front / back



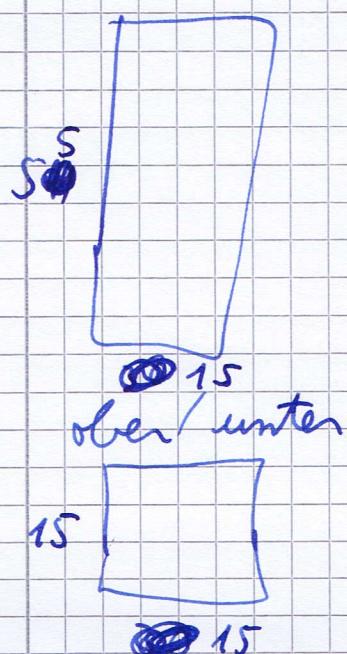
Seite



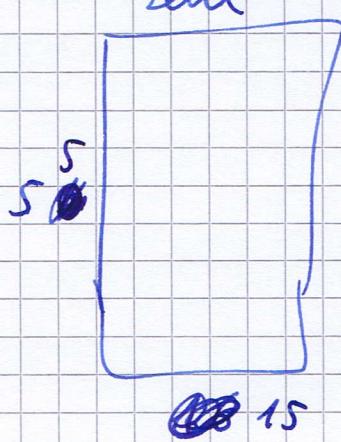
(0/0) $(\frac{7.5}{16}/0)$

(0/1) $(\frac{7.5}{16}/1)$

front/back

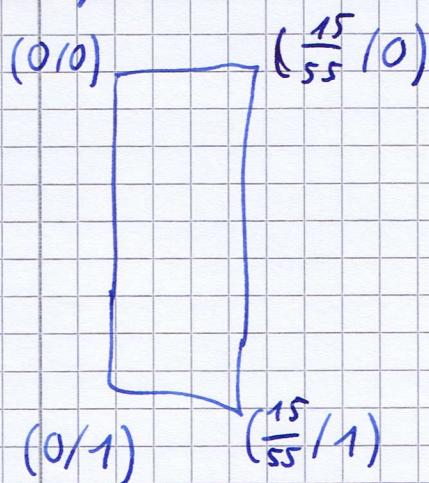


Leite

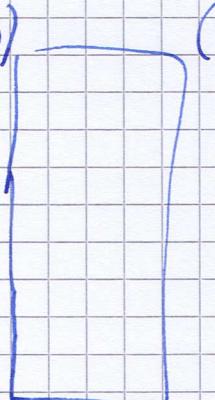


Thigh

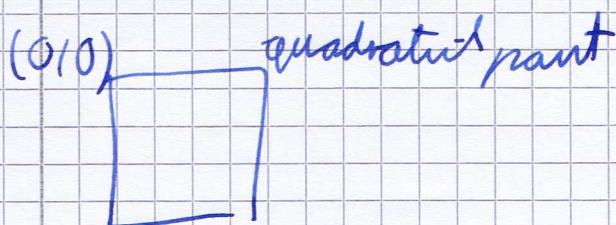
front/back



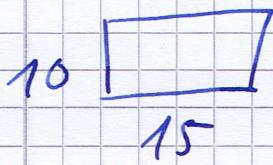
Leite identisch zu front/back



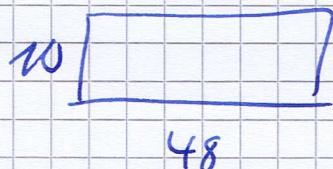
ober/unten



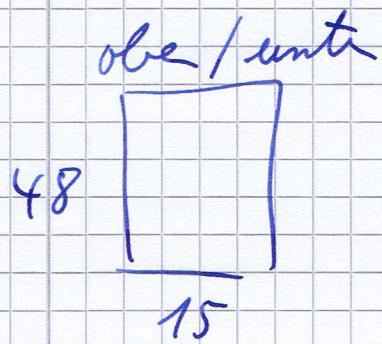
front back



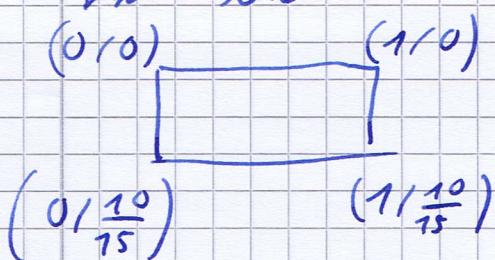
Seite



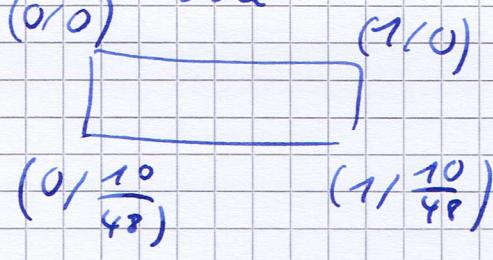
Foot



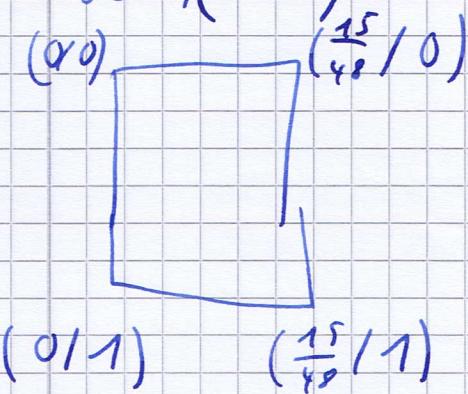
front back



Seite



oben / unten



(0/1) ($\frac{15}{48}$ / 1)