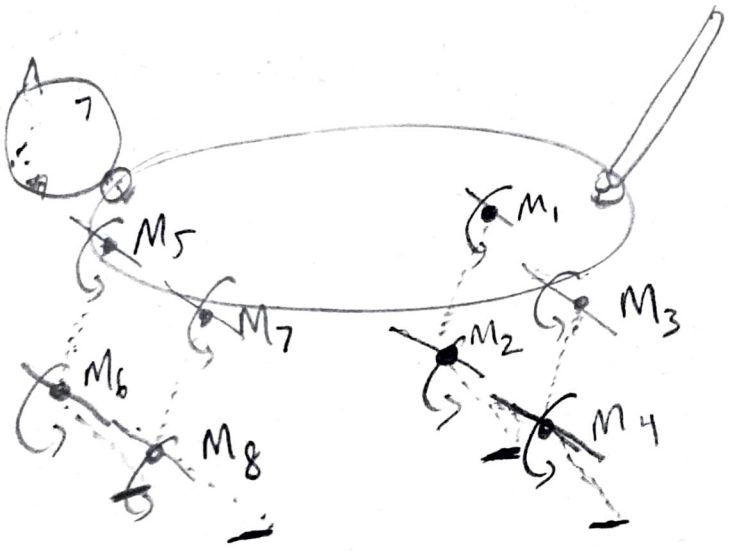
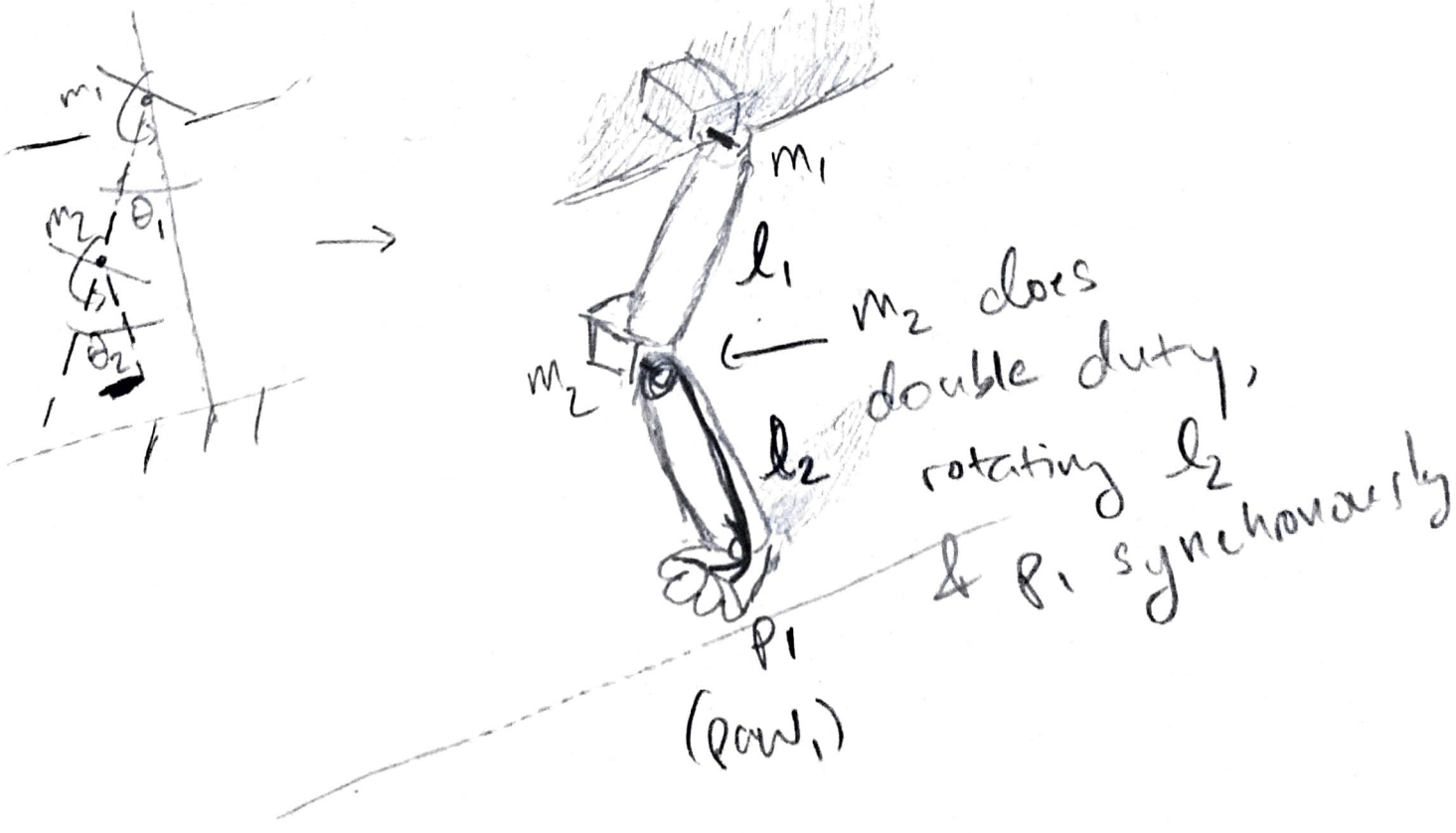
Cat concept

$M_i$ = motor i




leg zoom in



cat concept

moving, but unpowered components

↳ head, tail


constrained rotation | swivel |

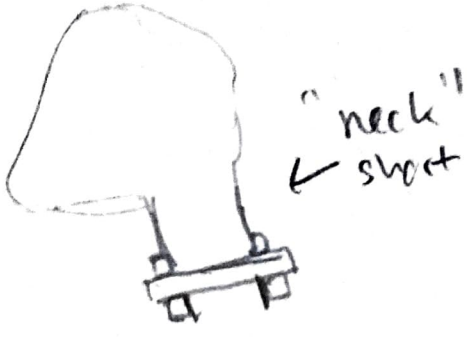
↳ torsion spring

↳ hard stops

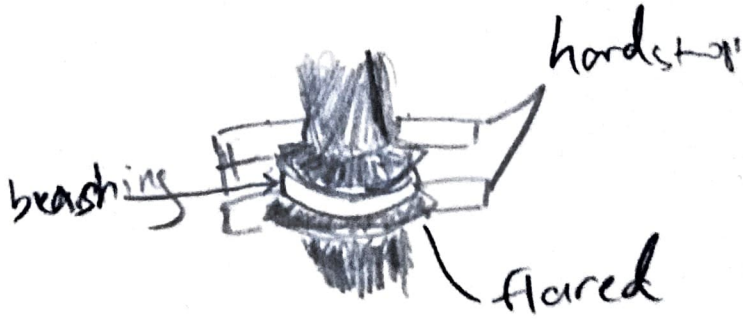
goal:
don't look creepy!!

H

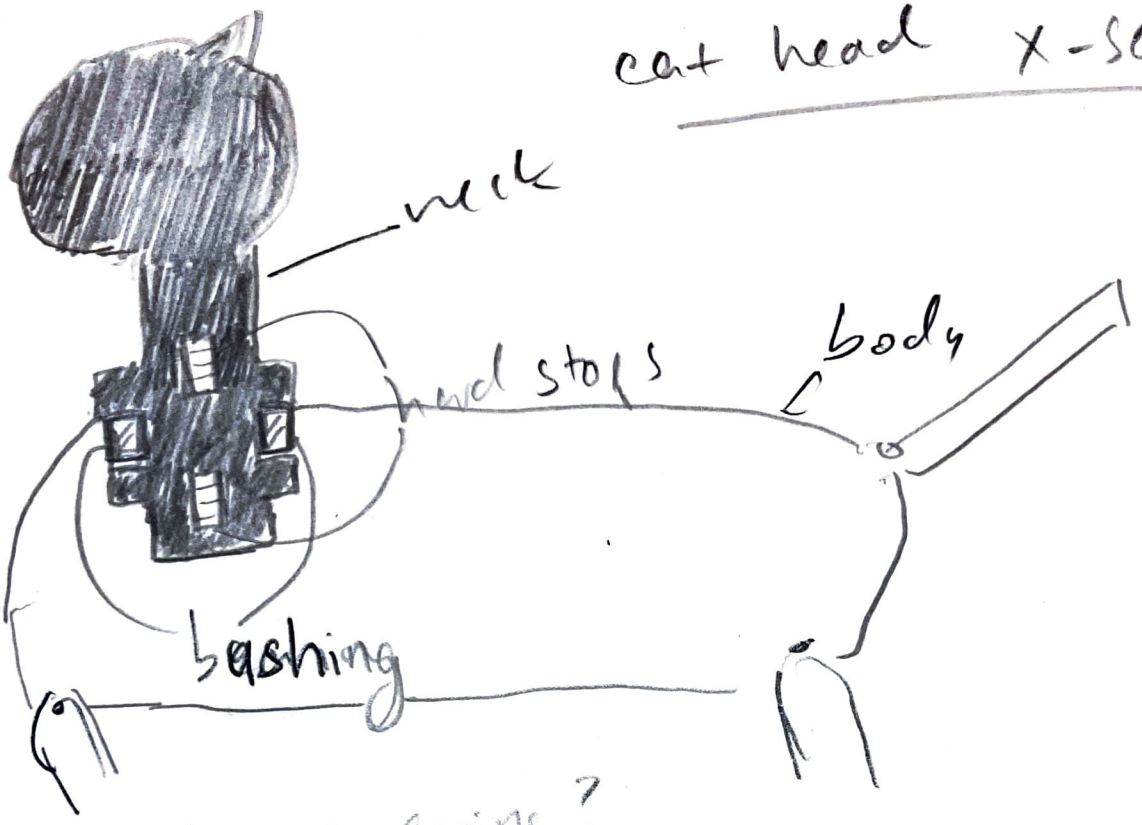
front view




isometric view
x-ray

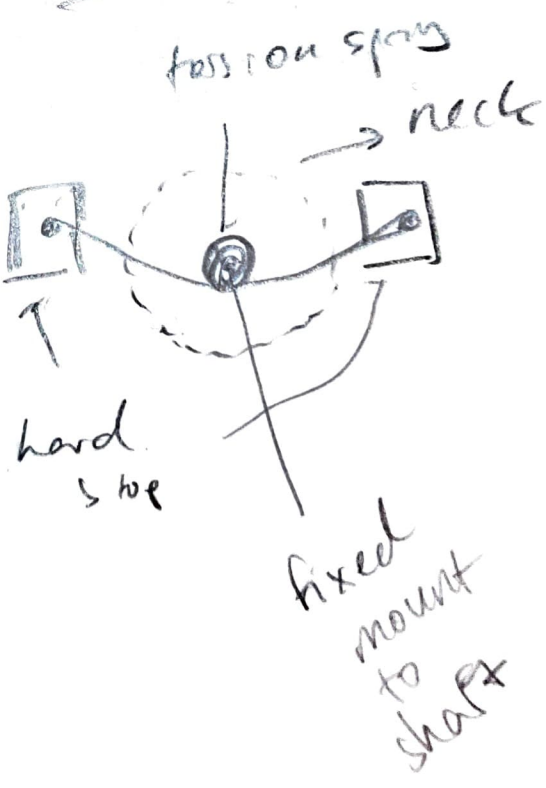


# cat head x-section



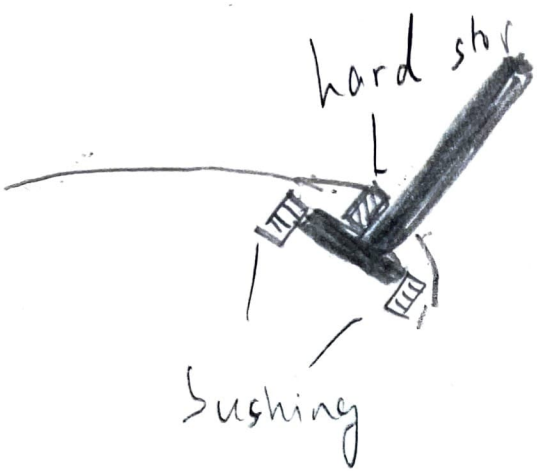

torsion spring?


bottom view

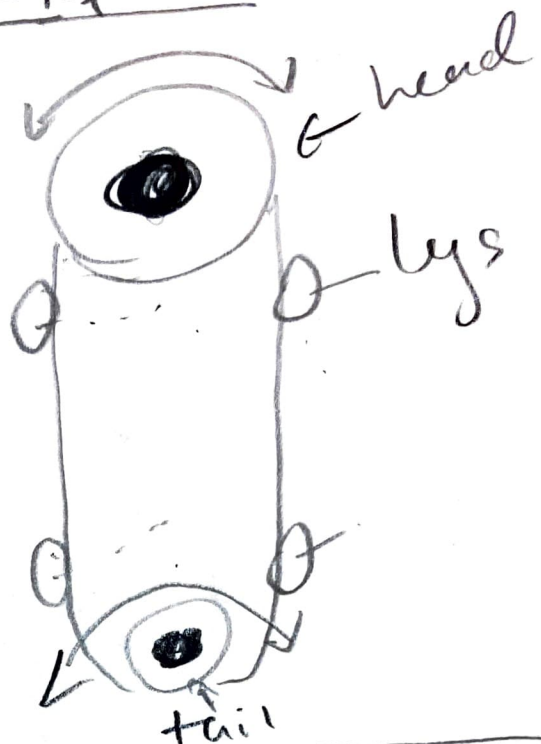


Cat concept

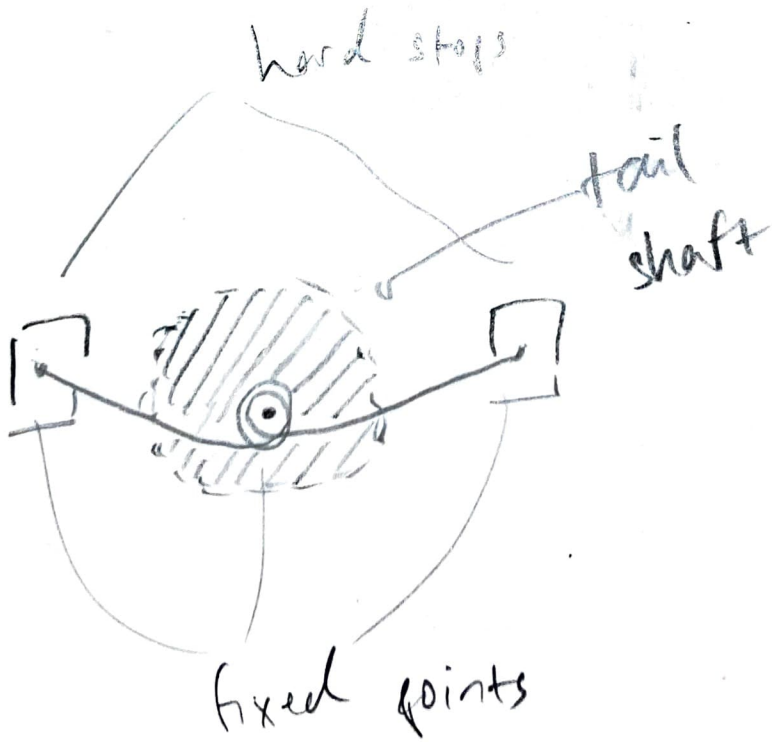
tail




cat top view

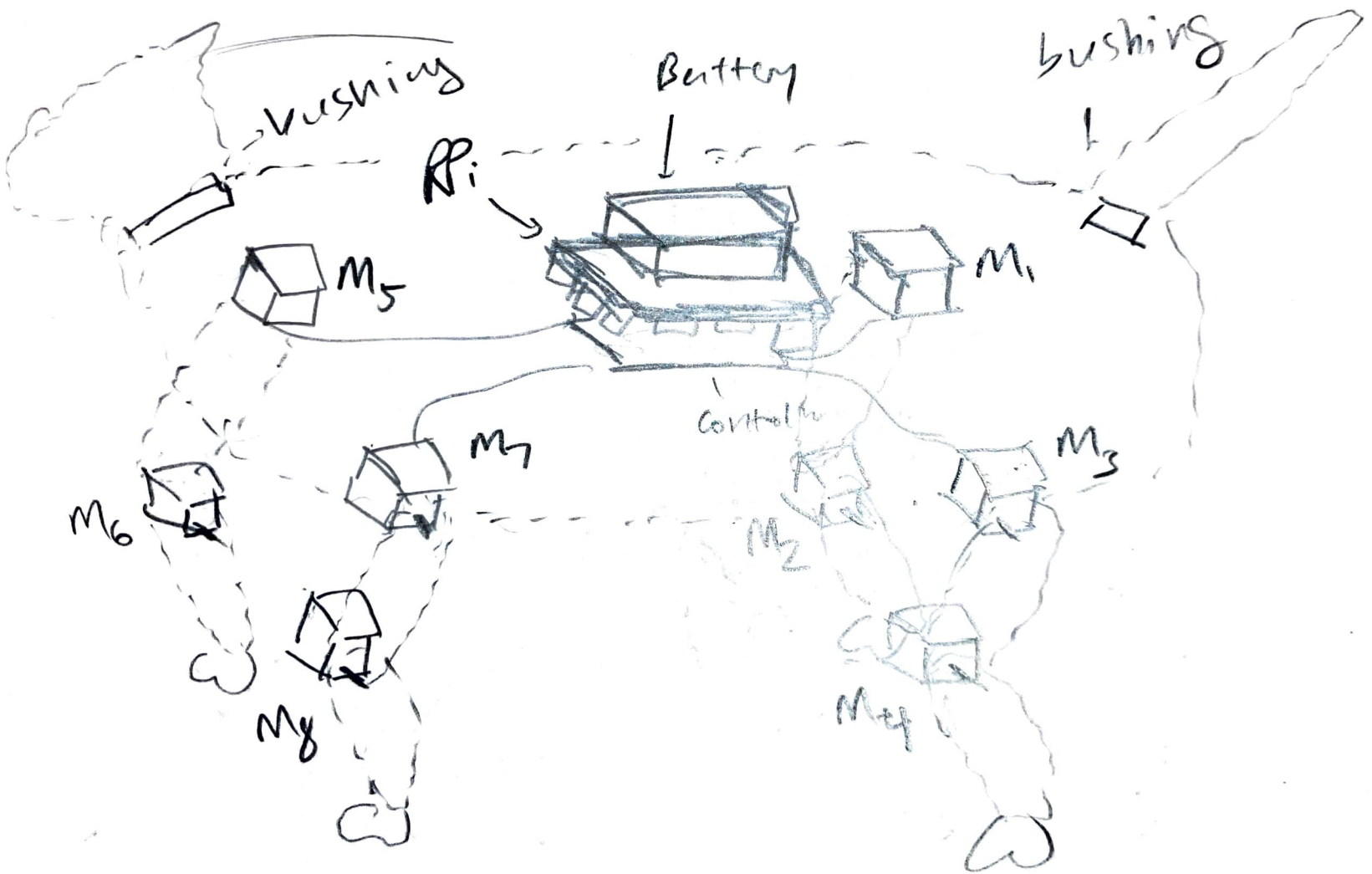



torsion spring → same as head



Cat concept

Component view

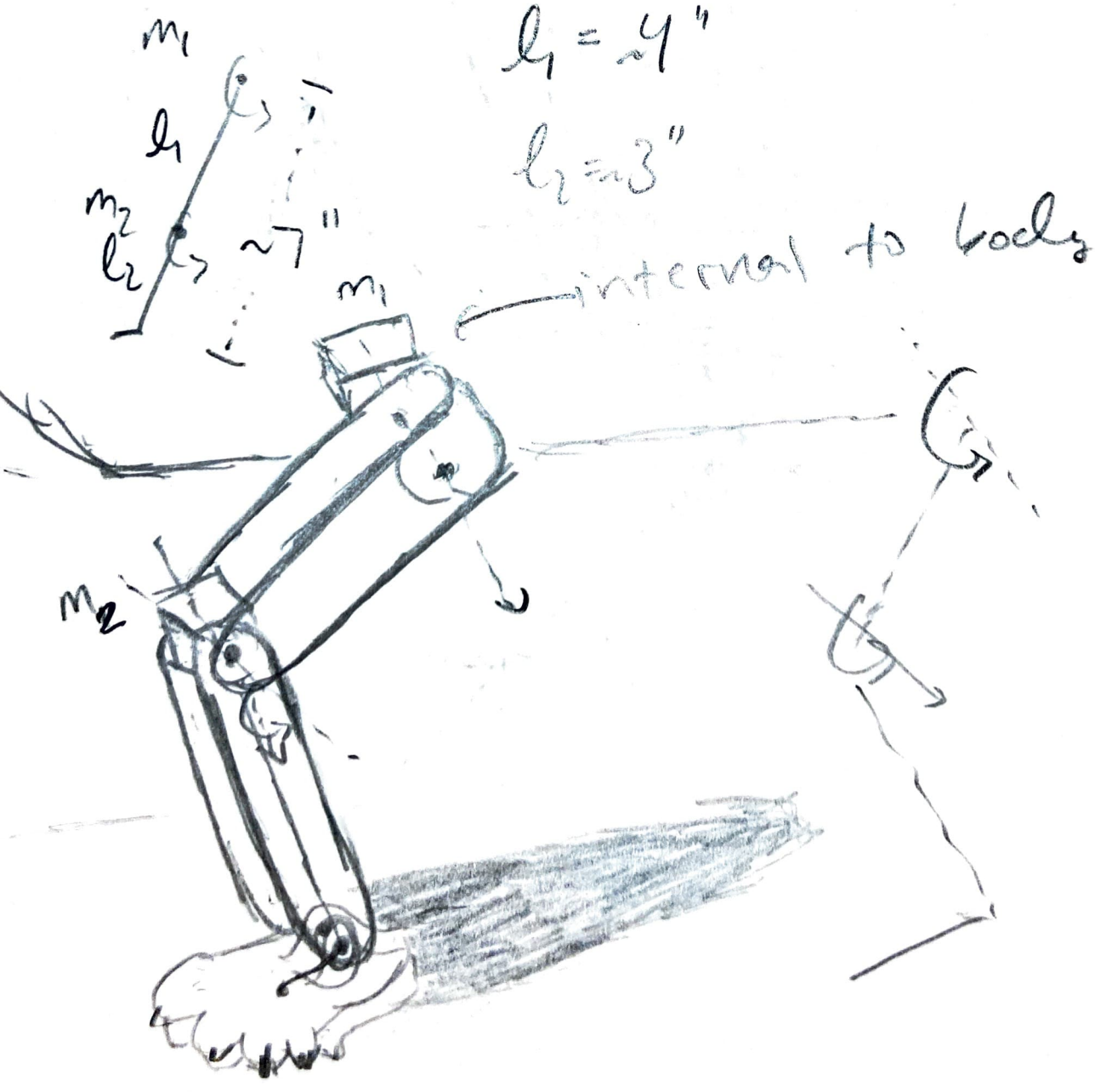


Actual size:

emulate a small kitten

↳ 4-5 lbs ~ 2 kg

each leg is ~7"



With a small-kitten-scale, robot should be able to balance on 2 paws at a time