t(posx, 0, posz)
Ry(angleY)
Rx(angleX)
body()

t(1,1.2,0)
Rz(15)
Rx(arm1angle)
arm()

t(-1,1.2,0)
Rz(15)
Rx(arm2angle)
arm()

t(0,-1.0,0)
Rz(-15)
Rx(elbow1angle)
elbow()

t(0,-1.0,0)
Rz(-15)
Rx(elbow1angle)
elbow()

t(0,-1.0,0.0)
Rx(hand1angle)
hand()

t(0,-1.0,0)
Rx(hand1angle)
hand()

t(0.4,0.1,0)
Rx(thigh1angle)
thigh()

t(-0.4,0.1,0)
Rx(thigh2angle)
thigh()

t(0,-1.1,0)
Rx(tibia1angle)
tibia()

t(0,-1.1,0)
Rx(tibia2angle)
tibia()

t(0,-1,0)
Rx(foot1angle)
foot()

t(0,-1,0)
Rx(foot2angle)
foot()