Leg Link structure

(this data is for Left Leg. For Right Leg, change the signal of y values in relative position)

Torso

stlexport

Mass 4.638838036

COM

Xcbar = 57.398606158

Ycbar = -0.304170719

Zcbar = 134.904069352

Inertiamtx

Ixx = 43249.589454061

Iyy = 32832.240627750

Izz = 26890.957053877

Pyz = -34.554417674

Pxz = 289.646895846

Pxy = 17.645766171

Relative position000

Rpy000

Leg1

Stlexport o

mass = 0.274425794

com

Xcbar = 1.415017702

Ycbar = -0.000000000

Zcbar = -65.512458575

Ixx = 148.345278236

Iyy = 591.755842056

Izz = 481.510239752

Pyz = -0.000000000

Pxz = 11.936401210

Pxy = -0.000000000

Relative position

델타 XC = 73.250000000 X = 73.250000000

YC = 71.350000000 Y = 71.350000000

ZC = -24.000000000 Z = -24.000000000

델타 XC = 73.250000000 X = 73.250000000

YC = 71.350000000 Y = 71.350000000

ZC = 64.000000000 Z = 64.000000000

Rpy000

leg2

stlexport o

mass = 0.046874646

com

Xcbar = -0.466596392

Ycbar = 0.283403608

Zcbar = 0.000000000

Ixx = 46.779986918

Iyy = 46.779986918

Izz = 75.562473483

Pyz = 0.206066900

Pxz = -0.206066900

Pxy = -0.003764859

Relative position

델타 XC = 10.000000000 X = 10.000000000

YC = 71.350000000 Y = 71.350000000

ZC = -62.750000000 Z = -62.750000000

델타 XC = 138.000000000 X = 138.000000000

YC = 71.350000000 Y = 71.350000000

ZC = -62.750000000 Z = -62.750000000

Rpy000

Leg3

Stlexport o

mass = 0.547628097

com

Xcbar = -0.028502948

Ycbar = -0.022022997

Zcbar = -102.776631567

Ixx = 4948.744844660

Iyy = 4378.525598681

Izz = 646.549753602

Pyz = 0.013099467

Pxz = -0.000095871

Pxy = 0.000032920

Relative position

델타 XC = 73.250000000 X = 73.250000000

YC = 8.100000000 Y = 8.100000000

ZC = -62.750000000 Z = -62.750000000

델타 XC = 73.250000000 X = 73.250000000

YC = 136.100000000 Y = 136.100000000

ZC = -62.750000000 Z = -62.750000000

Rpy000

Leg4

Stlexport o

mass = 0.308203309

COM

Xcbar = 0.455876571

Ycbar = -0.000680272

Zcbar = -157.600147962

Ixx = 1111.794373738

Iyy = 652.897999488

Izz = 503.741046507

Pyz = -0.002022785

Pxz = -1.851394388

Pxy = -0.000042170

Relative position

델타 XC = 73.250000000 X = 73.250000000

YC = 29.600000000 Y = 29.600000000

ZC = -270.250000000 Z = -270.250000000

델타 XC = 73.250000000 X = 73.250000000

YC = 114.600000000 Y = 114.600000000

ZC = -270.250000000 Z = -270.250000000

Rpy000

leg5

stlexport o

mass = 0.046874646

COM

Xcbar = 0.283403608

Ycbar = 0.466596392

Zcbar = 0.000000000

Ixx = 46.779986918

Iyy = 46.779986918

Izz = 75.562473483

Pyz = 0.206066900

Pxz = 0.206066900

Pxy = 0.003764859

Relative position

델타 XC = 73.750000000 X = 73.750000000

YC = 9.600000000 Y = 9.600000000

ZC = -458.500000000 Z = -458.500000000

델타 XC = 73.750000000 X = 73.750000000

YC = 134.600000000 Y = 134.600000000

ZC = -458.500000000 Z = -458.500000000

Rpy000

leg6

stlexport o

mass = 0.429111905

COM

Xcbar = 5.247919095

Ycbar = -0.000000000

Zcbar = -34.721920396

Ixx = 463.468834406

Iyy = 1066.254938543

Izz = 801.229791360

Pyz = 0.000000000

Pxz = -87.598043075

Pxy = -0.000000000

Relative position

델타 XC = 12.000000000 X = 12.000000000

YC = 72.850000000 Y = 72.850000000

ZC = -458.500000000 Z = -458.500000000

델타 XC = 137.000000000 X = 137.000000000

YC = 72.850000000 Y = 72.850000000

ZC = -458.500000000 Z = -458.500000000

Rpy000