

# OpenWalk

6378, Informal Robotics, Fall 2015.

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Jose Guillermo Saavedra Roman  
Enol Vallina Fernandez



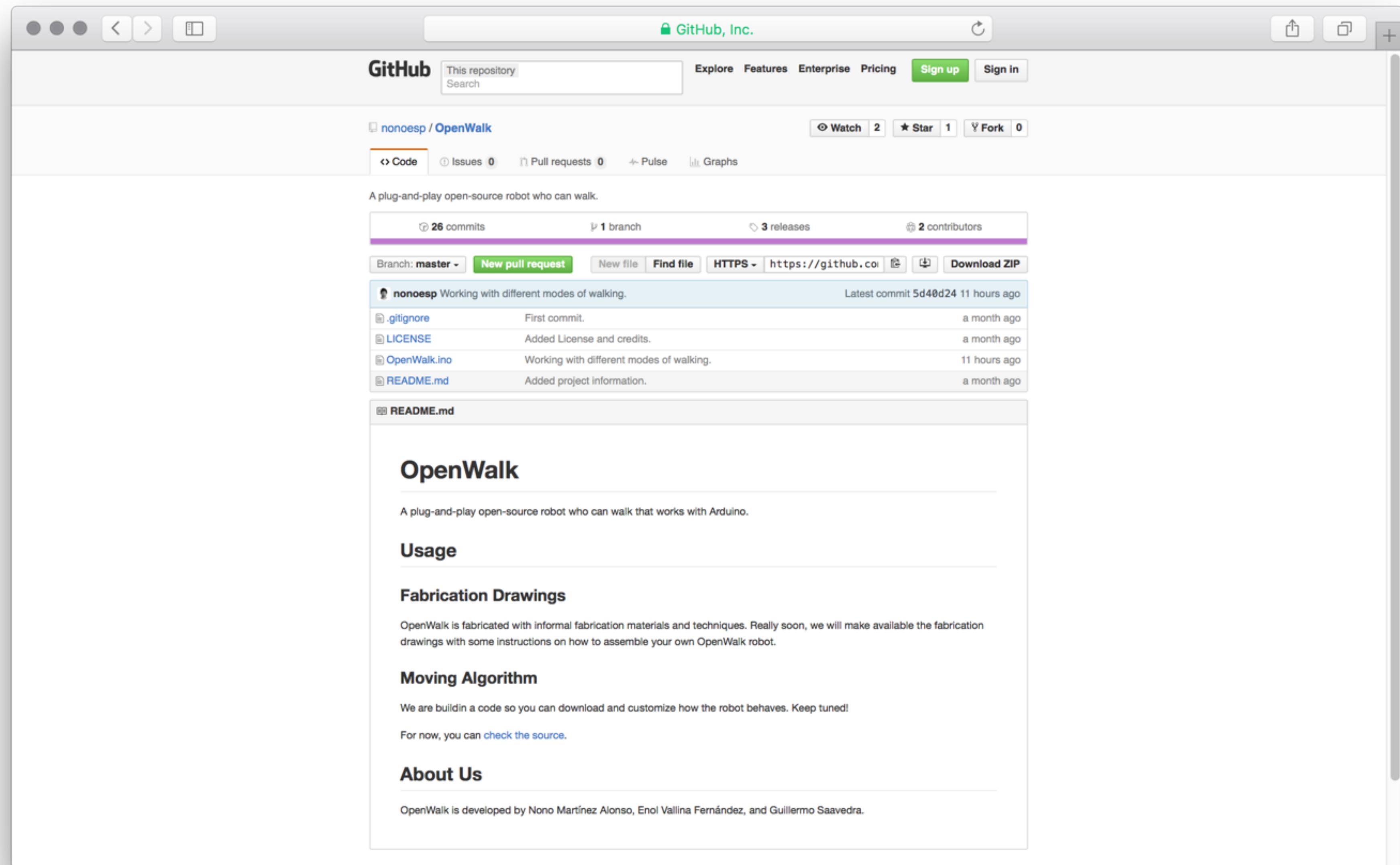
Bioinspired. Open Source. Plug & Play.







Project Ara. Google

A screenshot of a GitHub repository page for "nonoesp / OpenWalk". The page shows a summary of the repository's activity, including 26 commits, 1 branch, 3 releases, and 2 contributors. The "Code" tab is selected, showing a commit history. The latest commit was made 11 hours ago by "nonoesp" and involved working with different modes of walking. Below the commit history, there is a file viewer for "README.md". The page also includes sections for "OpenWalk", "Usage", "Fabrication Drawings", "Moving Algorithm", "About Us", and copyright information.

This repository

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nonoesp / OpenWalk

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A plug-and-play open-source robot who can walk.

26 commits 1 branch 3 releases 2 contributors

Branch: master New pull request New file Find file HTTPS https://github.com/ Download ZIP

nonoesp Working with different modes of walking. Latest commit 5d40d24 11 hours ago

.gitignore First commit. a month ago

LICENSE Added License and credits. a month ago

OpenWalk.ino Working with different modes of walking. 11 hours ago

README.md Added project information. a month ago

README.md

## OpenWalk

A plug-and-play open-source robot who can walk that works with Arduino.

### Usage

### Fabrication Drawings

OpenWalk is fabricated with informal fabrication materials and techniques. Really soon, we will make available the fabrication drawings with some instructions on how to assemble your own OpenWalk robot.

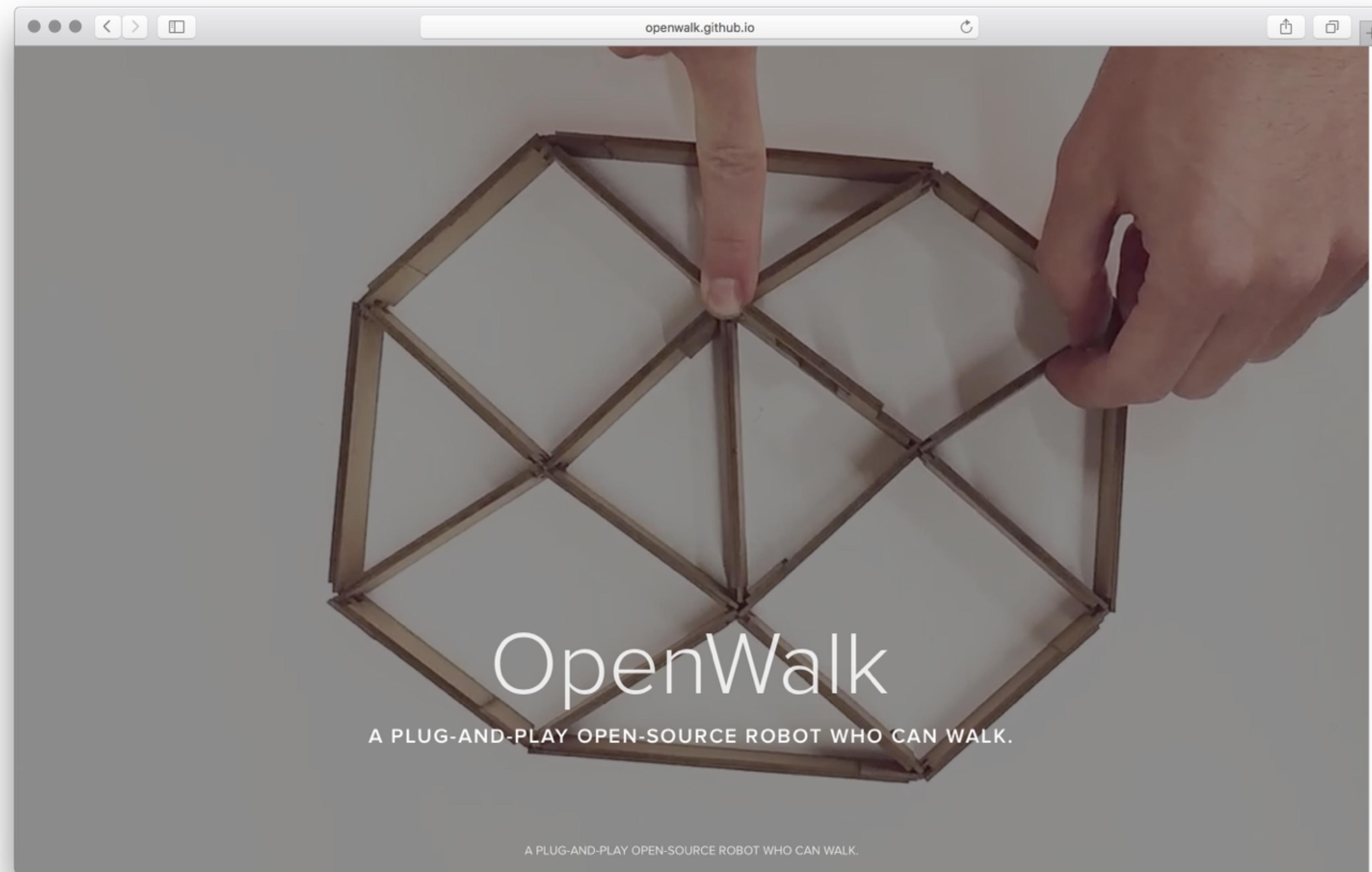
### Moving Algorithm

We are building a code so you can download and customize how the robot behaves. Keep tuned!

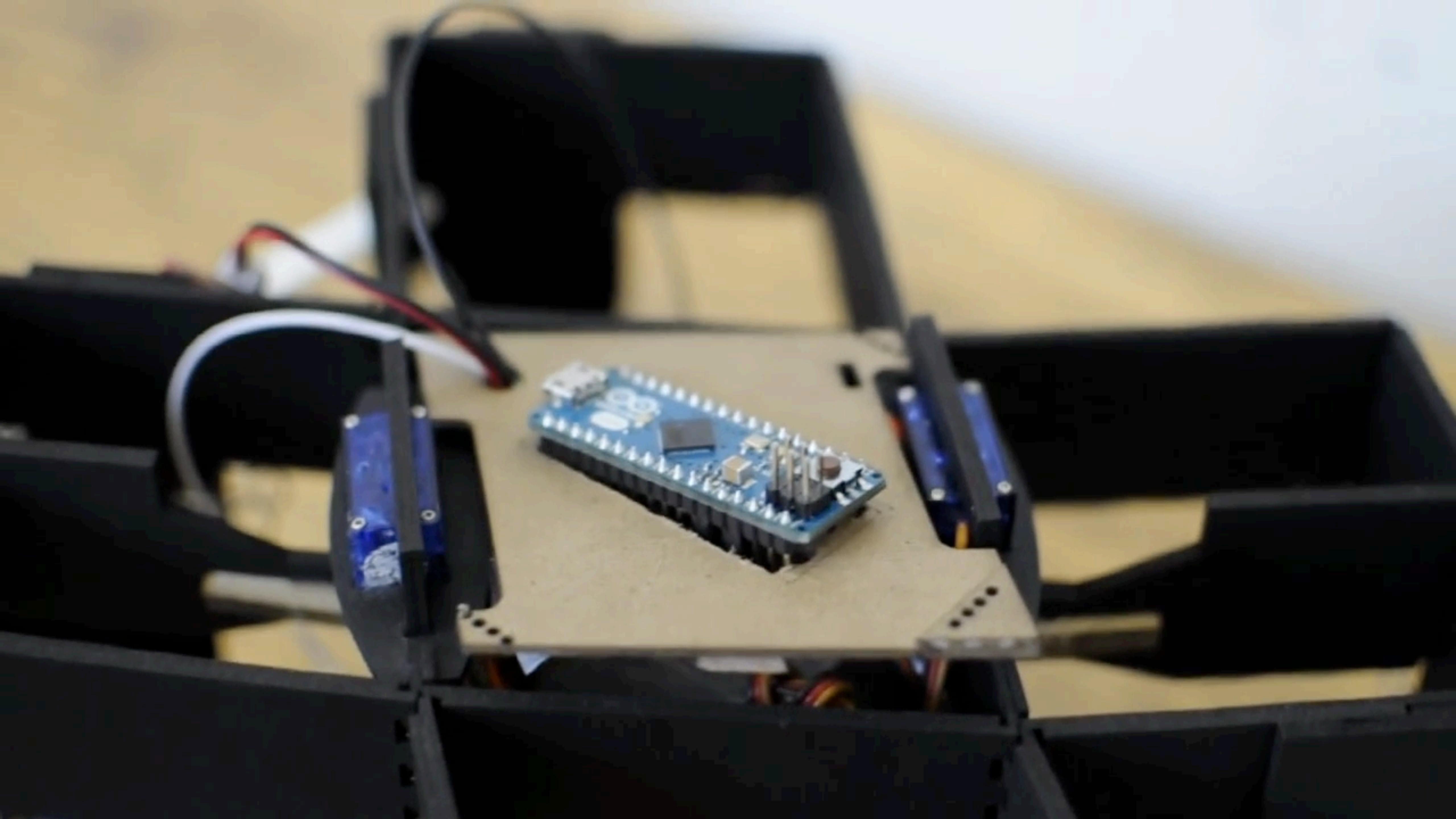
For now, you can [check the source](#).

### About Us

OpenWalk is developed by Nono Martínez Alonso, Enol Vallina Fernández, and Guillermo Saavedra.

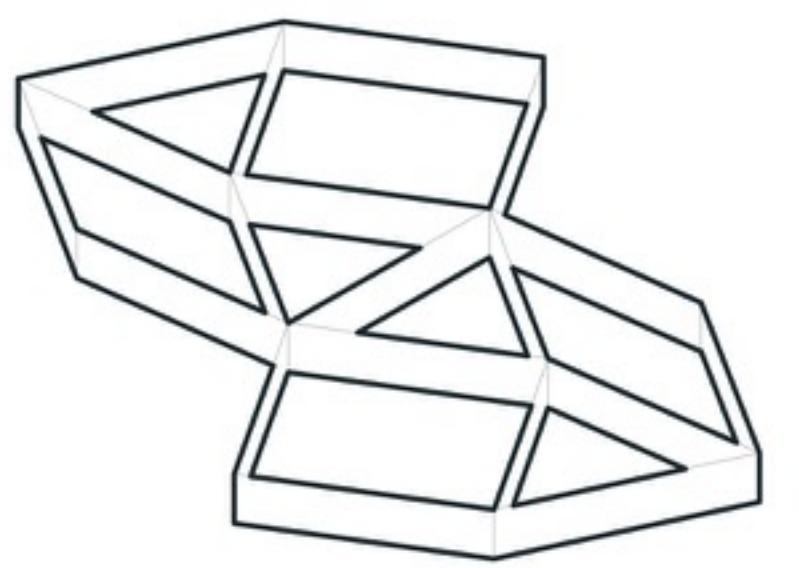


Device.

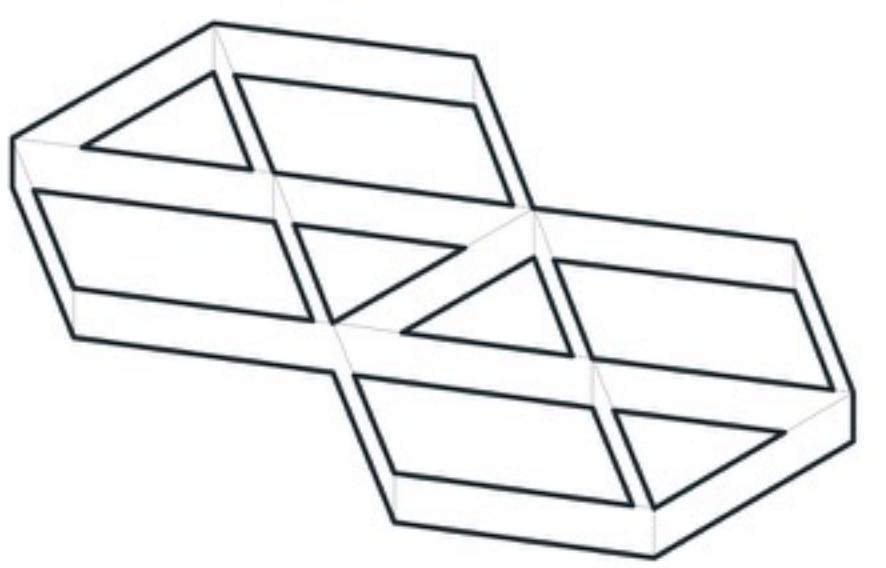


Kinematics.

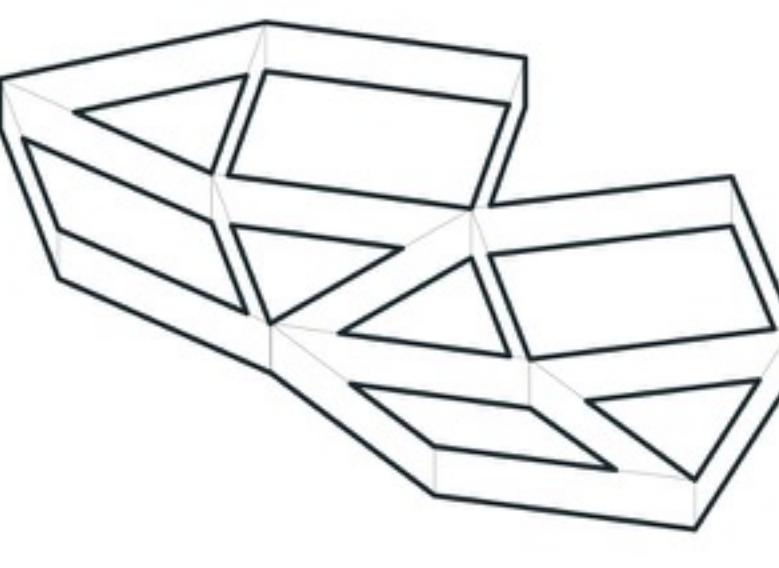
Body.



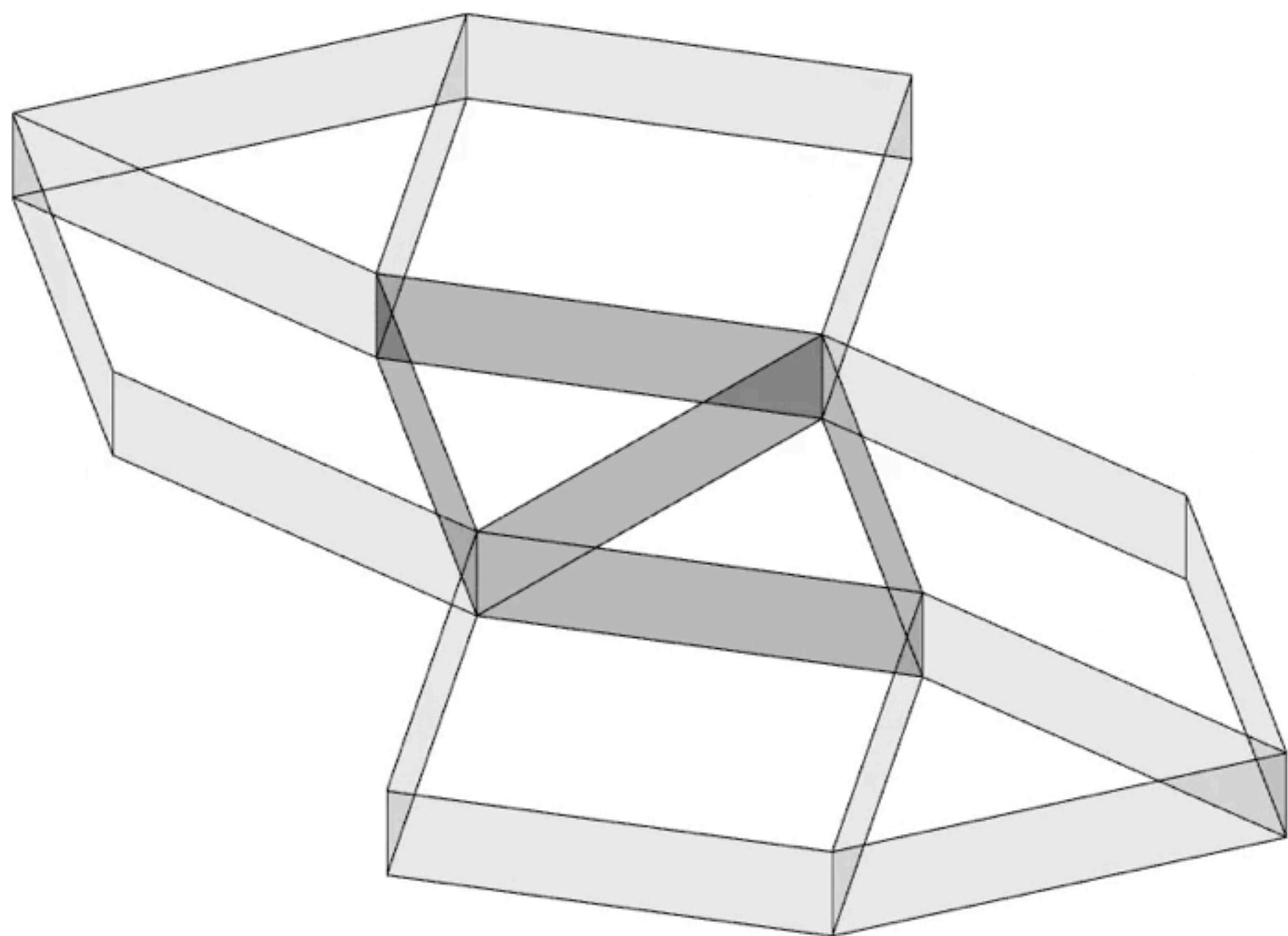
Asymmetric

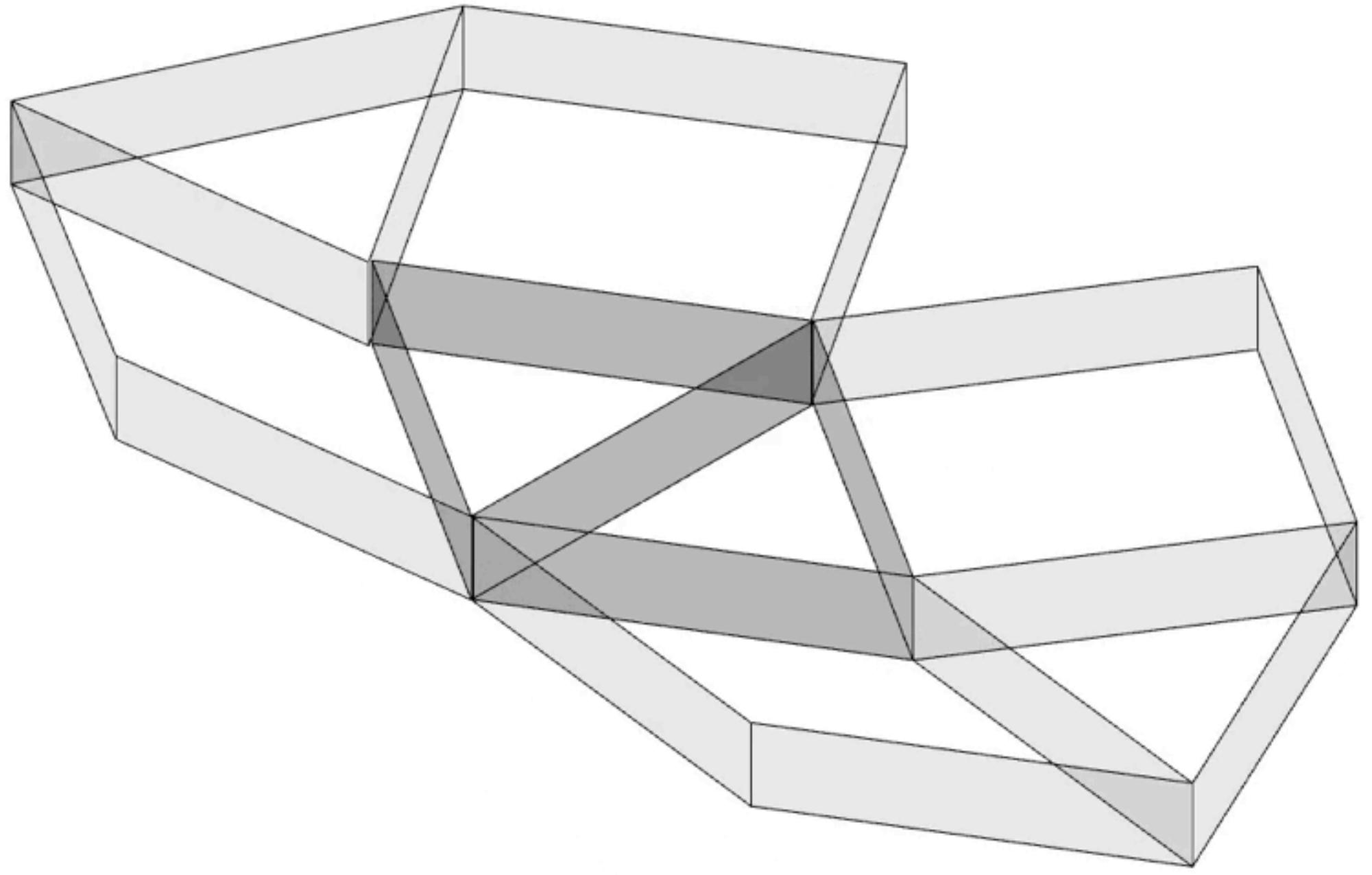


Rest

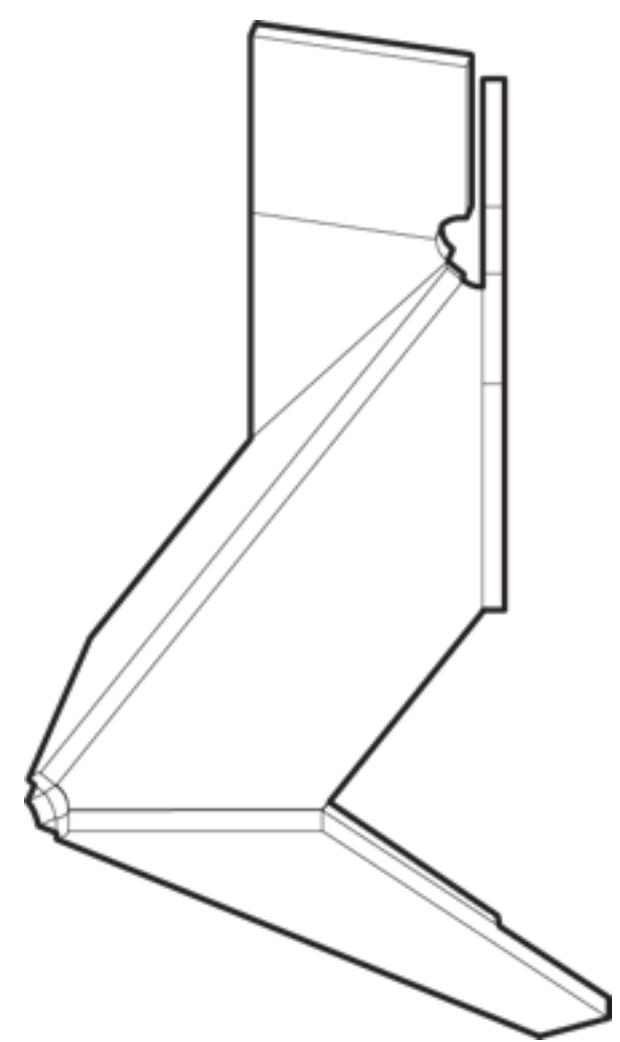


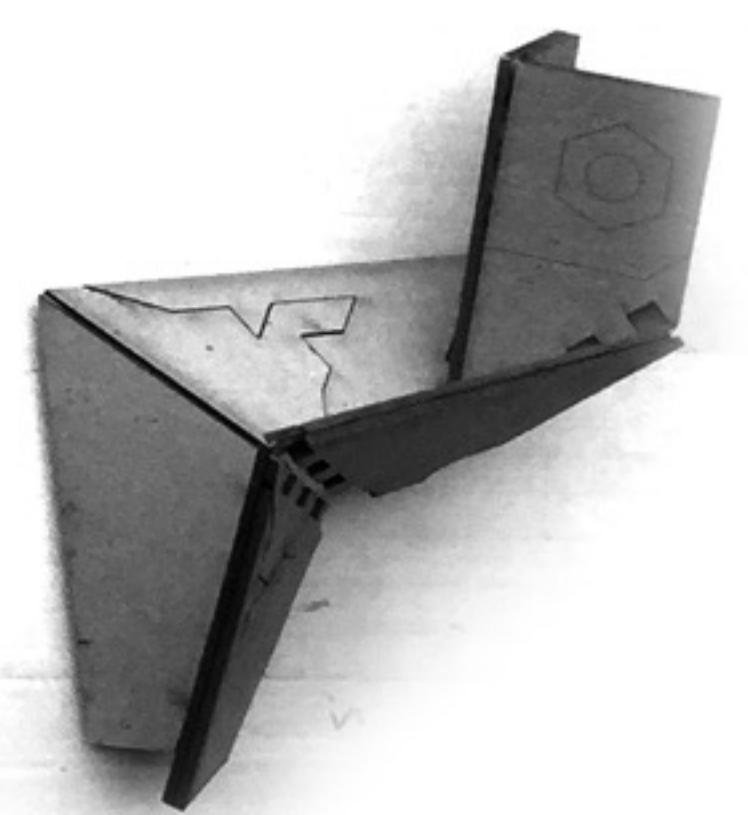
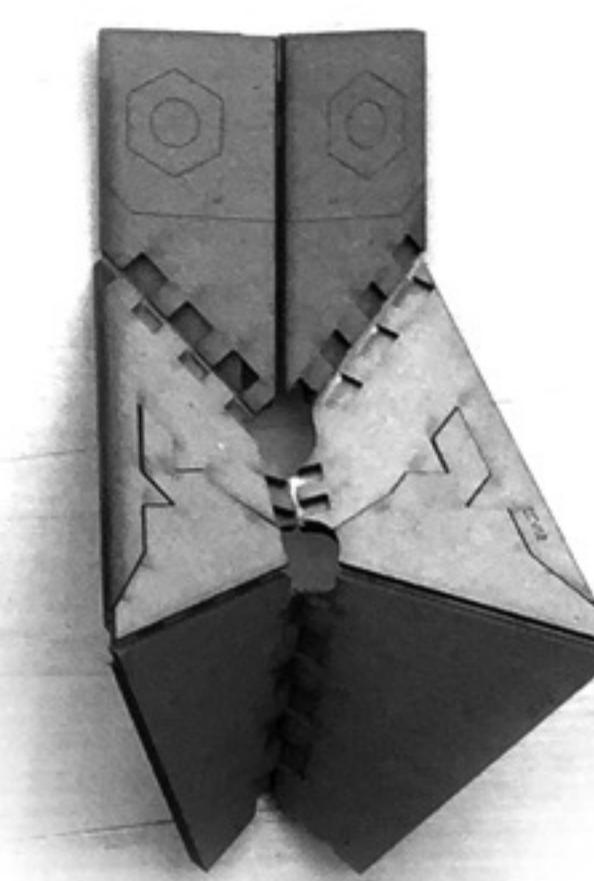
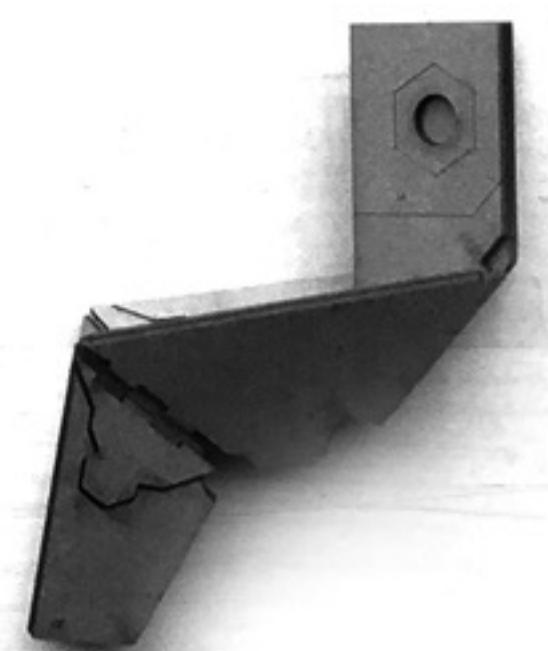
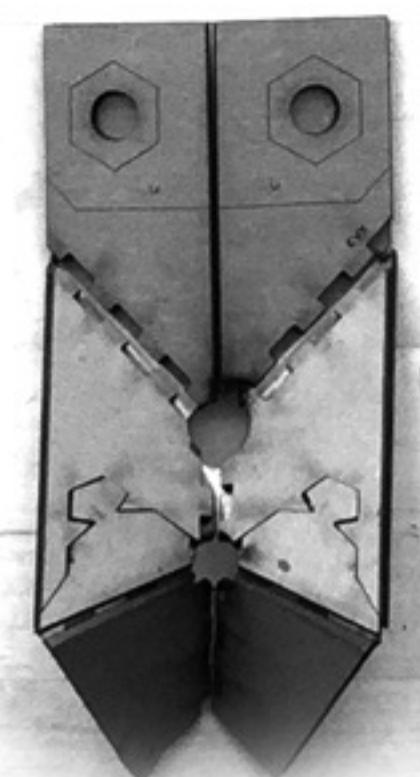
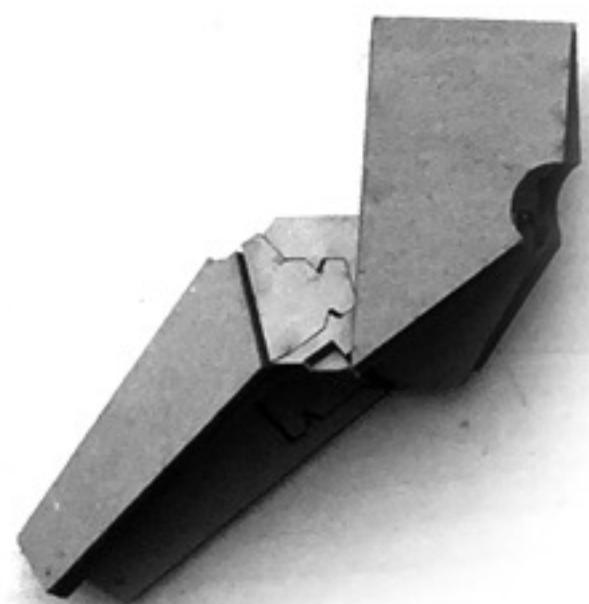
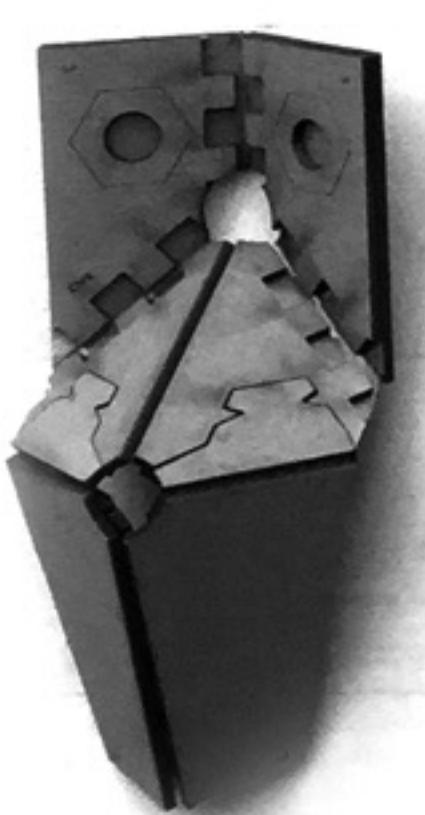
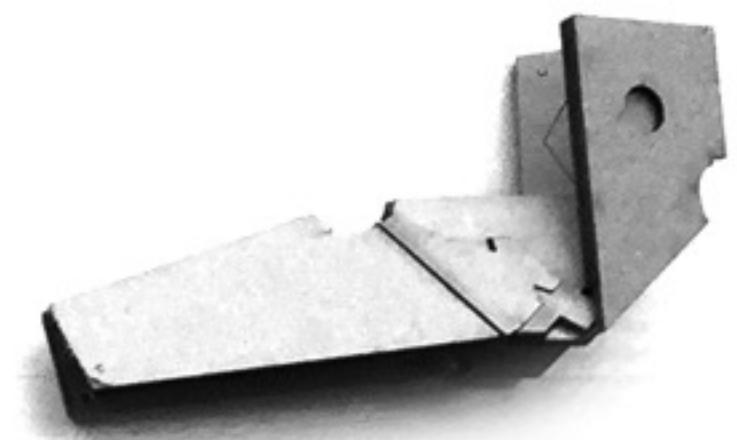
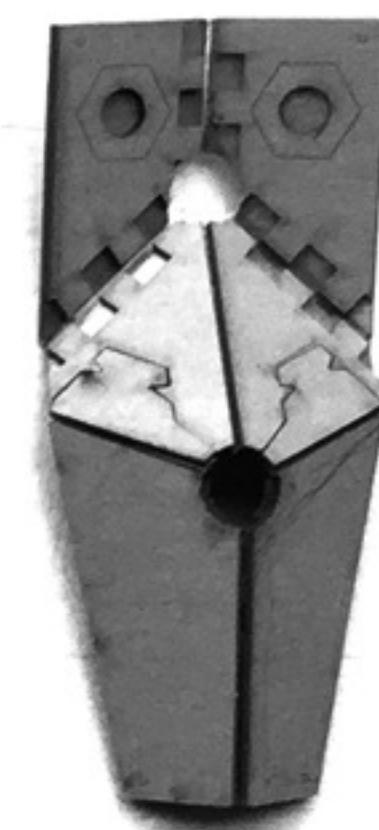
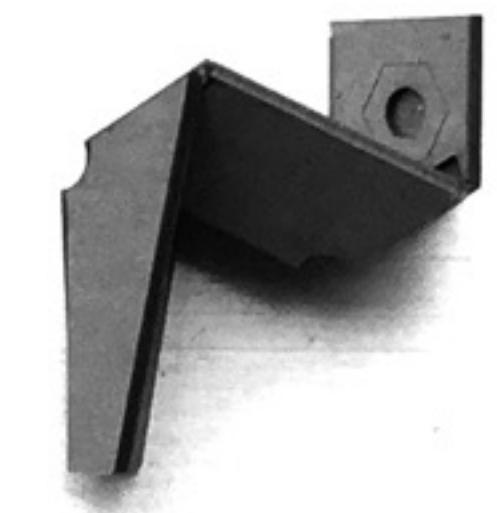
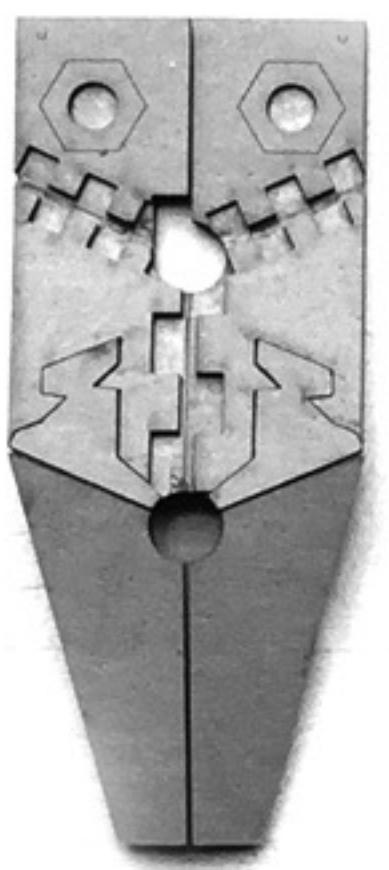
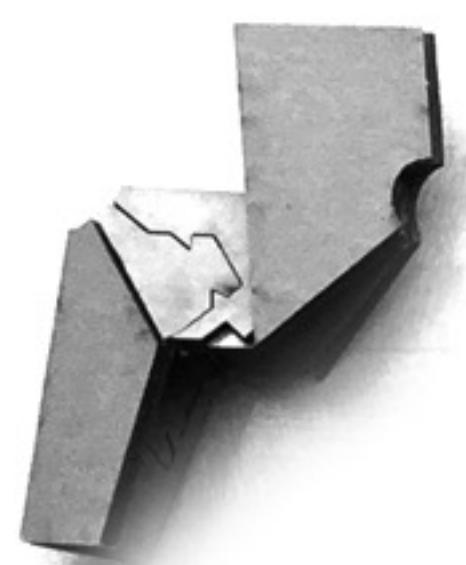
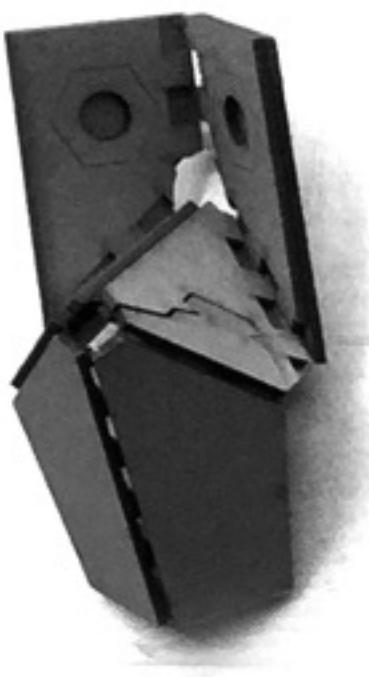
Symmetric

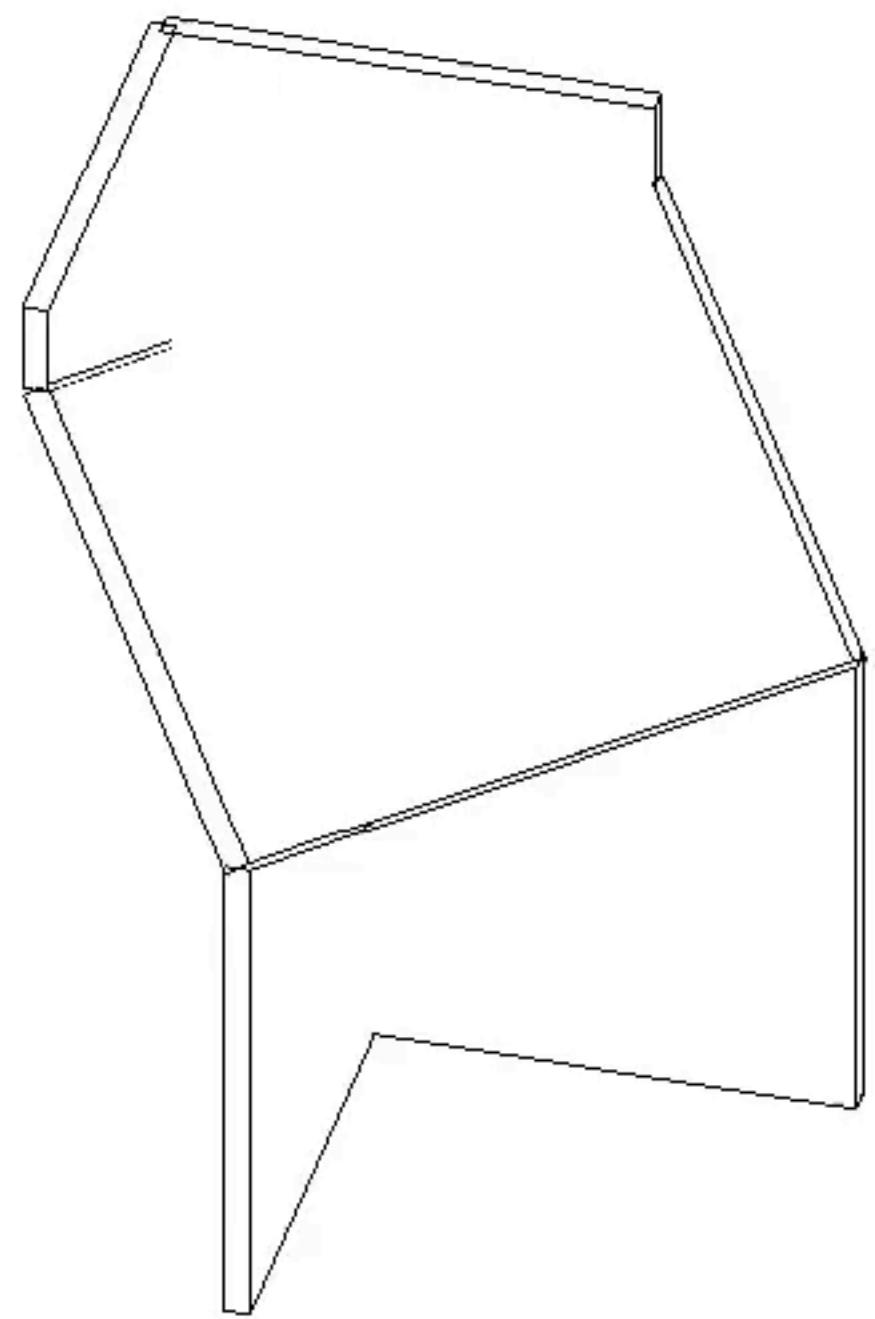




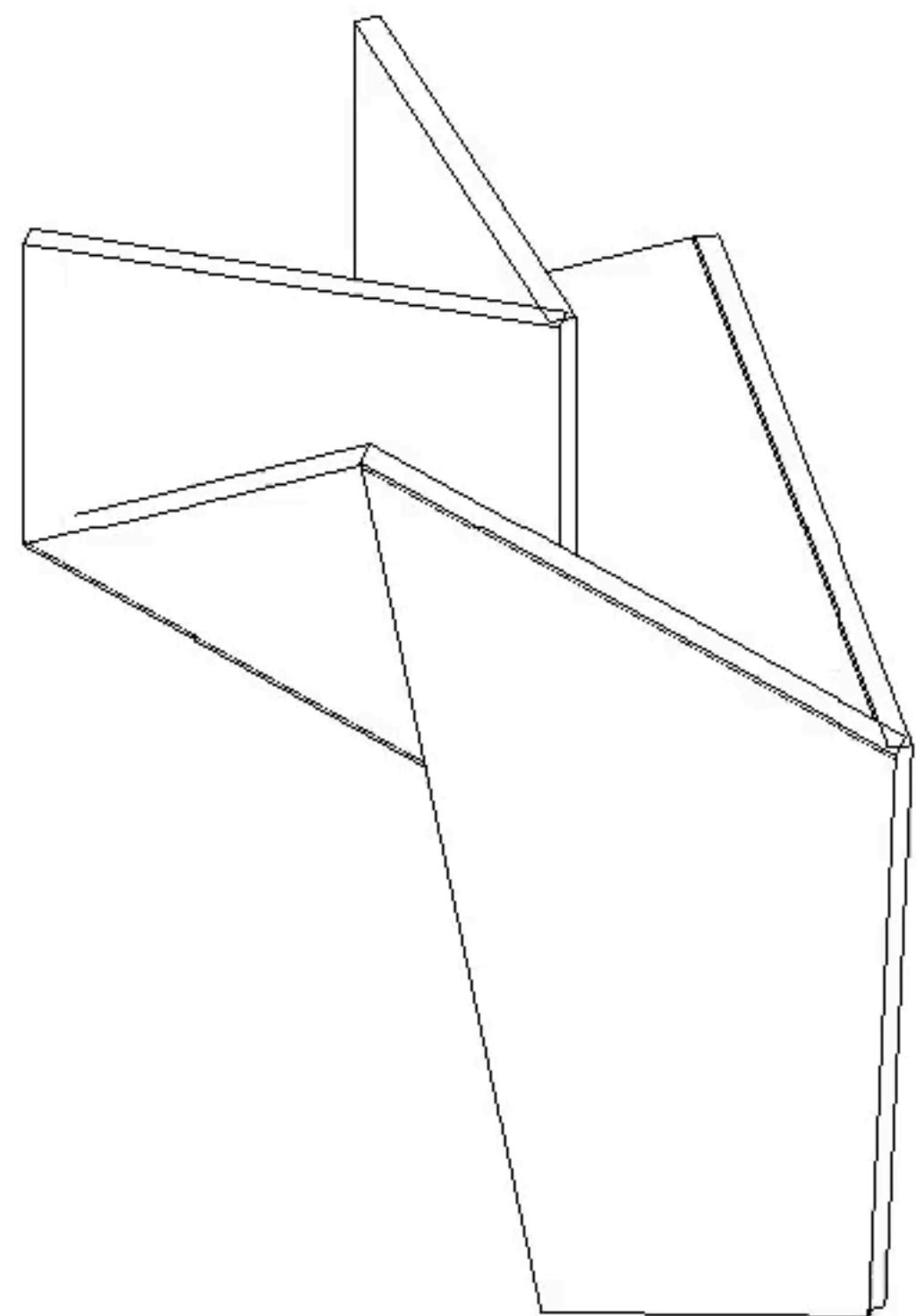
Legs.



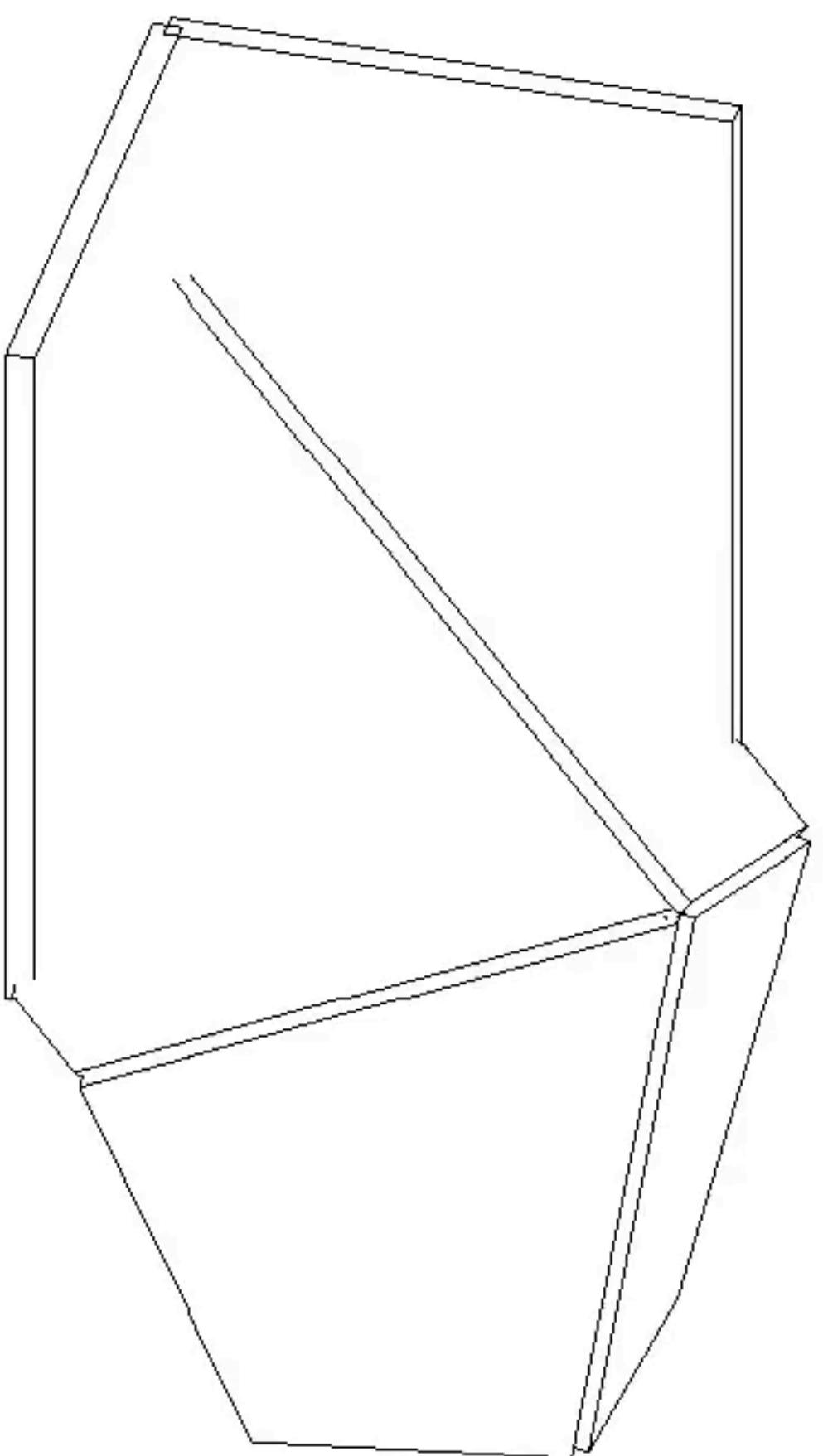




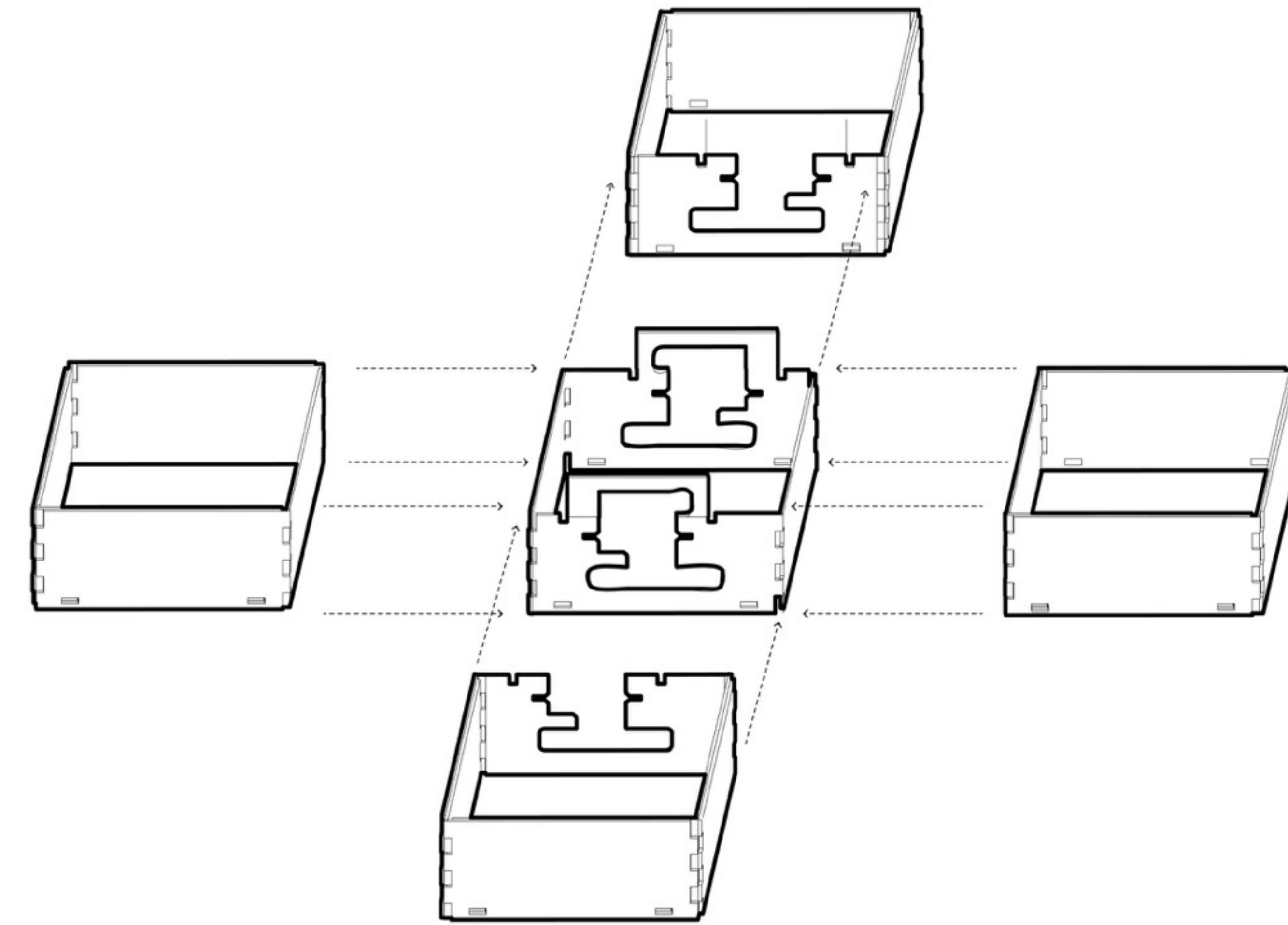
x  
y  
z

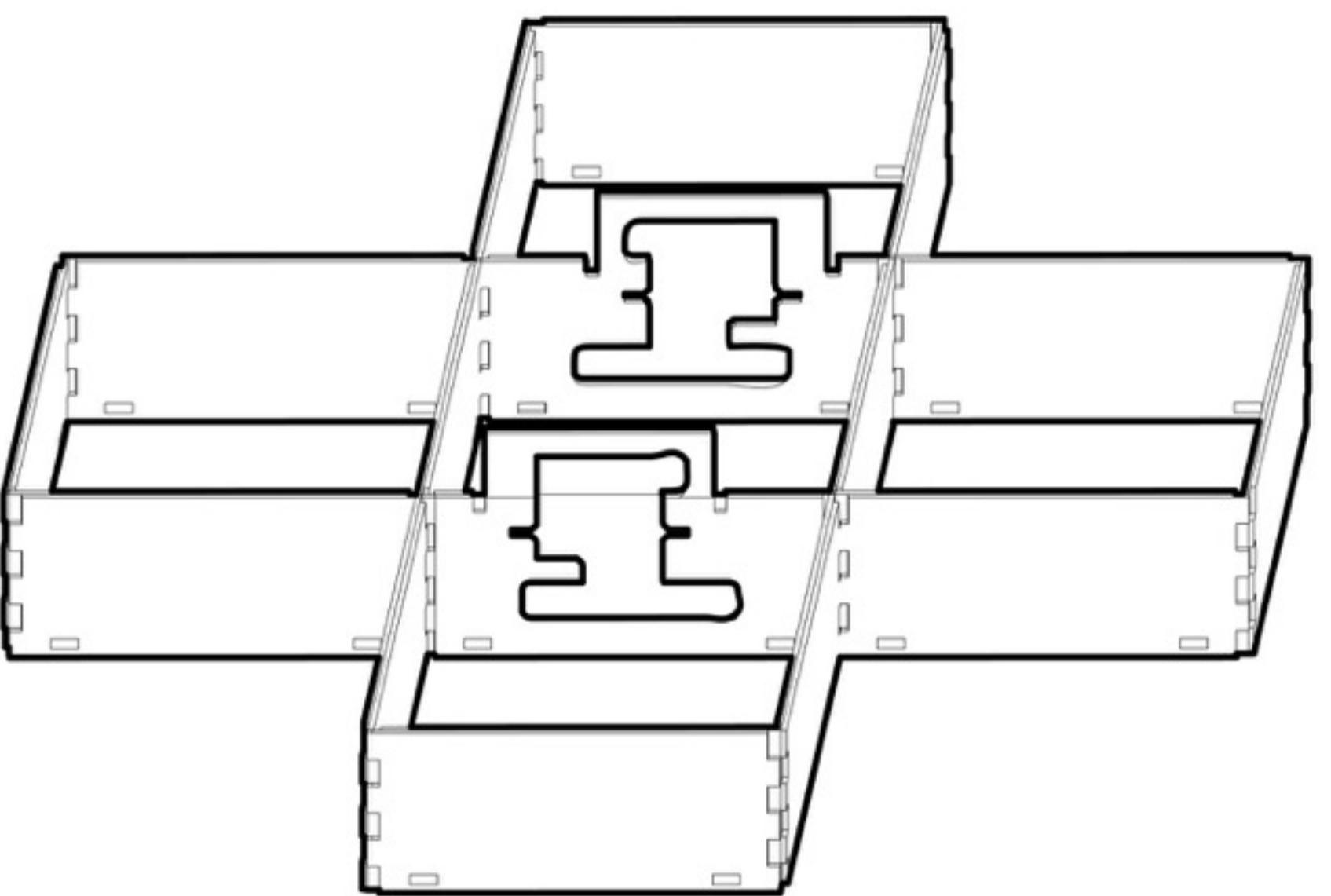


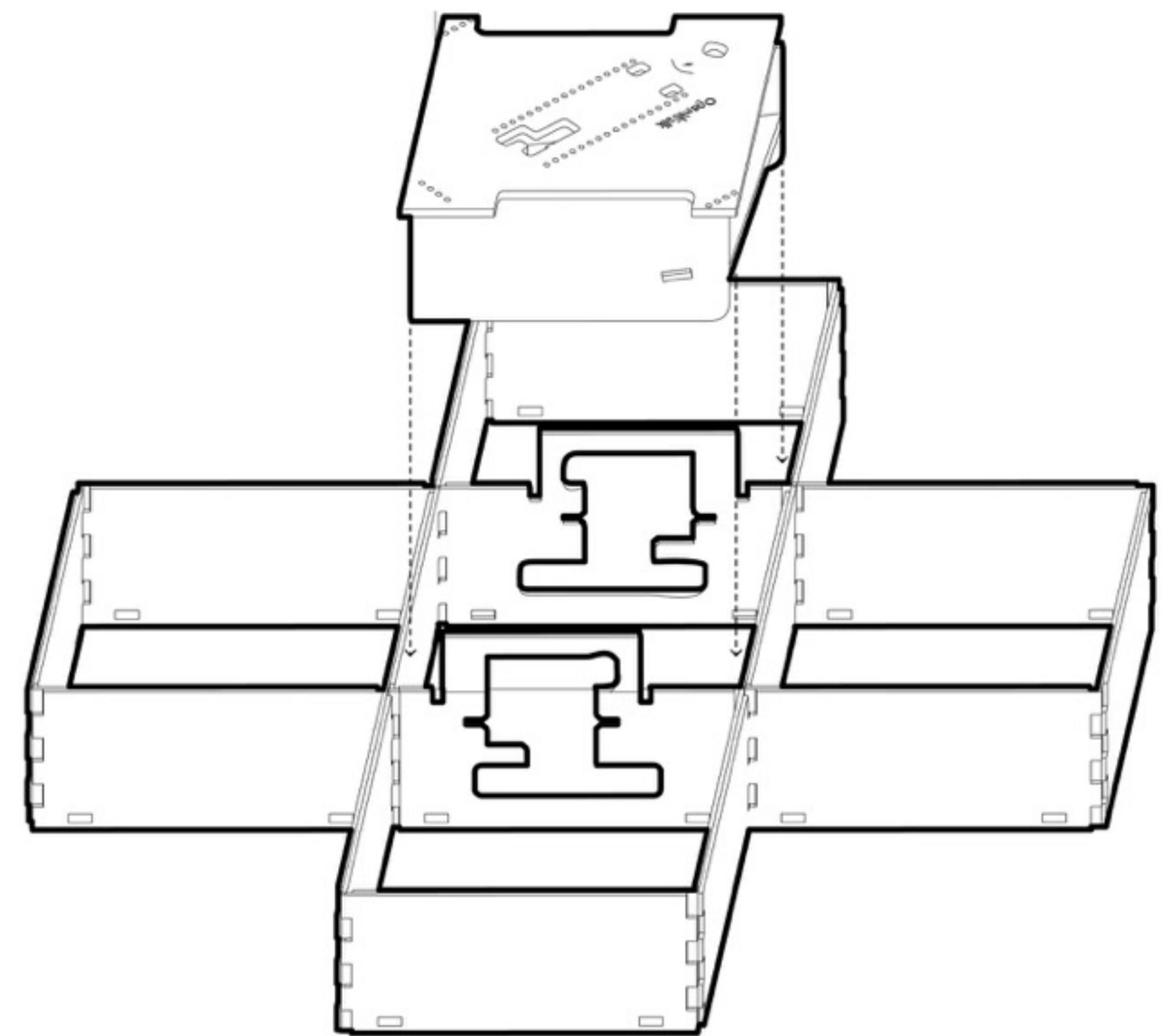
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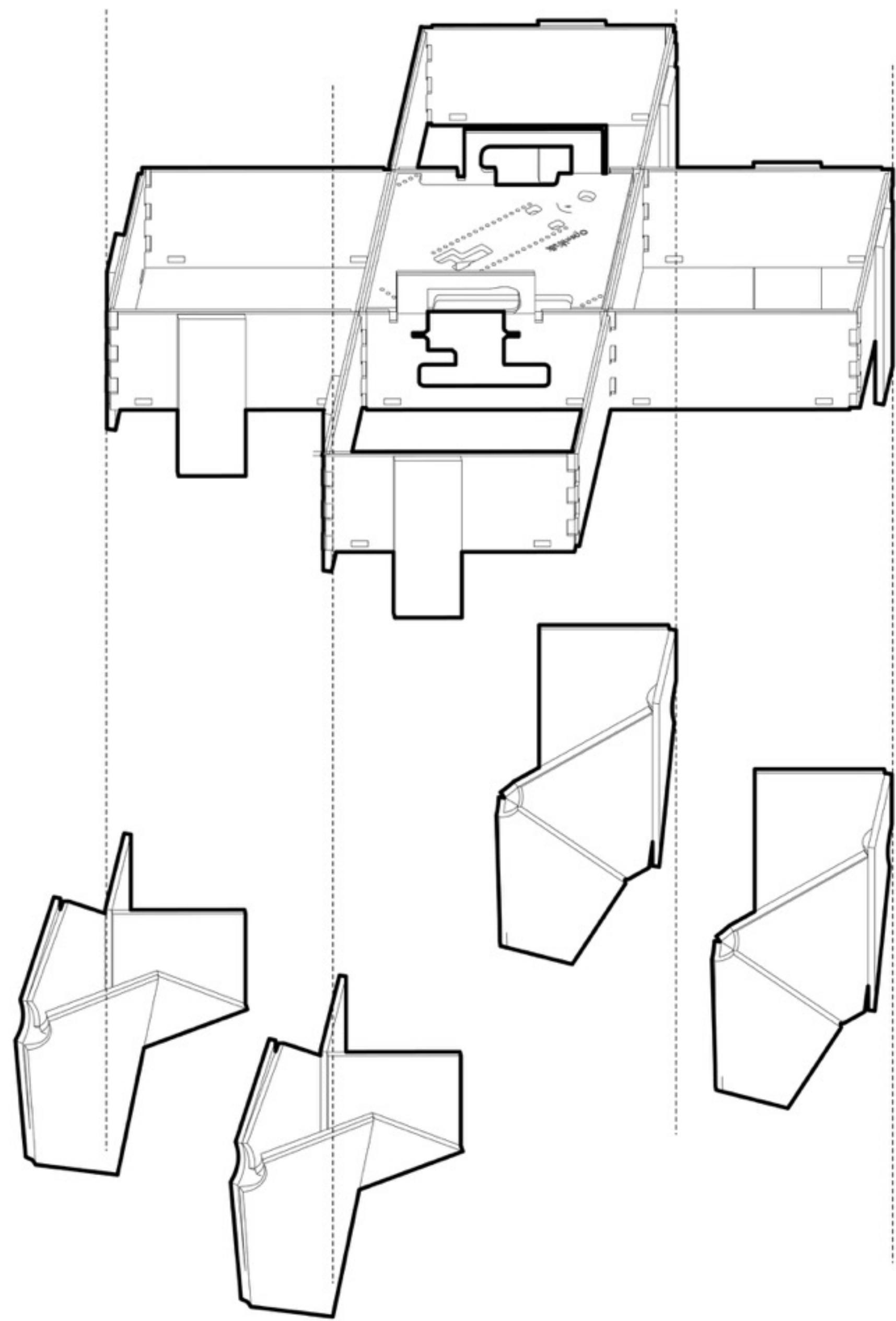


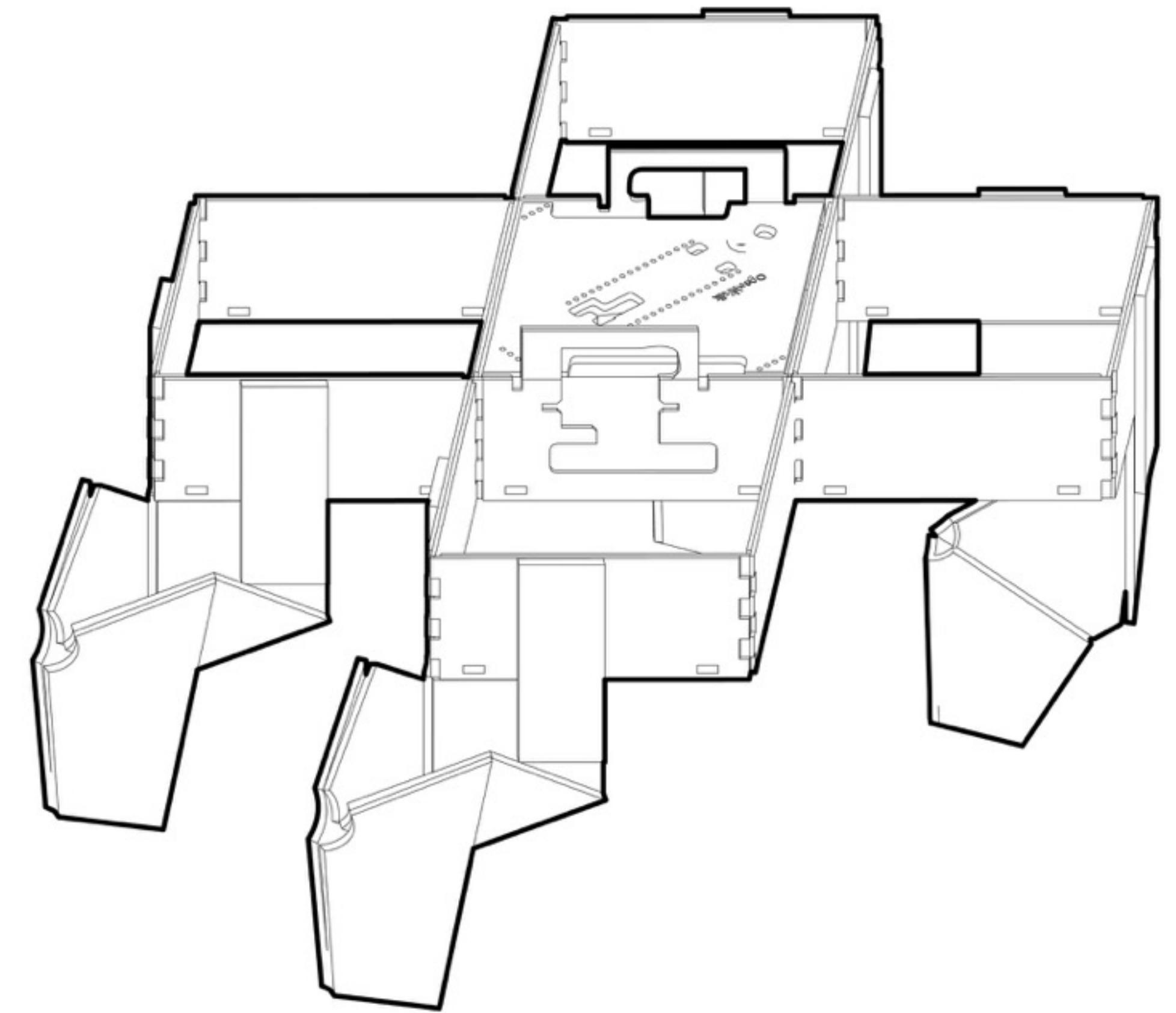
Assembly.

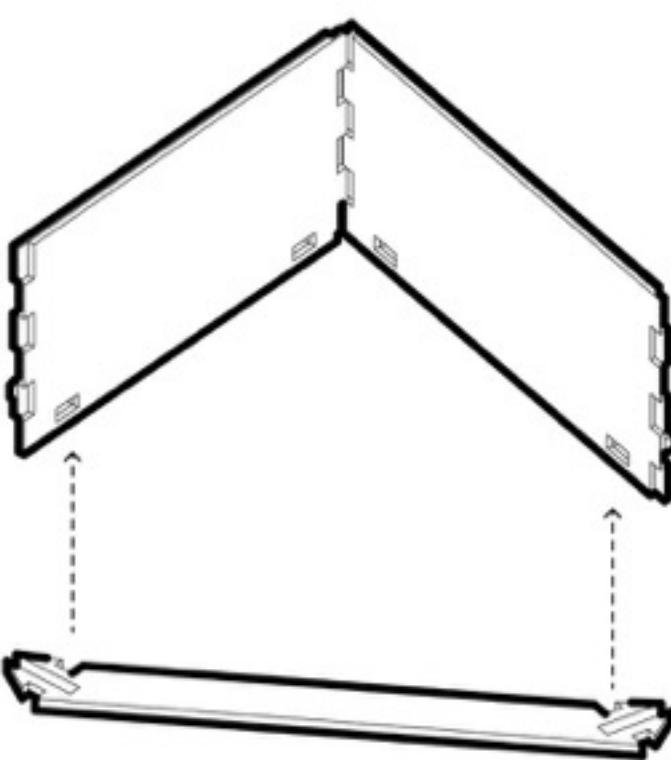


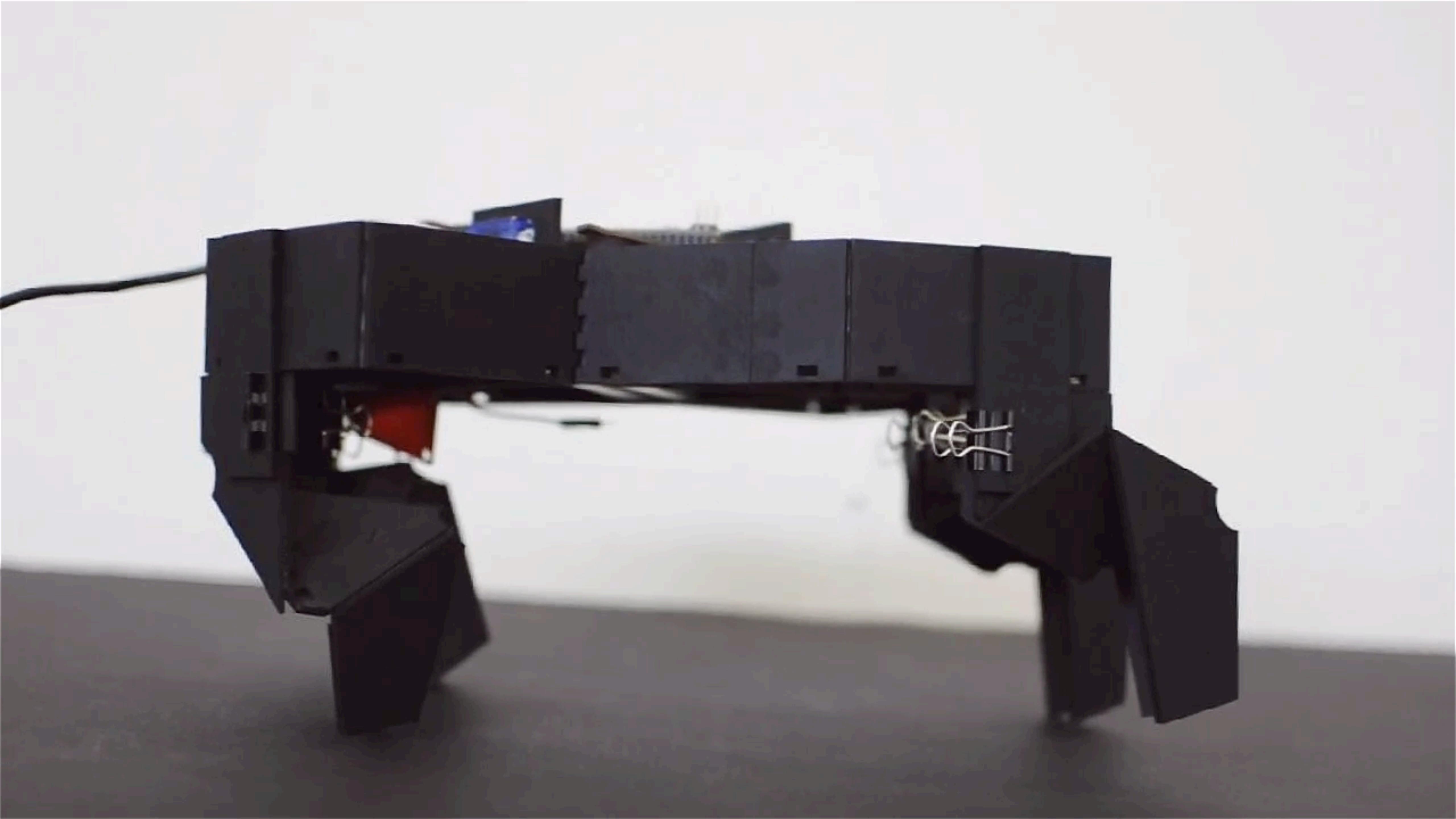






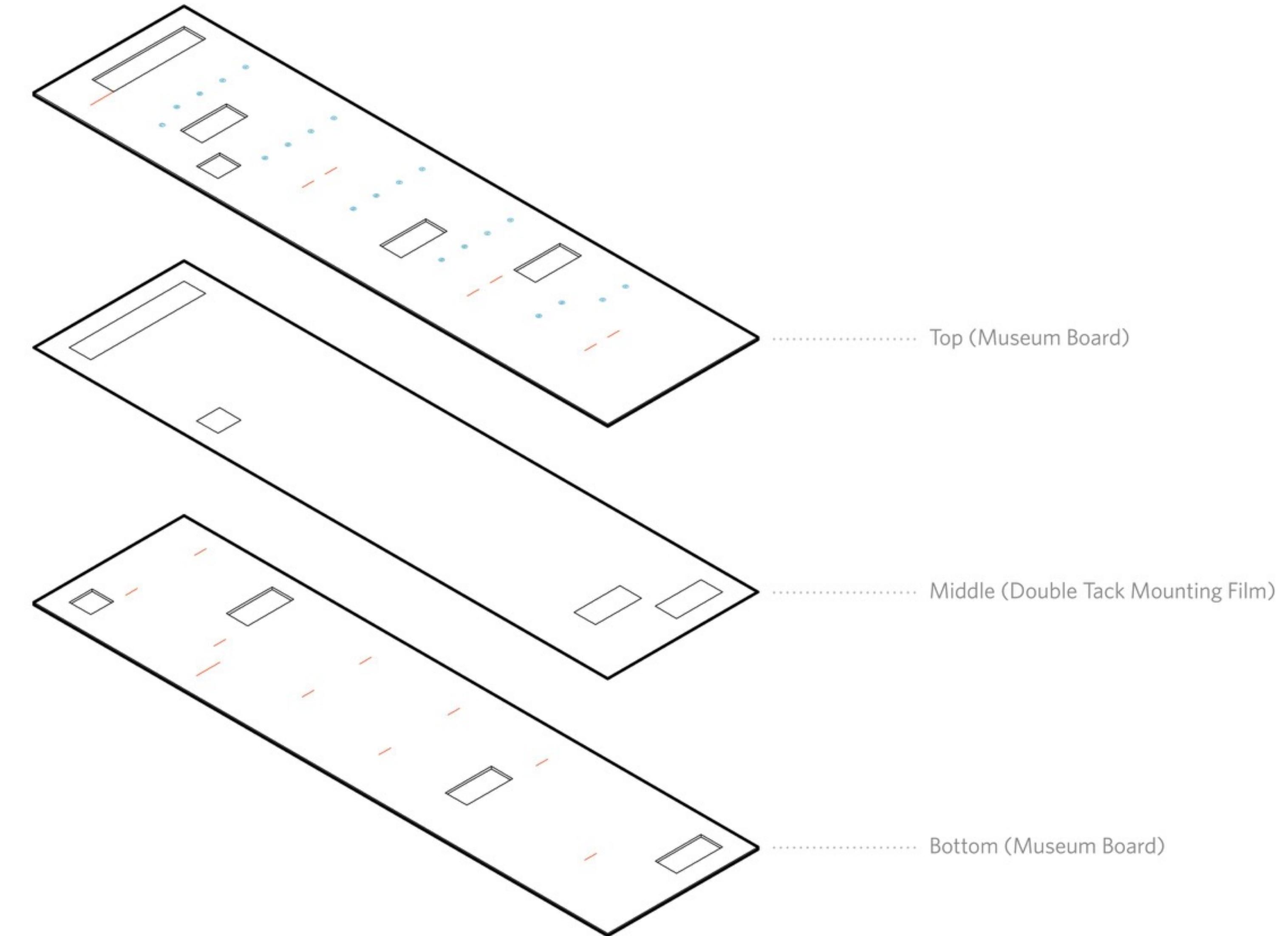


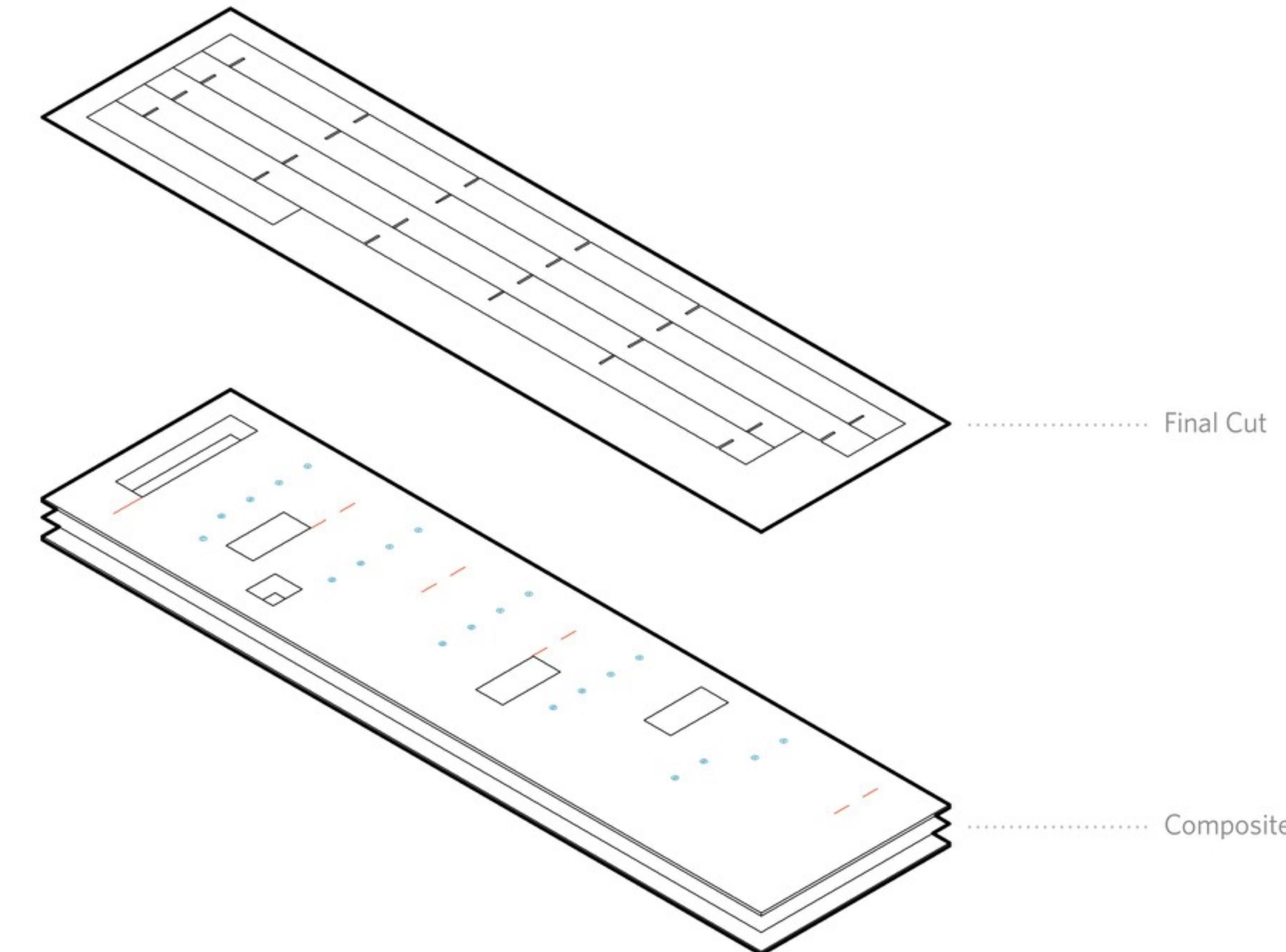


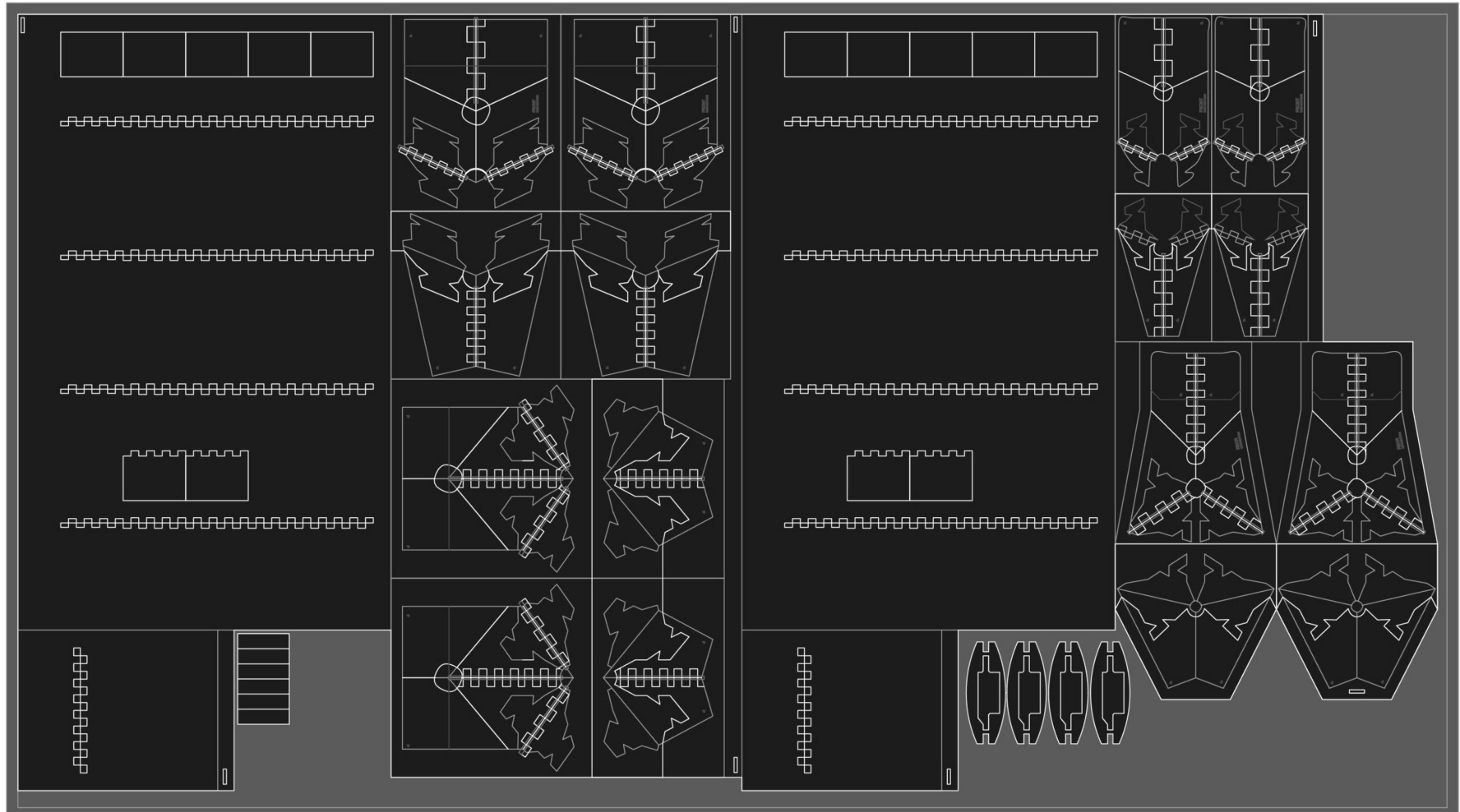


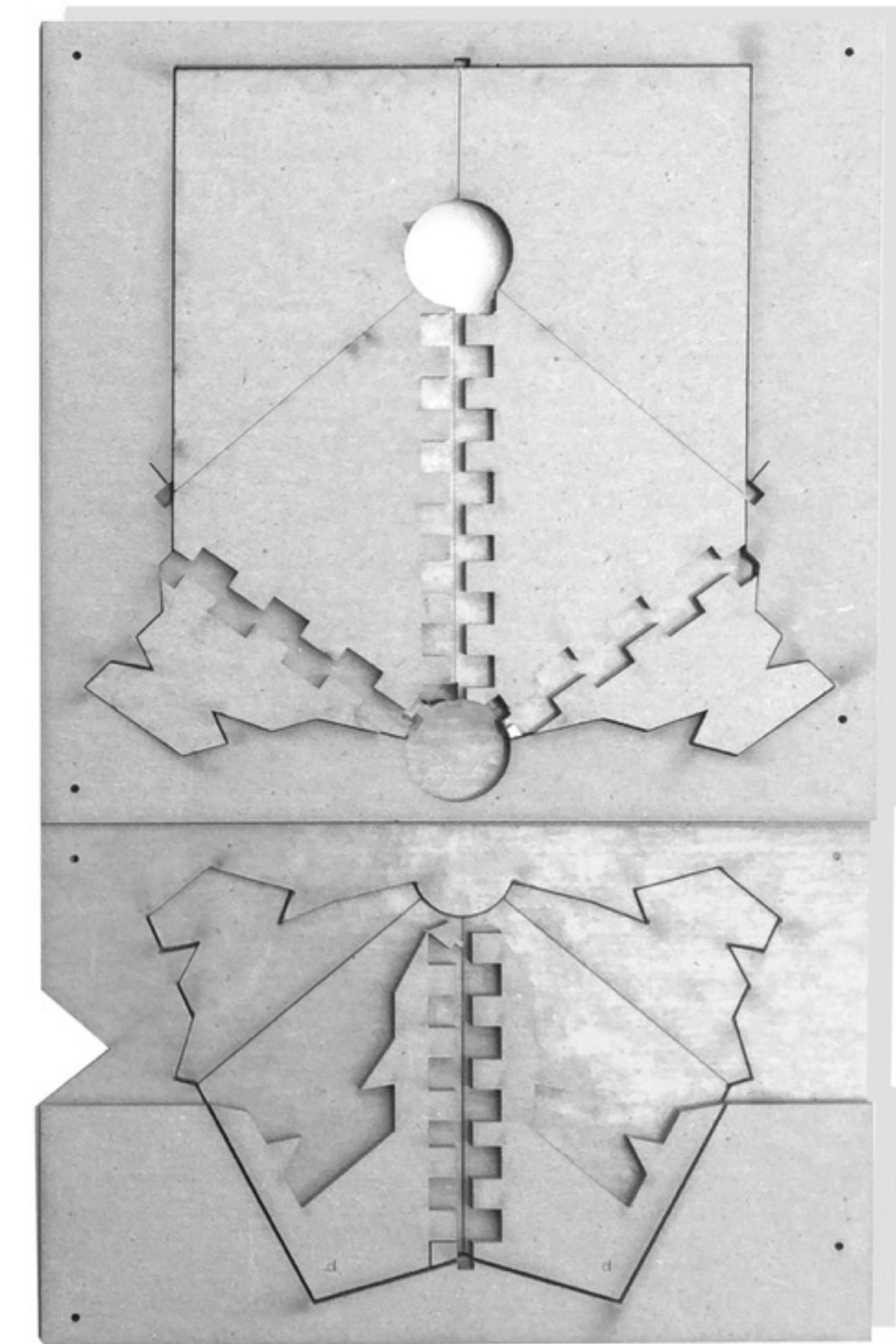
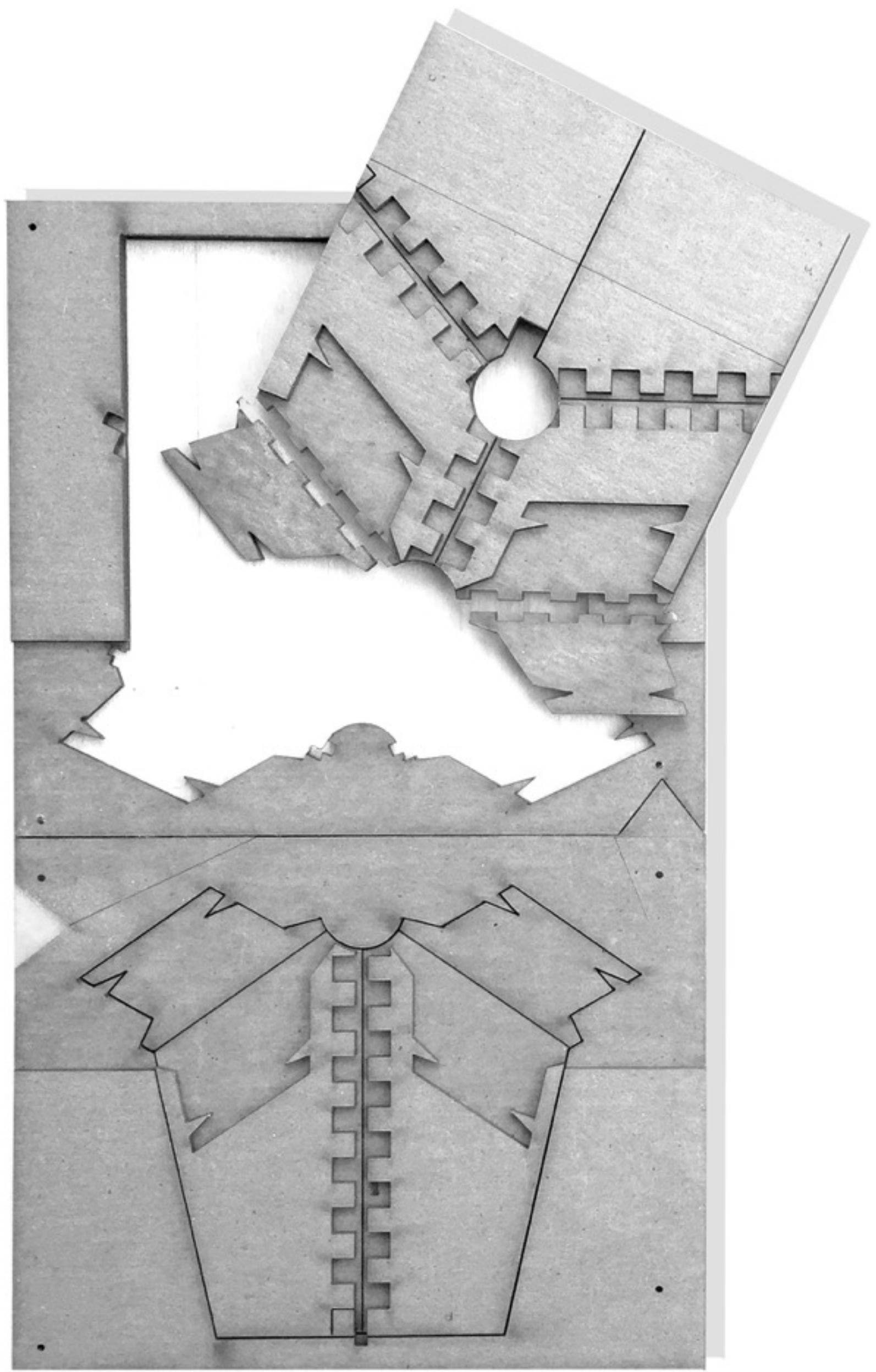
Manufacture.

3 sheets of chipboard (20"x30").  
Half letter of YUPO (1/32").  
Half letter of Acrylic (1/16").

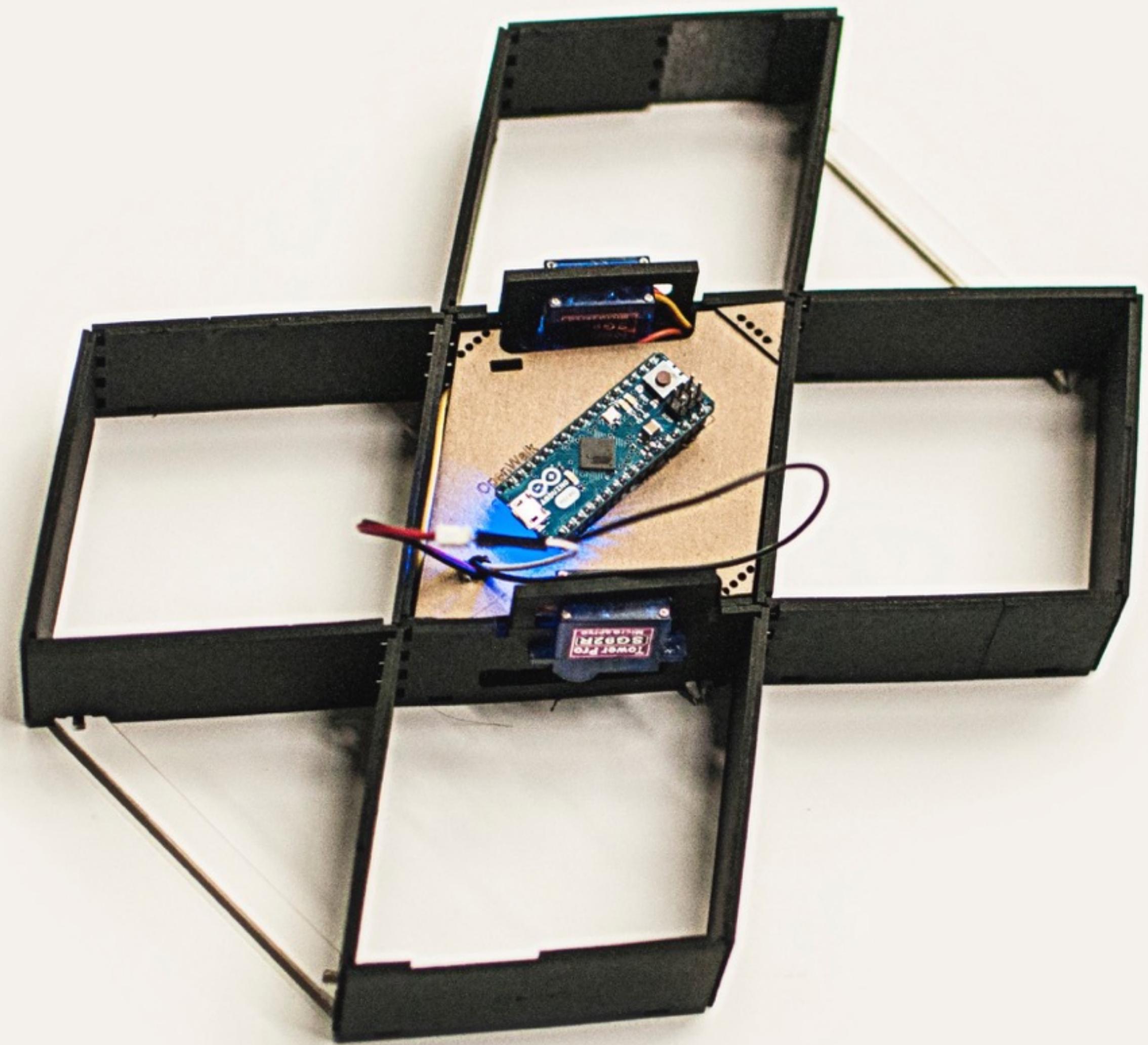






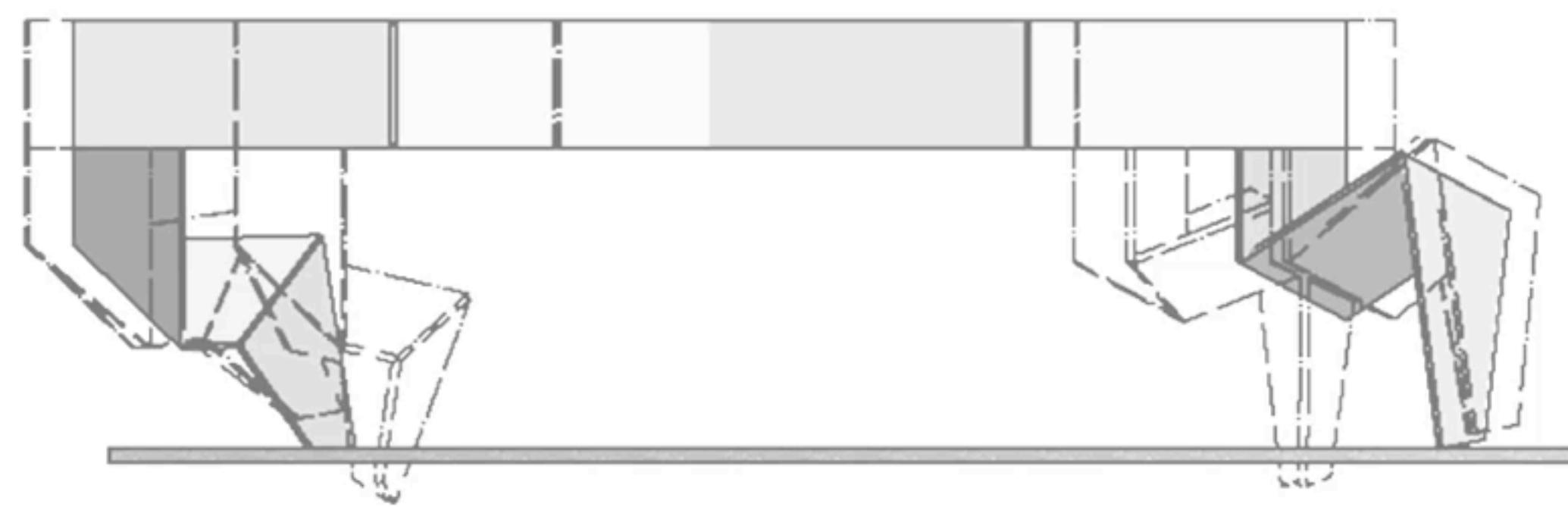
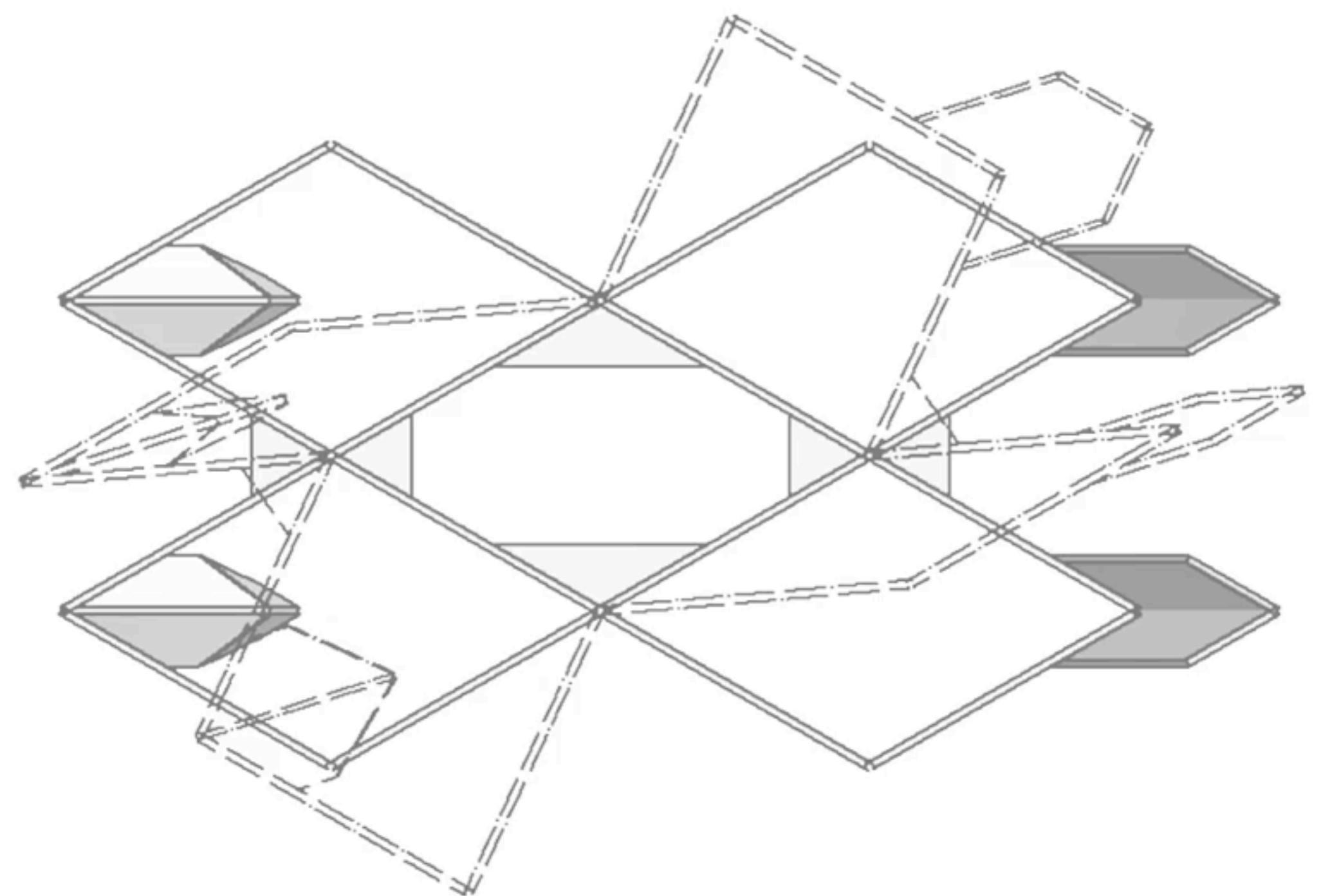


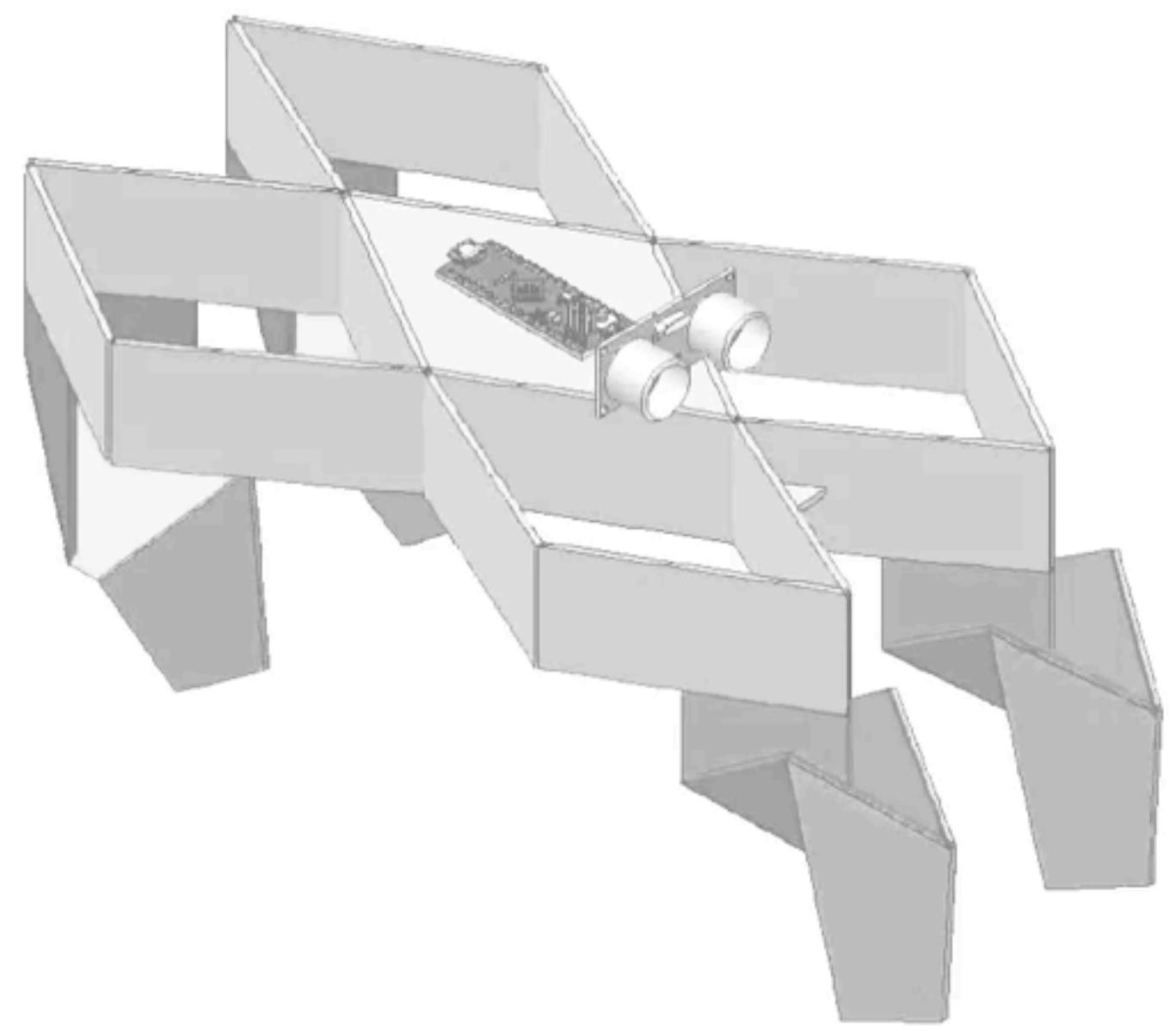
Prototype(s).

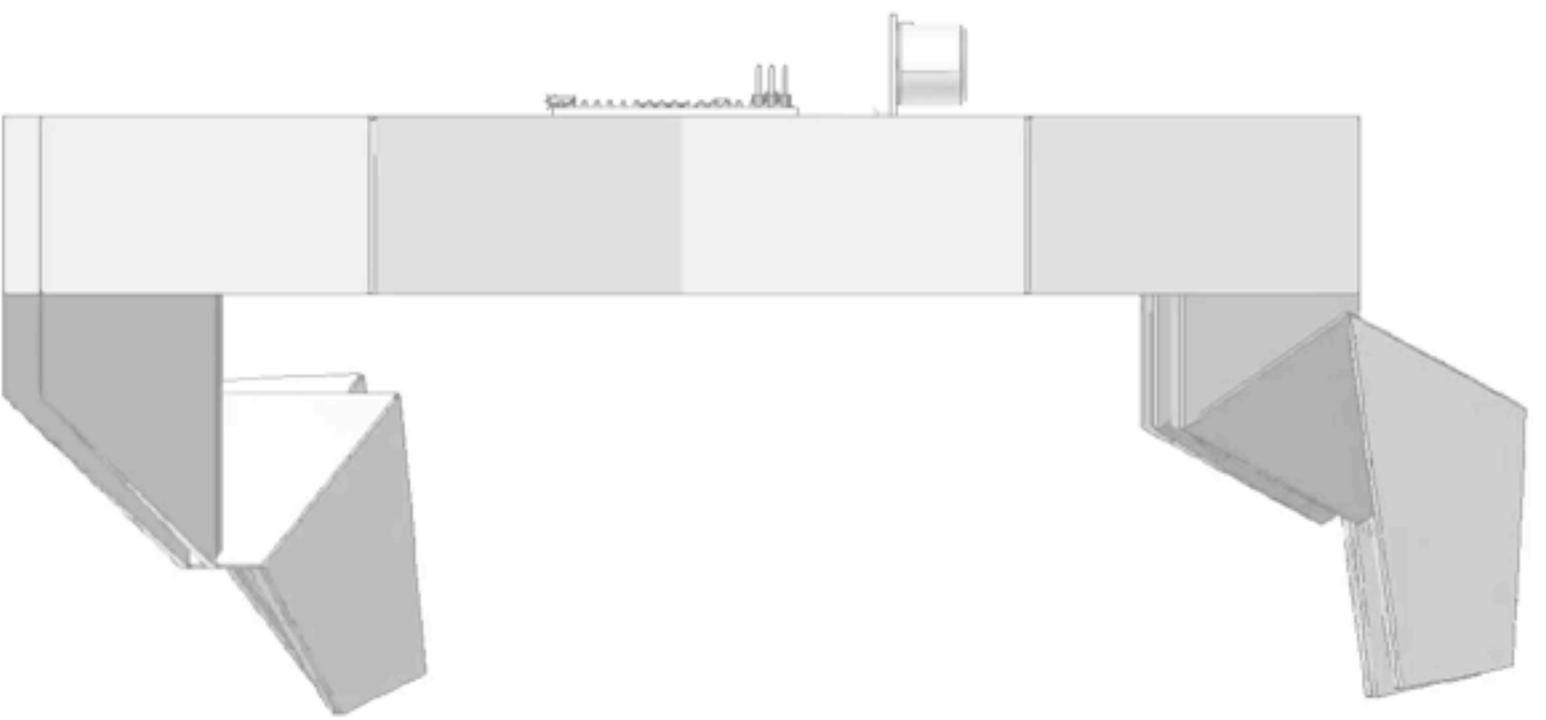


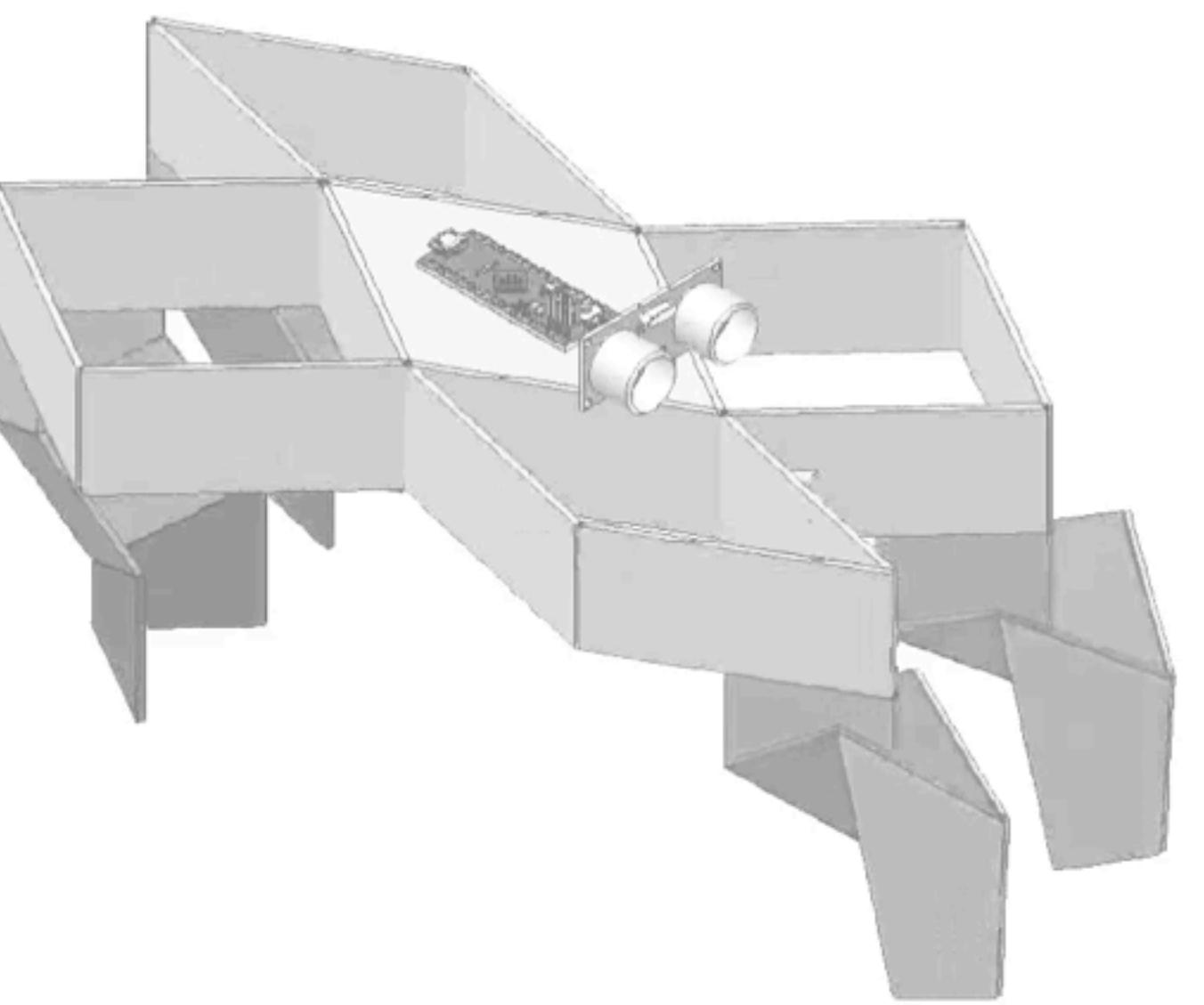
Pictures of prototypes

Behavior.

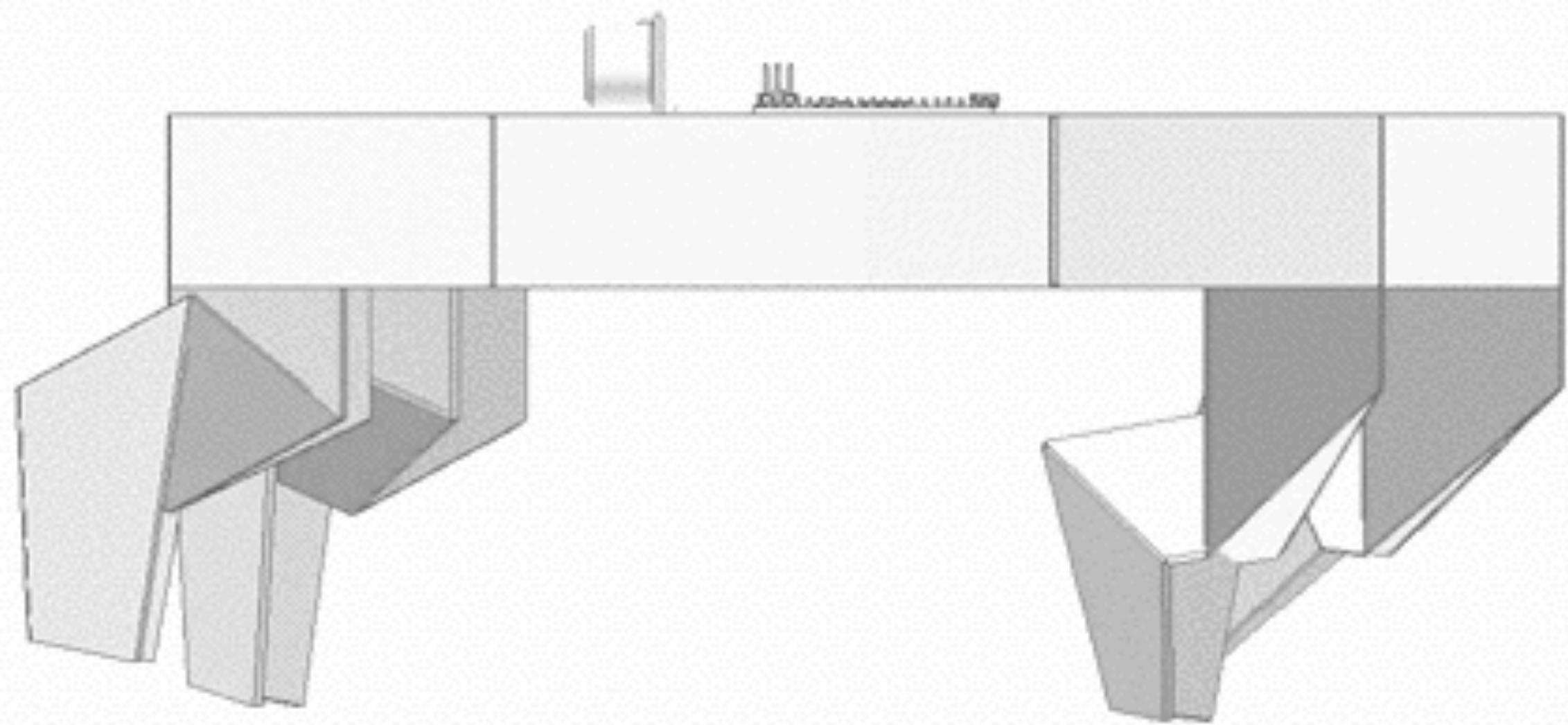


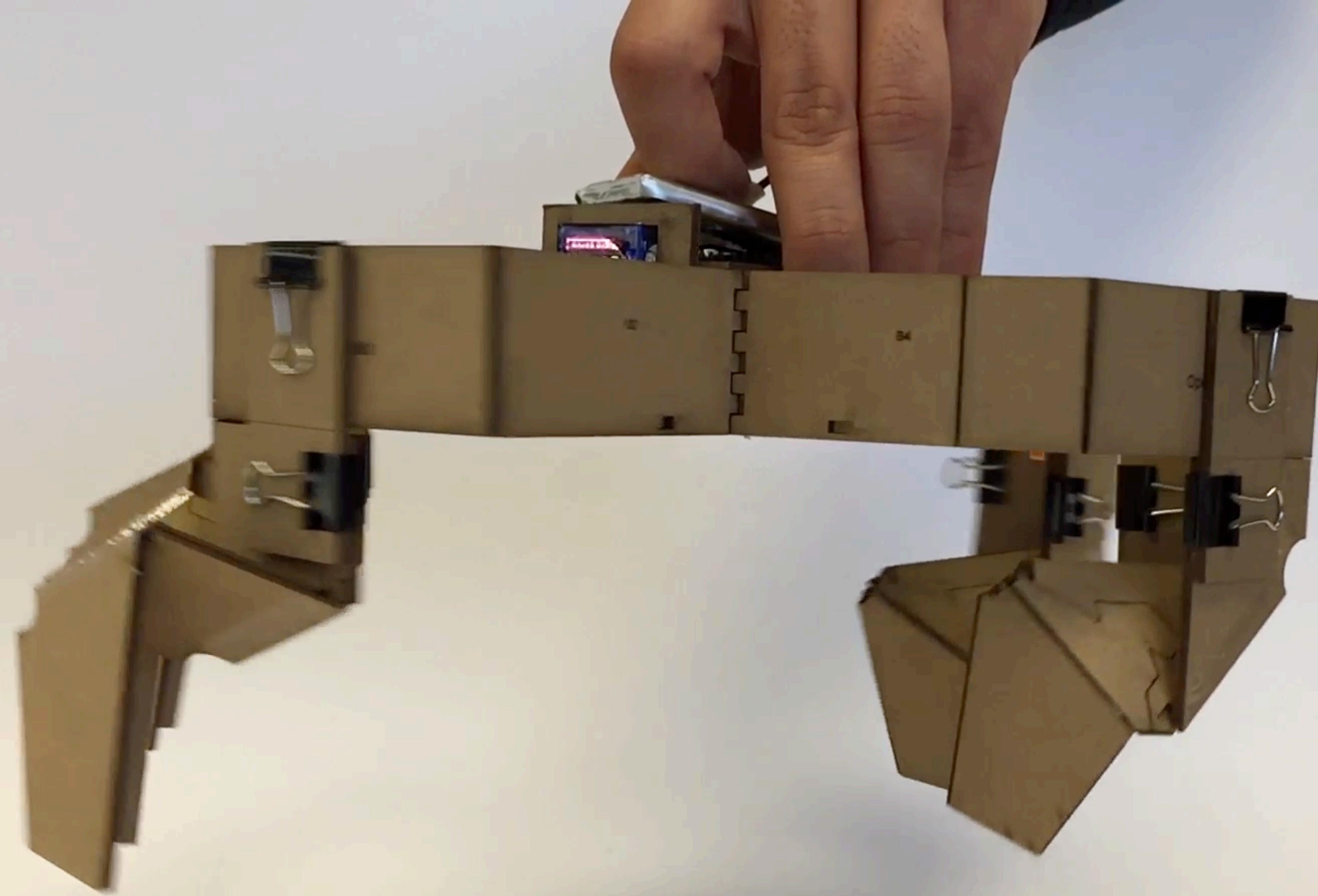


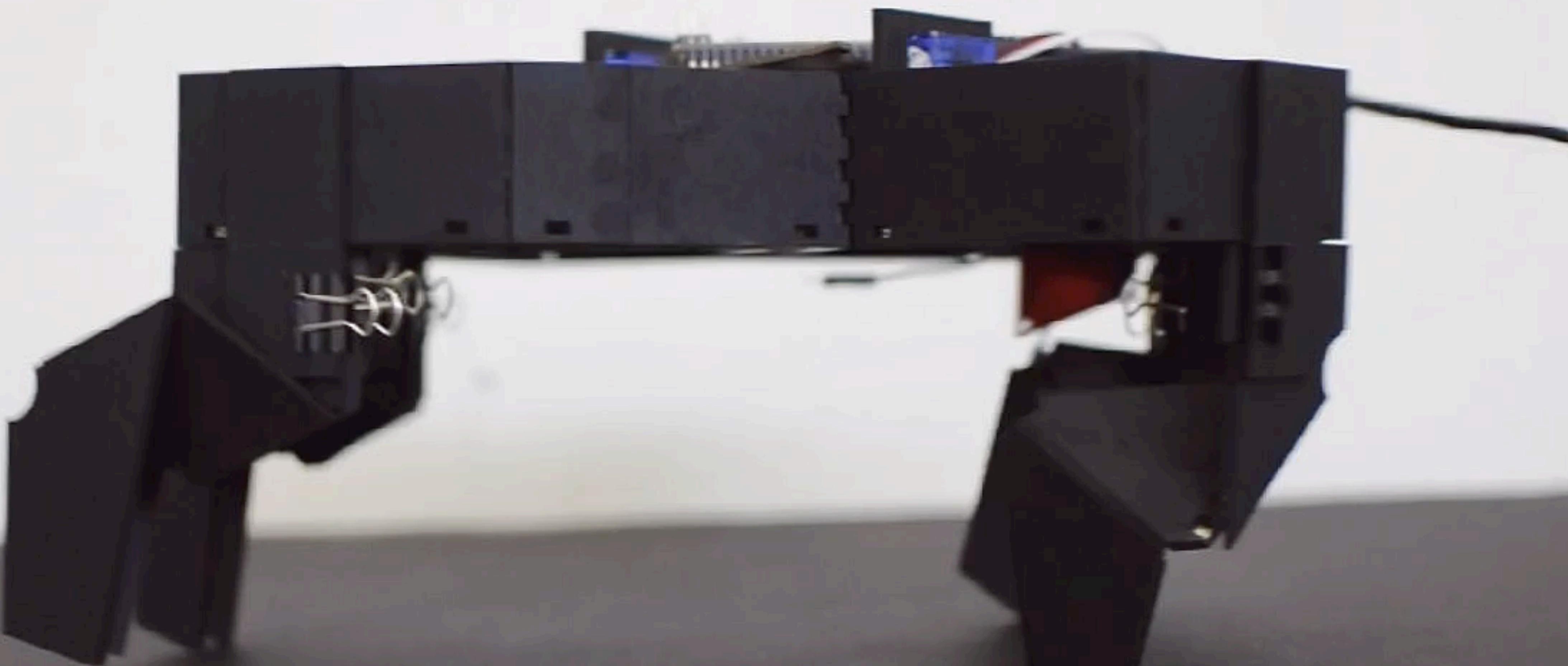


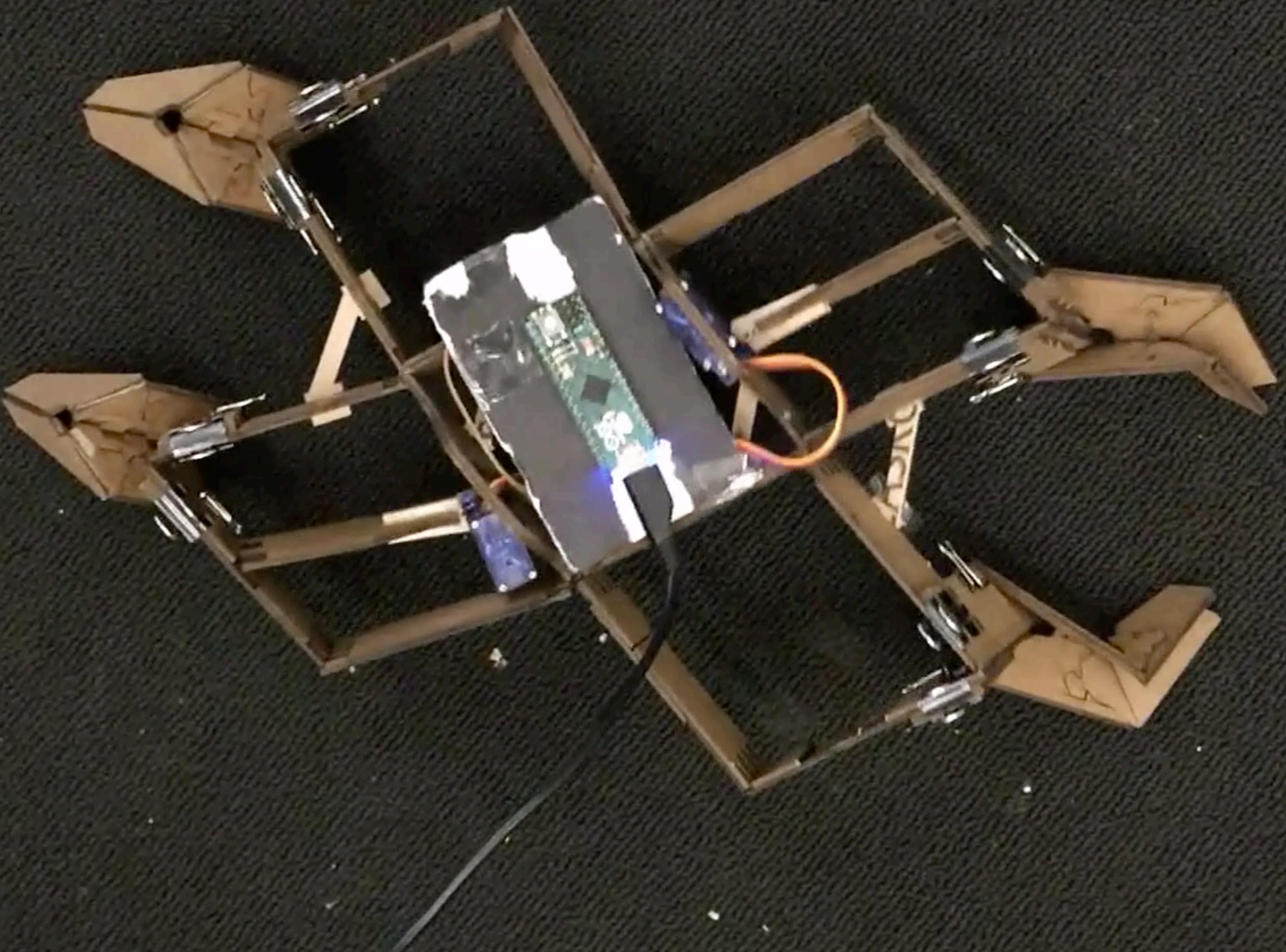












Further Development.



