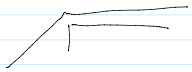
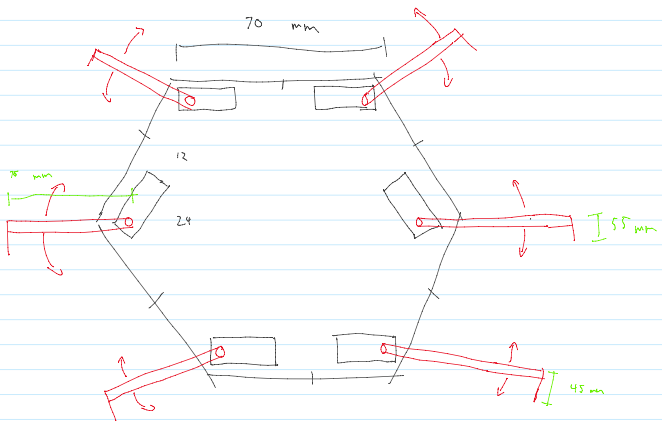
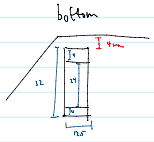
Sunday, October 20, 2019 4:16 PM

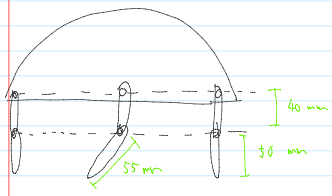
Top down view not including dome







Profile View



$60 = \sqrt{50^2 + a^2}$

$a = 33.16$

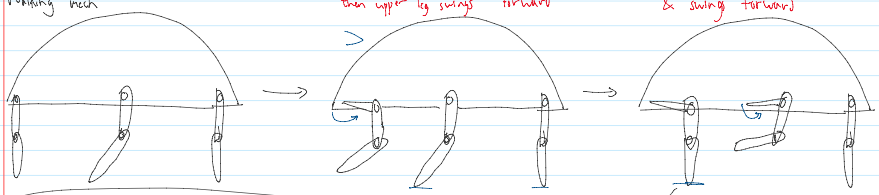
$55 = \sqrt{50^2 + a^2}$

$a = 22.912$

Walking inch

Rear legs pivots so not contacting ground then upper leg swings forward

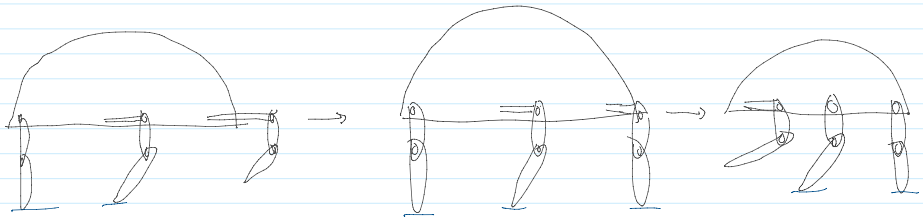
rear leg pivots down to contact ground, middle leg pivots up & swing forward



Rear leg swings back, middle leg pivots to touch ground, front leg swings & pivots

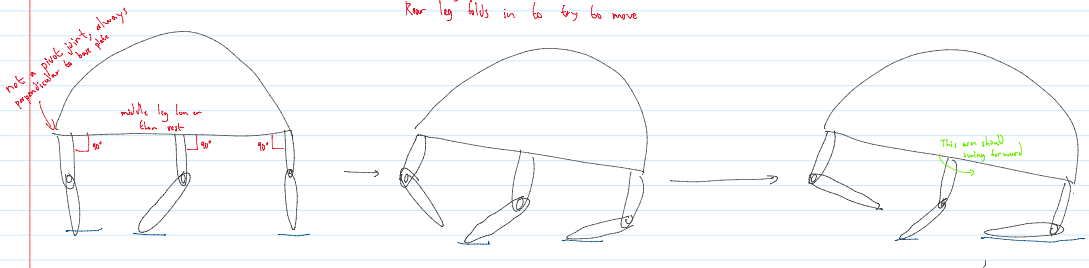
front leg pivots to make contact

rear leg pivots & swings while front 2 legs swing back



Rolling mechanic

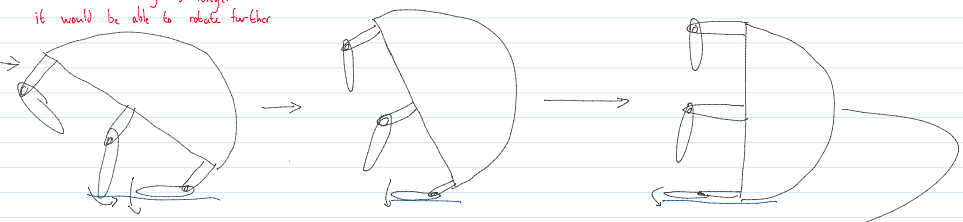
Middle leg begins to straighten out
front leg shortens down
Rear leg folds in to try to move



95

40

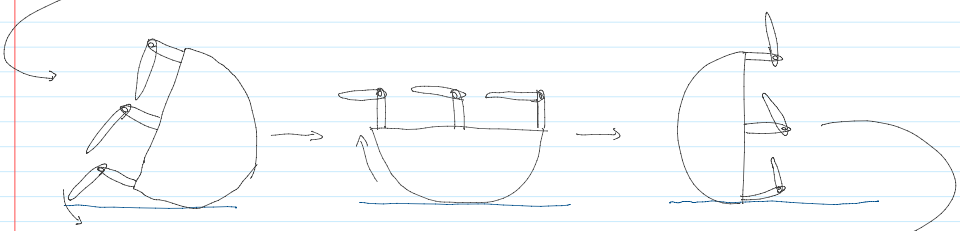
since middle leg is longer
it would be able to rotate further

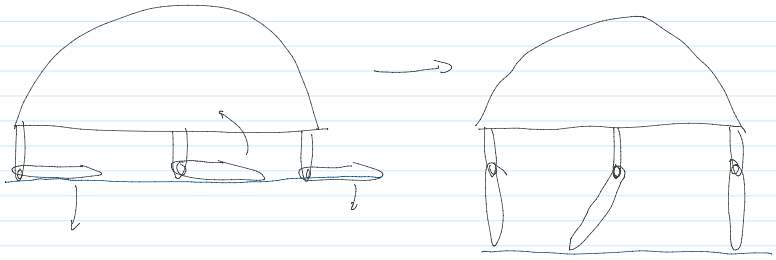


55

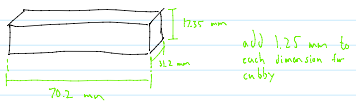
45°

50





battery dimensions



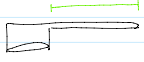
add 1.25 mm to each dimension for cubby

19.52 mm use 20.10

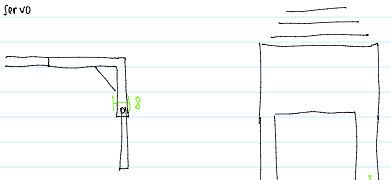
12.3
use 12.6

27.6

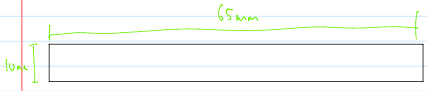
use hex base - 0.2



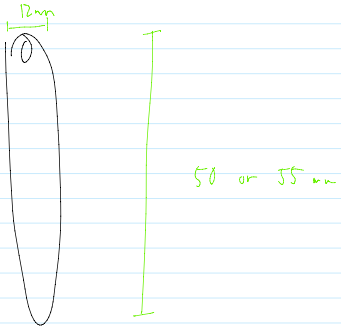
Leg design servo



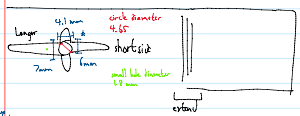
Top view



2nd link



Revision for first stage Leg



*Note the cross bends to have a wider width

V2 design

cut a strip in the arch of the leg

Extend by 17 mm

Reduce thickness from 5 mm to 3.71