

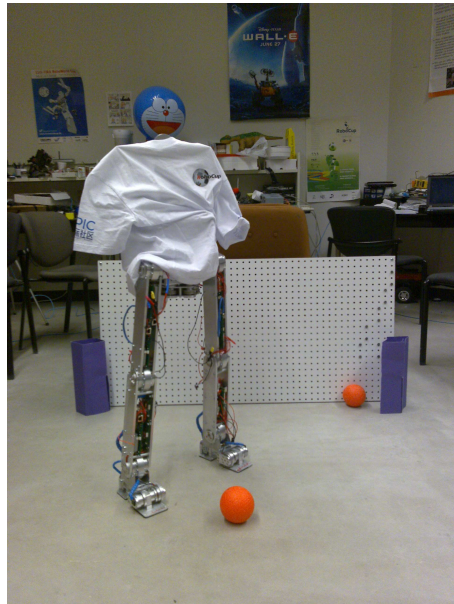
# Archie Specifications

Jacky Baltes<sup>1</sup>, Chi Tai Cheng<sup>1</sup>, M.C. Lau<sup>1</sup>, Peter Kopacek<sup>2</sup>, and John Anderson<sup>1</sup>

<sup>1</sup>Autonomous Agent Lab  
University of Manitoba  
Winnipeg, Manitoba  
Canada, R3T 2N2

[j.baltes@cs.umanitoba.ca](mailto:j.baltes@cs.umanitoba.ca)  
<http://www.cs.umanitoba.ca/~jacky>

<sup>2</sup>Institute for Handhabungsgeräte und Robotertechnik  
Technische Universität Wien  
Favoritenstr. 9-11  
A-1040 Wien, Österreich  
[kopacek@ihrt.tuwien.ac.at](mailto:kopacek@ihrt.tuwien.ac.at)



The Adult-sized Robot ARCHIE

Robot name(s)	ARCHIE
DOFs	2 * 7 (legs) + 2 * 3 (arms) + 1 * 3 (head) + 1 * 5 (Face)
Processing	2 * 1.7GHz Pentium
Walking speed	0.10 m/sec.
Camera	2 * CMOS Sensor 640x480 resolution
Sensors	3 * AD 3 axis accelerometer and 1 Inertia Measurement Unit
Other specs.	None