

NimbRo TeenSize Robot Data Sheet

Philipp Allgeuer, Hafez Farazi, Michael Schreiber, and Sven Behnke

Rheinische Friedrich-Wilhelms-Universität Bonn
Computer Science Institute VI: Autonomous Intelligent Systems
Friedrich-Ebert-Allee 144, 53113 Bonn, Germany

{ pallgeuer | hfarazi | schreiber | behnke } @ ais.uni-bonn.de
<http://www.nimbro.net>



Fig. 1. The igus Humanoid Open Platform

- **Robot name:** igus Humanoid Open Platform
- **Degrees of freedom:** 20 DOF (6 per leg, 3 per arm, 2 in the neck)
- **Type of motors:** Robotis Dynamixel MX-106 ($\times 12$) and MX-64 ($\times 8$)
- **Processor:** Intel Core i7-5500U CPU (dual-core, 2.4 GHz up to 3.0 GHz)
- **Walking speed:** Omnidirectional walking, up to 21 cm/s
- **Cameras:** Logitech C905 USB camera with a custom wide-angle lens
- **Sensors:** Robotis CM730 with onboard 3-axis accelerometer and gyroscope
- **Other specs:** Height 92 cm, weight 6.6 kg, 3D printed

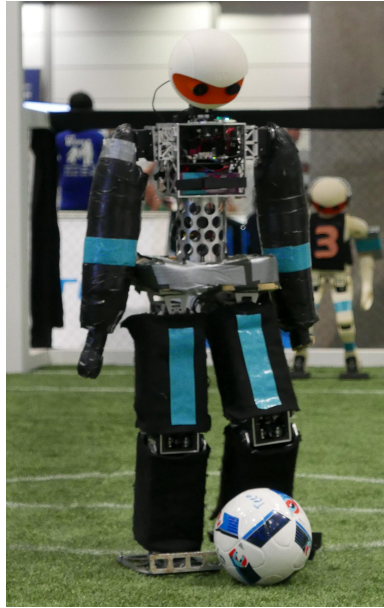


Fig. 2. The robot Dynaped

- **Robot name:** Dynaped
- **Degrees of freedom:** 14 DOF (5 per leg, 1 per arm, 2 in the neck)
- **Type of motors:** Robotis Dynamixel EX-106 and RX-64
- **Processor:** Intel Core i7-5500U CPU (dual-core, 2.4 GHz up to 3.0 GHz)
- **Walking speed:** Omnidirectional walking, up to 40 cm/s
- **Cameras:** Logitech C905 USB camera with a custom wide-angle lens
- **Sensors:** Robotis CM740 with onboard 3-axis accelerometer and gyroscope
- **Other specs:** Height 111 cm, weight 7.5 kg