

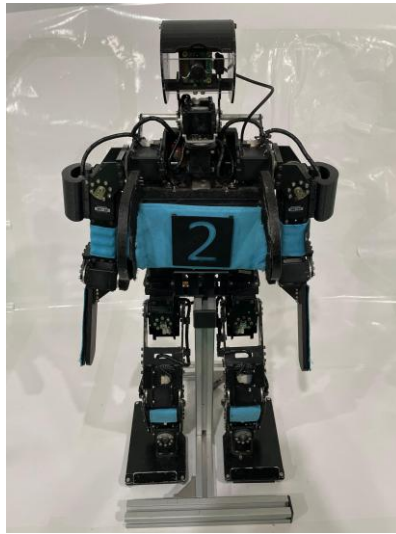
Barelang FC Robot Specification

BarelangFC 1



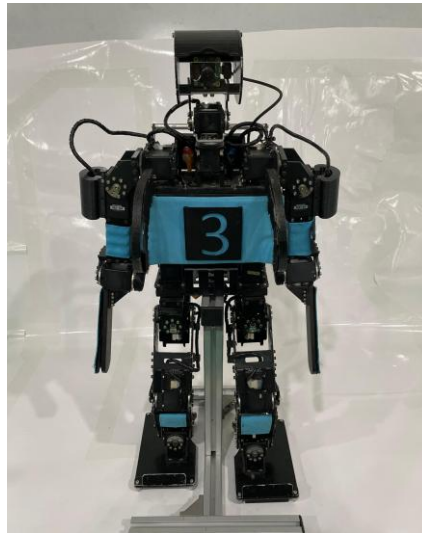
Dimension	Height	690 mm
	Foot	100 mm x 160 mm
	Leg	370 mm
	Arm	320 mm
	Weight	6,874 kg
20 DoF	Head	2 Dynamixel MX 28
	Hip	2 Dynamixel MX 64
	Arm	3x2 Dynamixel MX 64
	Leg	5x2 Dynamixel MX 106
Motion	Walking Speed	25 cm/s
Sensor	Camera	See3CAM _CU55M
	IMU	- GY-25 Tilt Angle. - ICM-20648 Gyroscope, Accelerometer.
Computing Unit	Main-Controller	NVIDIA Jetson Xavier NX
	Sub-Controller	OpenCR 1.0
Materials	Head	Aluminum 6061 and PLA+ Filament
	Arm	Aluminum 6061, Polyoxymethylene, and TPU Filament
	Hip	Aluminum 6061, Polyoxymethylene, and PLA+ Filament
	Leg	Aluminum 6061 and Polyoxymethylene
Electronics	OpenCR 1.0	Communicating with servo
	USB to Dynamixel	The interface between the main controller and sub-controller
Operating System	Ubuntu 20.04	
Battery	LiPo Battery 4 cell 2200 mAh	

BarelangFC 2



Dimension	Height	690 mm
	Foot	100 mm x 160 mm
	Leg	370 mm
	Arm	320 mm
	Weight	6,874 kg
20 DoF	Head	2 Dynamixel MX 28
	Hip	2 Dynamixel MX 64
	Arm	3x2 Dynamixel MX 64
	Leg	5x2 Dynamixel MX 106
Motion	Walking Speed	25 cm/s
Sensor	Camera	See3CAM _CU55M
	IMU	- GY-25 Tilt Angle. - ICM-20648 Gyroscope, Accelerometer.
Computing Unit	Main-Controller	NVIDIA Jetson Xavier NX
	Sub-Controller	OpenCR 1.0
Materials	Head	Aluminum 6061 and PLA+ Filament
	Arm	Aluminum 6061, Polyoxymethylene, and TPU Filament
	Hip	Aluminum 6061, Polyoxymethylene, and PLA+ Filament
	Leg	Aluminum 6061 and Polyoxymethylene
Electronics	OpenCR 1.0	Communicating with servo
	USB to Dynamixel	The interface between the main controller and sub-controller
Operating System	Ubuntu 20.04	
Battery	LiPo Battery 4 cell 2200 mAh	

BarelangFC 3



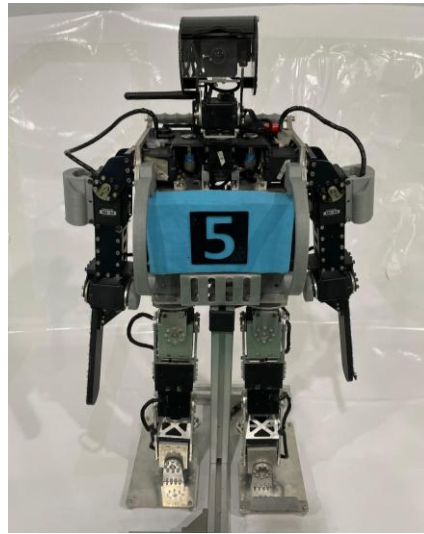
Dimension	Height	690 mm
	Foot	100 mm x 160 mm
	Leg	370 mm
	Arm	320 mm
	Weight	6,874 kg
20 DoF	Head	2 Dynamixel MX 28
	Hip	2 Dynamixel MX 64
	Arm	3x2 Dynamixel MX 64
	Leg	5x2 Dynamixel MX 106
Motion	Walking Speed	25 cm/s
Sensor	Camera	See3CAM _CU55M
	IMU	- GY-25 Tilt Angle. - ICM-20648 Gyroscope, Accelerometer.
Computing Unit	Main-Controller	NVIDIA Jetson Xavier NX
	Sub-Controller	OpenCR 1.0
Materials	Head	Aluminum 6061 and PLA+ Filament
	Arm	Aluminum 6061, Polyoxymethylene, and TPU Filament
	Hip	Aluminum 6061, Polyoxymethylene, and PLA+ Filament
	Leg	Aluminum 6061 and Polyoxymethylene
Electronics	OpenCR 1.0	Communicating with servo
	USB to Dynamixel	The interface between the main controller and sub-controller
Operating System	Ubuntu 20.04	
Battery	LiPo Battery 4 cell 2200 mAh	

BarelangFC 4



Dimension	Height	690 mm
	Foot	100 mm x 160 mm
	Leg	370 mm
	Arm	320 mm
	Weight	6,874 kg
20 DoF	Head	2 Dynamixel MX 28
	Hip	2 Dynamixel MX 64
	Arm	3x2 Dynamixel MX 64
	Leg	5x2 Dynamixel MX 106
Motion	Walking Speed	25 cm/s
Sensor	Camera	See3CAM _CU55M
	IMU	- GY-25 Tilt Angle. - ICM-20648 Gyroscope, Accelerometer.
Computing Unit	Main-Controller	NVIDIA Jetson Xavier NX
	Sub-Controller	OpenCR 1.0
Materials	Head	Aluminum 6061 and PLA+ Filament
	Arm	Aluminum 6061, Polyoxymethylene, and TPU Filament
	Hip	Aluminum 6061, Polyoxymethylene, and PLA+ Filament
	Leg	Aluminum 6061 and Polyoxymethylene
Electronics	OpenCR 1.0	Communicating with servo
	USB to Dynamixel	The interface between the main controller and sub-controller
Operating System	Ubuntu 20.04	
Battery	LiPo Battery 4 cell 2200 mAh	

BarelangFC 5



Dimension	Height	670 mm
	Foot	100 mm x 160 mm
	Leg	370 mm
	Arm	320 mm
	Weight	7,367 kg
20 DoF	Head	2 Dynamixel MX 28
	Hip	2 Dynamixel XH 540
	Arm	3x2 Dynamixel MX 64
	Leg	5x2 Dynamixel XH 540
Motion	Walking Speed	25 cm/s
Sensor	Camera	See3CAM _CU55M
	IMU	- GY-25 Tilt Angle. - ICM-20648 Gyroscope, Accelerometer.
Computing Unit	Main-Controller	NVIDIA Jetson Xavier NX
	Sub-Controller	OpenCR 1.0
Materials	Head	Aluminum 6061 and PLA+ Filament
	Arm	Aluminum 6061, Polyoxymethylene, and TPU Filament
	Hip	Aluminum 6061
	Leg	Aluminum 6061 and Polyoxymethylene
Electronics	OpenCR 1.0	Communicating with servo
	USB to Dynamixel	The interface between the main controller and sub-controller
Operating System	Ubuntu 20.04	
Battery	LiPo Battery 4 cell 2200 mAh	