Interest Points:
A - Toe\{L,R\}\{Fr,Bk\}Paw_4
B - Lower\{Inner,Outer\}Front\{L,R\}\{Fr,Bk\}Shin_3
C - Lower\{Inner,Outer\}Middle\{L,R\}\{Fr,Bk\}Shin_3
D - Lower\{Inner,Outer\}Back\{L,R\}\{Fr,Bk\}Shin_3
E - Middle\{Inner,Outer\}Middle\{L,R\}\{Fr,Bk\}Shin_3
F - Upper\{Inner,Outer\}Front\{L,R\}\{Fr,Bk\}Shin_3
G - Upper\{Inner,Outer\}Back\{L,R\}\{Fr,Bk\}Shin_3
H - Lower\{Inner,Outer\}Front\{L,R\}\{Fr,Bk\}Thigh_2
I - Lower\{Inner,Outer\}Back\{L,R\}\{Fr,Bk\}Thigh_2
J - Upper\{Inner,Outer\}Front\{L,R\}\{Fr,Bk\}Thigh_2
K - Upper\{Inner,Outer\}Back\{L,R\}\{Fr,Bk\}Thigh_2
L - Upper\{L,R\}Chest_0
M - Lower\{L,R\}Chest_0
N - \{L,R\}\{Fr,Bk\}Belly_0
O - Lower\{L,R\}Rump_0
P - Upper\{L,R\}Rump_0

ERS-7 Legs

<table>
<thead>
<tr>
<th></th>
<th>(\Delta x)</th>
<th>(\Delta y)</th>
<th>(\Delta z)</th>
</tr>
</thead>
<tbody>
<tr>
<td>1. - shoulder</td>
<td>65</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>2. - elevator</td>
<td>0</td>
<td>0</td>
<td>62.5</td>
</tr>
<tr>
<td>3. - knee</td>
<td>69.5</td>
<td>0</td>
<td>9</td>
</tr>
<tr>
<td>f4. - ball</td>
<td>69.987</td>
<td>-4.993</td>
<td>4.7</td>
</tr>
<tr>
<td>h4. - ball</td>
<td>67.681</td>
<td>-18.503</td>
<td>4.7</td>
</tr>
</tbody>
</table>

Diameter of ball of foot is 23.433mm
Each link offset is relative to previous link

The shins shown in this diagram appear to be slightly distorted compared to a real robot.
Corresponding measurements have been taken from actual models.