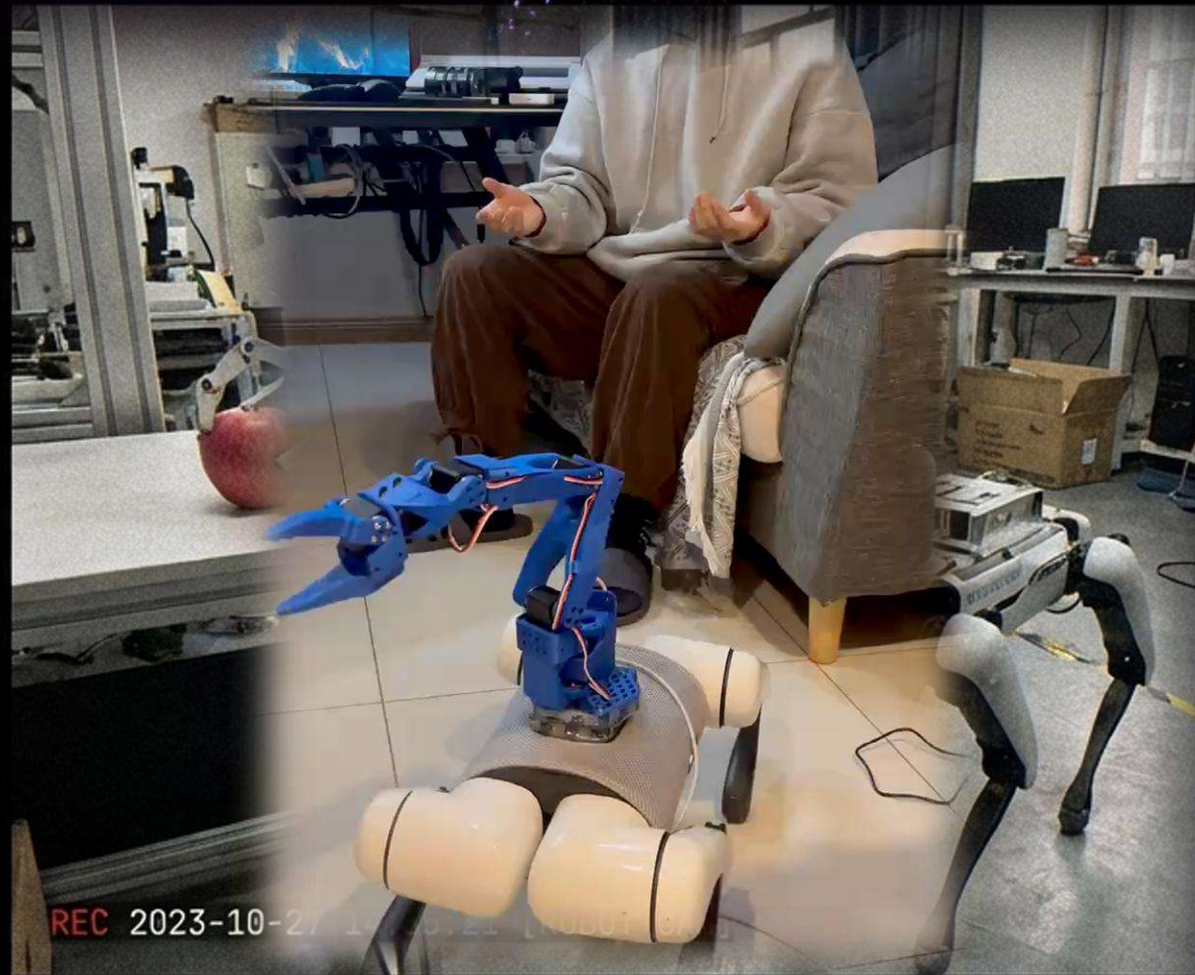


00make / Zhang Zhenyao

代码的重量

I am Lazy.



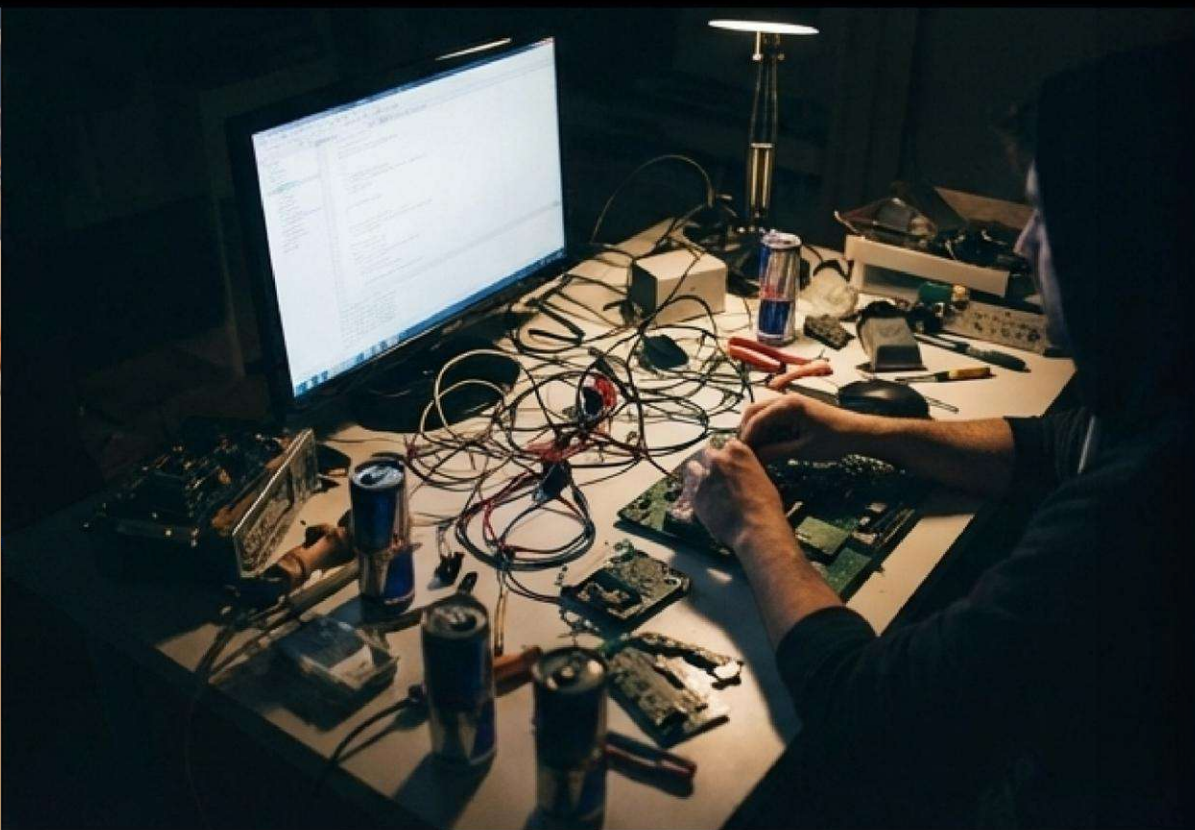
TELEOPERATION PROTOTYPE: DIRECT MANIPULATION

Raw Footage. Unedited.





外界眼中的“光鲜”

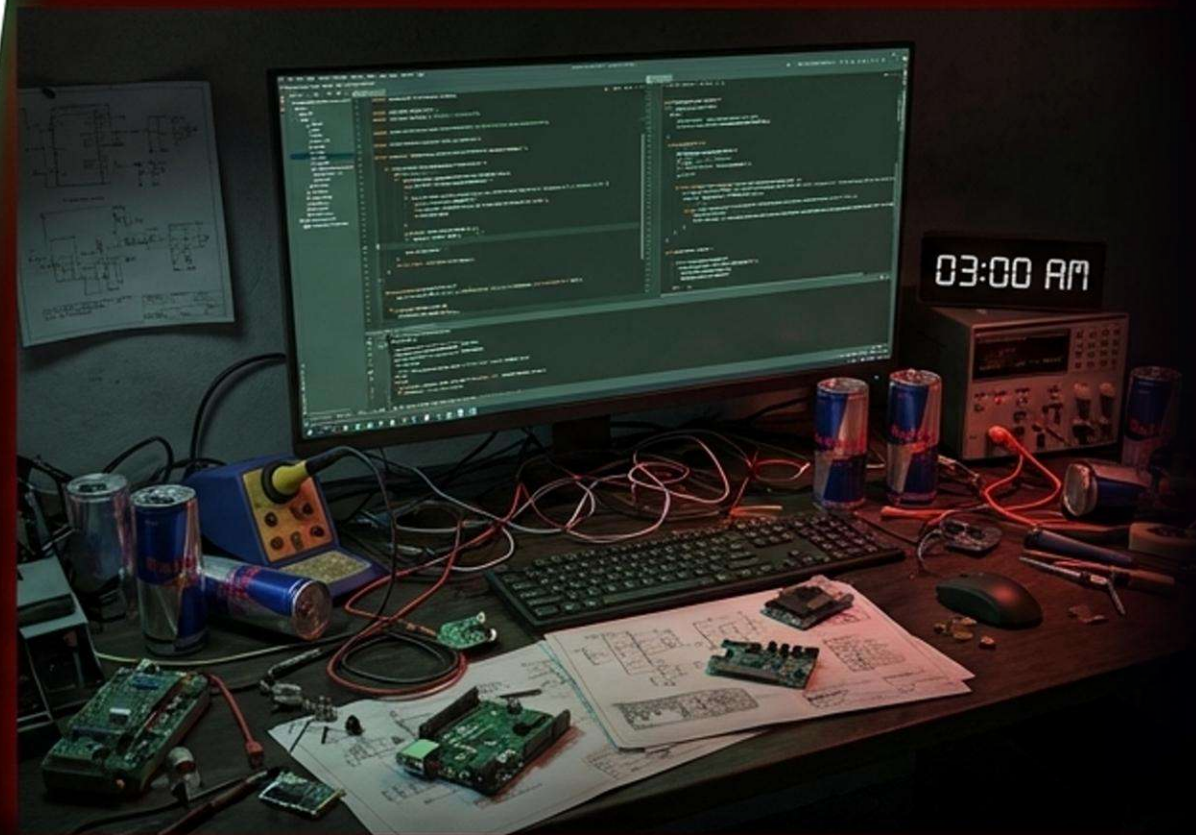


凌晨3点的“地狱”

光鲜 (GLAMOUR)

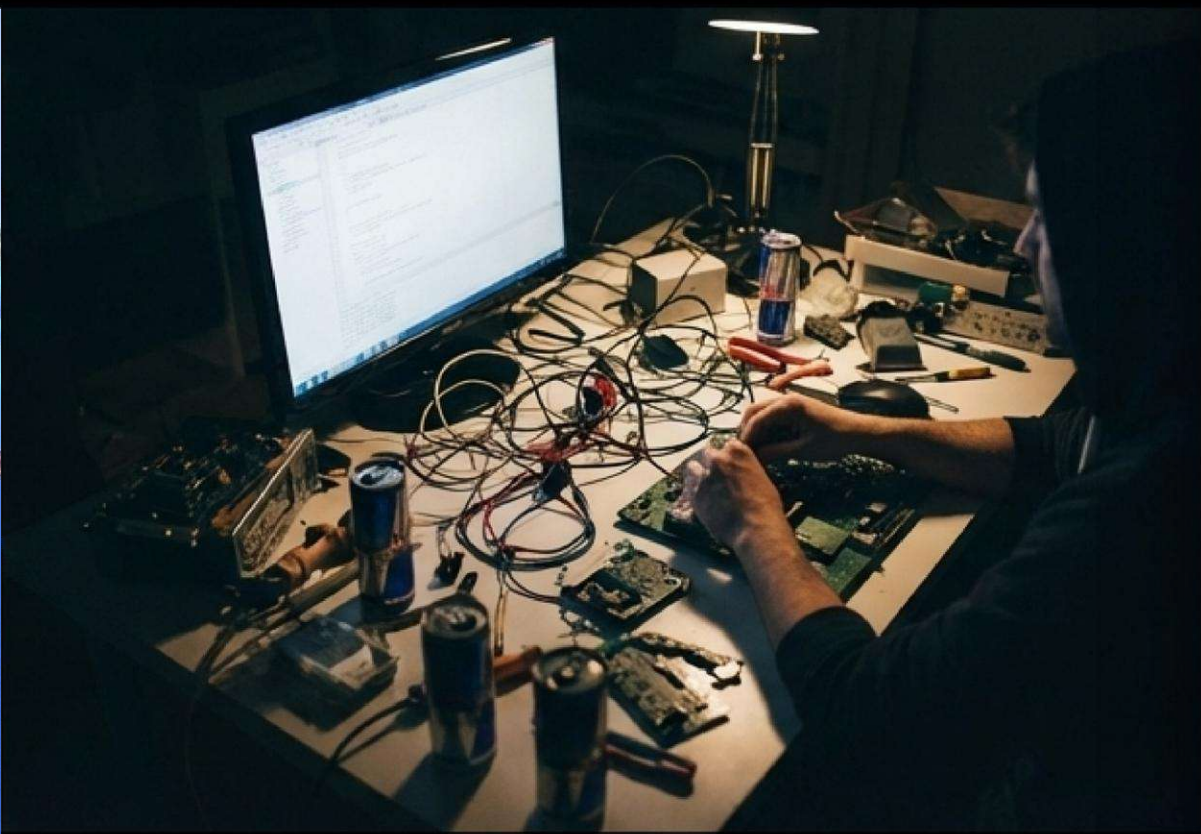


地狱 (HELL)





外界眼中的“光鲜”



凌晨3点的“地狱”

```
tion=Hardware Interface Service
WantedBy=network.target
ConditionPathExists=/etc/hardware/config.json
```

```
[Service]
Type=simple
User=root Group=root
WorkingDirectory=/opt/hardware/drivers
ExecStart=/usr/bin/python3 /opt/hardware/drivers/main.py --config /etc/hardware/config.json --log-level DEBUG --device-path /dev/ttyUSB0 --baudrate 115200 --timeout
```

```
Restart=on-failure
RestartSec=5s
Environment="LD_LIBRARY_PATH=/opt/hardware/libs:$LD_LIBRARY_PATH"
Environment="PYTHONPATH=/opt/hardware/drivers:$PYTHONPATH"
```

```
Configure hardware parameters
Ensure correct permissions for device access
Handle specific error codes
Handle=correctdata
ExecStart=/usr/bin/python3 /opt/hardware/libs:$LD_LIBRARY_PATH --acors=0000
ConfigClose=etc/hardware/config.json
LogLevel=DEBUG--main.py
LogLevel config=133200
SystemdServiceBaud=115200
ExecStart=/usr/bin/python3 /opt/hardware/drivers/main.py /etc/hardware
Restart=on-failure
ExecStarts=/etc/hardware/config.json
RestartSec=5s
Environment="LD_LIBRARY_PATH=/opt/hardware/libs:$LD_LIBRARY_PATH"
Environment="PYTHONPATH=/opt/hardware/drivers:$PYTHONPATH"
Ensure correct permissions for device access
Handle specific error codes
Environment="LD_LIBRARY_PATH=/opt/hardware/libs:$LD_LIBRARY_PATH"
Environment="PYTHONPATH=/opt/hardware/drivers:$PYTHONPATH"
```

```
Configure hardware parameters
Ensure correct permissions for device access
Handle specific error codes
```

```
StandardOutput=journal
StandardError=journal
```



24 Hours → **10 Minutes**



`dog.go_forward()`

荣誉证书

CERTIFICATE OF HONOR

授予 紫荆战队

2025国际人形机器人技能大赛

(张江启动赛)

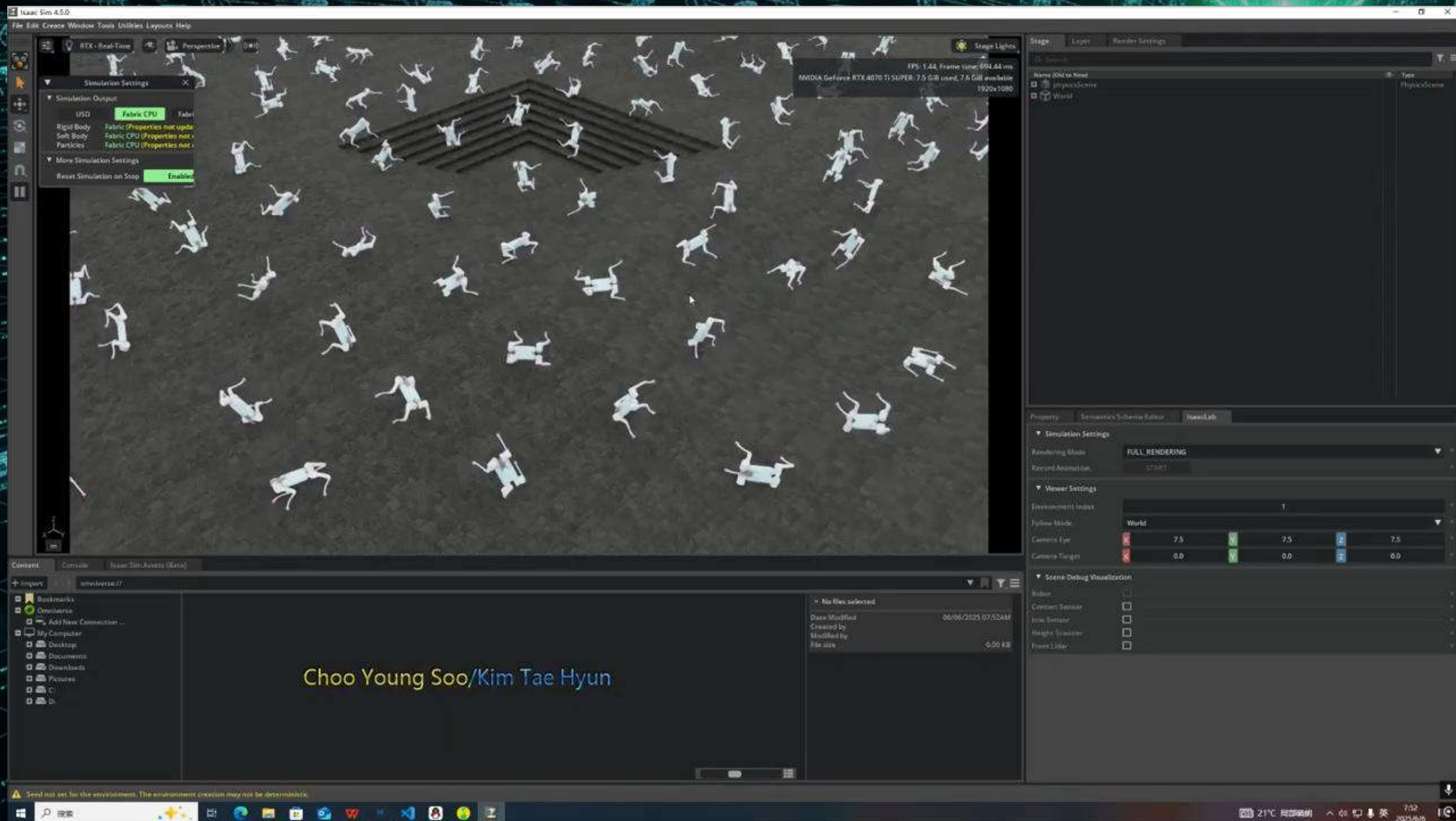
人形机器人应用场景挑战赛 张江记录

第一名

参赛单位: 清华大学

参赛成员: 陈树帆、卢嵩、张铮、张振尧、李庆伟

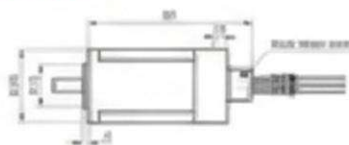
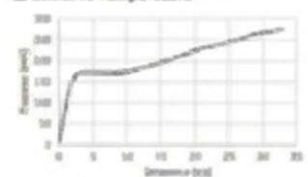
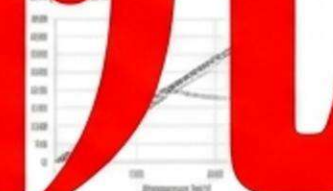
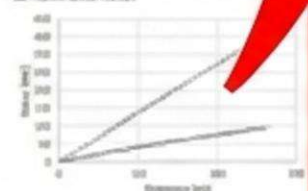
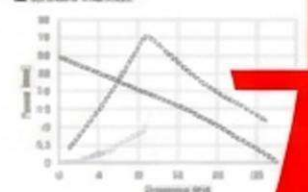
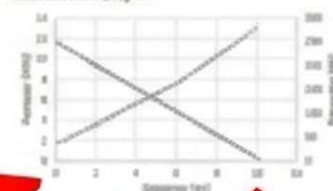




A large number of green wireframe kangaroos are running in a field, symbolizing speed and iteration. The kangaroos are arranged in a grid-like pattern, moving towards the right. The background is a dark, textured surface with a subtle pattern of small, glowing green dots.

在工程中，迭代速度就是上帝。

Robot Motor



Parameter	Default	Range
Water level	0.000	0.000 to 1.000
Water type	0.000	0.000 to 1.000
Water velocity	0.000	0.000 to 1.000
Water density	1.000	0.000 to 1.000
Water viscosity	0.000	0.000 to 1.000
Water temperature	0.000	0.000 to 1.000
Water salinity	0.000	0.000 to 1.000
Water color	0.000	0.000 to 1.000
Water turbidity	0.000	0.000 to 1.000
Water transparency	0.000	0.000 to 1.000
Water clarity	0.000	0.000 to 1.000
Water visibility	0.000	0.000 to 1.000
Water depth	0.000	0.000 to 1.000
Water width	0.000	0.000 to 1.000
Water height	0.000	0.000 to 1.000
Water area	0.000	0.000 to 1.000
Water volume	0.000	0.000 to 1.000
Water mass	0.000	0.000 to 1.000
Water weight	0.000	0.000 to 1.000
Water pressure	0.000	0.000 to 1.000
Water force	0.000	0.000 to 1.000
Water energy	0.000	0.000 to 1.000
Water power	0.000	0.000 to 1.000
Water speed	0.000	0.000 to 1.000
Water flow	0.000	0.000 to 1.000
Water rate	0.000	0.000 to 1.000
Water time	0.000	0.000 to 1.000
Water distance	0.000	0.000 to 1.000
Water angle	0.000	0.000 to 1.000
Water direction	0.000	0.000 to 1.000
Water position	0.000	0.000 to 1.000
Water location	0.000	0.000 to 1.000
Water status	0.000	0.000 to 1.000
Water condition	0.000	0.000 to 1.000
Water quality	0.000	0.000 to 1.000
Water quantity	0.000	0.000 to 1.000
Water amount	0.000	0.000 to 1.000
Water number	0.000	0.000 to 1.000
Water count	0.000	0.000 to 1.000
Water total	0.000	0.000 to 1.000
Water sum	0.000	0.000 to 1.000
Water average	0.000	0.000 to 1.000
Water mean	0.000	0.000 to 1.000
Water median	0.000	0.000 to 1.000
Water mode	0.000	0.000 to 1.000
Water range	0.000	0.000 to 1.000
Water variance	0.000	0.000 to 1.000
Water standard deviation	0.000	0.000 to 1.000
Water covariance	0.000	0.000 to 1.000
Water correlation	0.000	0.000 to 1.000
Water regression	0.000	0.000 to 1.000
Water prediction	0.000	0.000 to 1.000
Water estimation	0.000	0.000 to 1.000
Water calculation	0.000	0.000 to 1.000
Water operation	0.000	0.000 to 1.000
Water process	0.000	0.000 to 1.000
Water treatment	0.000	0.000 to 1.000
Water management	0.000	0.000 to 1.000
Water control	0.000	0.000 to 1.000
Water regulation	0.000	0.000 to 1.000
Water supervision	0.000	0.000 to 1.000
Water monitoring	0.000	0.000 to 1.000
Water observation	0.000	0.000 to 1.000
Water inspection	0.000	0.000 to 1.000
Water examination	0.000	0.000 to 1.000
Water investigation	0.000	0.000 to 1.000
Water research	0.000	0.000 to 1.000
Water study	0.000	0.000 to 1.000
Water analysis	0.000	0.000 to 1.000
Water evaluation	0.000	0.000 to 1.000
Water assessment	0.000	0.000 to 1.000
Water determination	0.000	0.000 to 1.000
Water identification	0.000	0.000 to 1.000
Water recognition	0.000	0.000 to 1.000
Water detection	0.000	0.000 to 1.000
Water discovery	0.000	0.000 to 1.000
Water finding	0.000	0.000 to 1.000
Water location	0.000	0.000 to 1.000
Water position	0.000	0.000 to 1.000
Water direction	0.000	0.000 to 1.000
Water movement	0.000	0.000 to 1.000
Water action	0.000	0.000 to 1.000
Water behavior	0.000	0.000 to 1.000
Water reaction	0.000	0.000 to 1.000
Water response	0.000	0.000 to 1.000
Water effect	0.000	0.000 to 1.000
Water influence	0.000	0.000 to 1.000
Water impact	0.000	0.000 to 1.000
Water effect	0.000	0.000 to 1.000
Water influence	0.000	0.000 to 1.000
Water impact	0.000	0.000 to 1.000
Water effect	0.000	0.000 to 1.000

	2019	2020	2021
Revenue	100	100	100
Operating Expenses	30	30	30
Operating Income	70	70	70
Interest Expense	10	10	10
Income Before Tax	60	60	60
Tax Expense	12	12	12
Net Income	48	48	48

[illegible]

* Data are the ratio of gross regional (G%) EU small company-MS employment total.



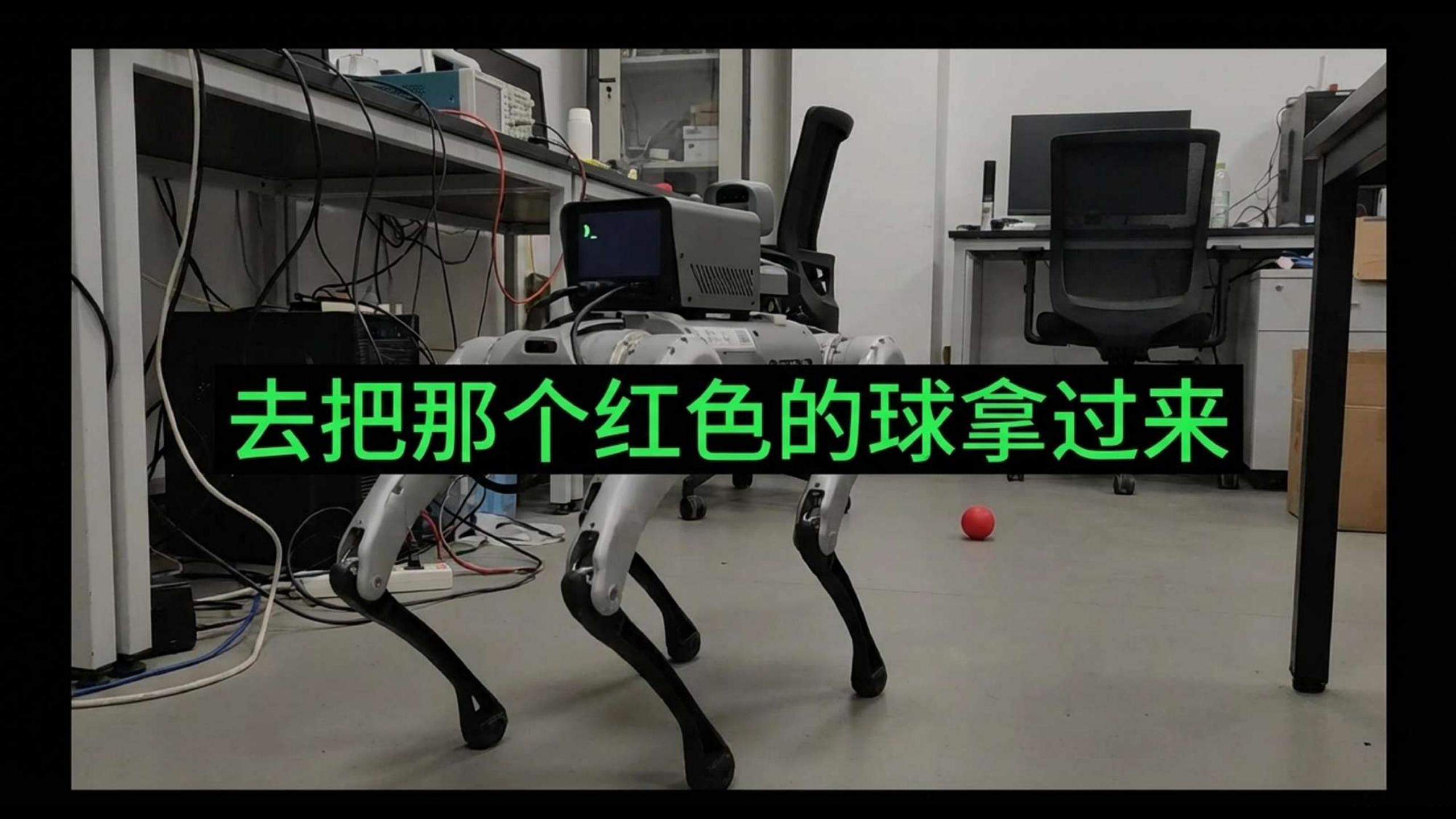
具身智能时代的“维基解密”

TECHNICAL SPECIFICATIONS - H-SERIES MOTOR

PARAMETER	VALUE	UNIT
MAX TORQUE	35.0	Nm
RATED POWER	1500	W
MAX SPEED	4500	RPM
EFFICIENCY	96%	-

Note: Values are under ideal test conditions. Subject to change.



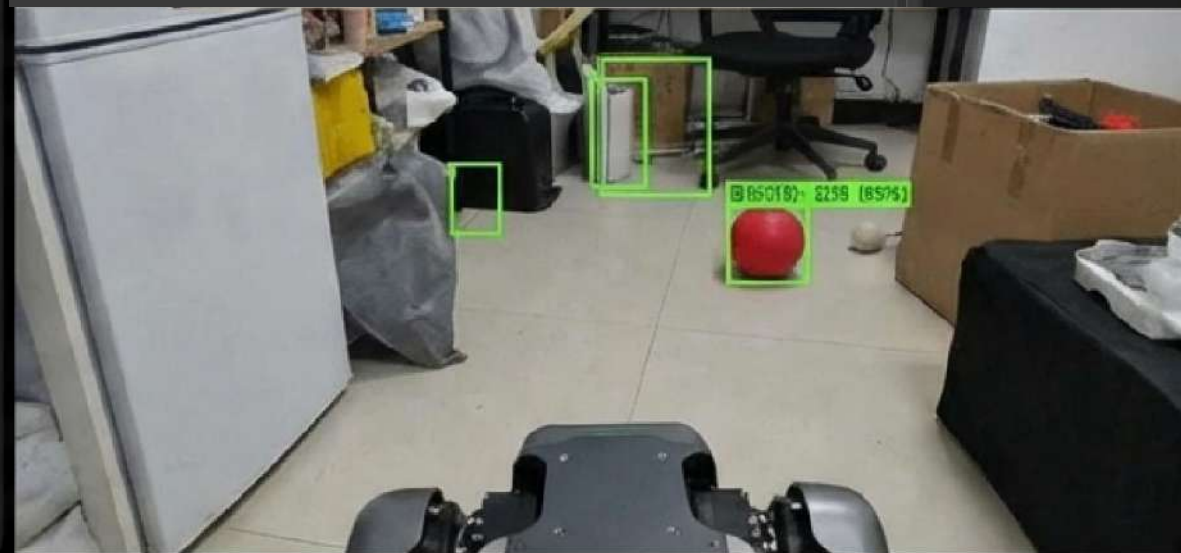
A quadruped robot, resembling a Boston Dynamics Spot, is positioned in a laboratory setting. The robot has a white body and black legs. A small screen on its back displays a green light. In the background, there are lab benches with various equipment, including a computer monitor and a chair. A red ball is on the floor in the distance. A large green text overlay is centered across the middle of the image.

去把那个红色的球拿过来

给我拿那个红色的球



坐标轴: (0,0,0)
目标位置: (100.0cm, 150.0cm, 50.0cm)
轨迹点:
T1: x=0.0, y=0.0, z=0.0
T2: x=0.0, y=0.0, z=0.0
T3: x=0.0, y=0.0, z=0.0
T4: x=0.0, y=0.0, z=0.0
T5: x=0.0, y=0.0, z=0.0
T6: x=0.0, y=0.0, z=0.0
T7: x=0.0, y=0.0, z=0.0
T8: x=0.0, y=0.0, z=0.0
T9: x=0.0, y=0.0, z=0.0
T10: x=0.0, y=0.0, z=0.0



我们正在把大模型塞进机器的身体里。



张振尧 ¹⁰⁰
北京 朝阳



Join the Resistance

扫码，来找我。