US 20070149089A1

(19) **United States**

(12) **Patent Application Publication** (10) **Pub. No.: US 2007/0149089 A1**

De La Torre (43) **Pub. Date: Jun. 28, 2007**

(54) **CUSTOMIZABLE ACTION FIGURES**

(76) Inventor: **Gabriel De La Torre**, Bell Gardens, CA (US)

Correspondence Address:
KOLISCH HARTWELL, P.C.
200 PACIFIC BUILDING
520 SW YAMHILL STREET
PORTLAND, OR 97204 (US)

(21) Appl. No.: **11/594,574**

(22) Filed: **Nov. 7, 2006**

Related U.S. Application Data

(60) Provisional application No. 60/734,710, filed on Nov. 7, 2005.

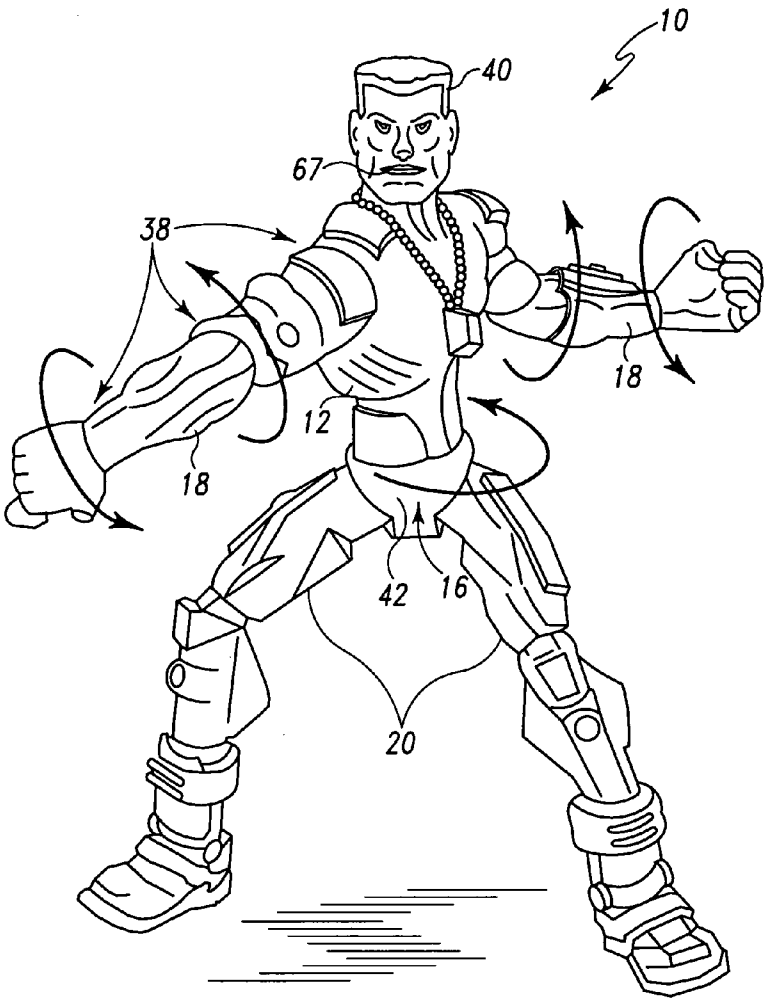
Publication Classification

(51) **Int. Cl.**
A63H 3/36 (2006.01)

(52) **U.S. Cl.** **446/373**

(57) **ABSTRACT**

Customizable action figures comprising a torso, a transmission mechanism supported in the torso, and an appendage operatively connected to the transmission mechanism. In some examples, the customizable action figures may include an upper torso rotatably connected to a lower torso. In some examples, the customizable action figures may include an appendage having a plurality of segments, with each segment configured to move relative to one or more neighboring segments. In some examples, the customizable action figures may include a set of arms, with each arm being configured to be selectively coupled to the transmission mechanism, or each arm may be configured to move differently than an other arm in the set.



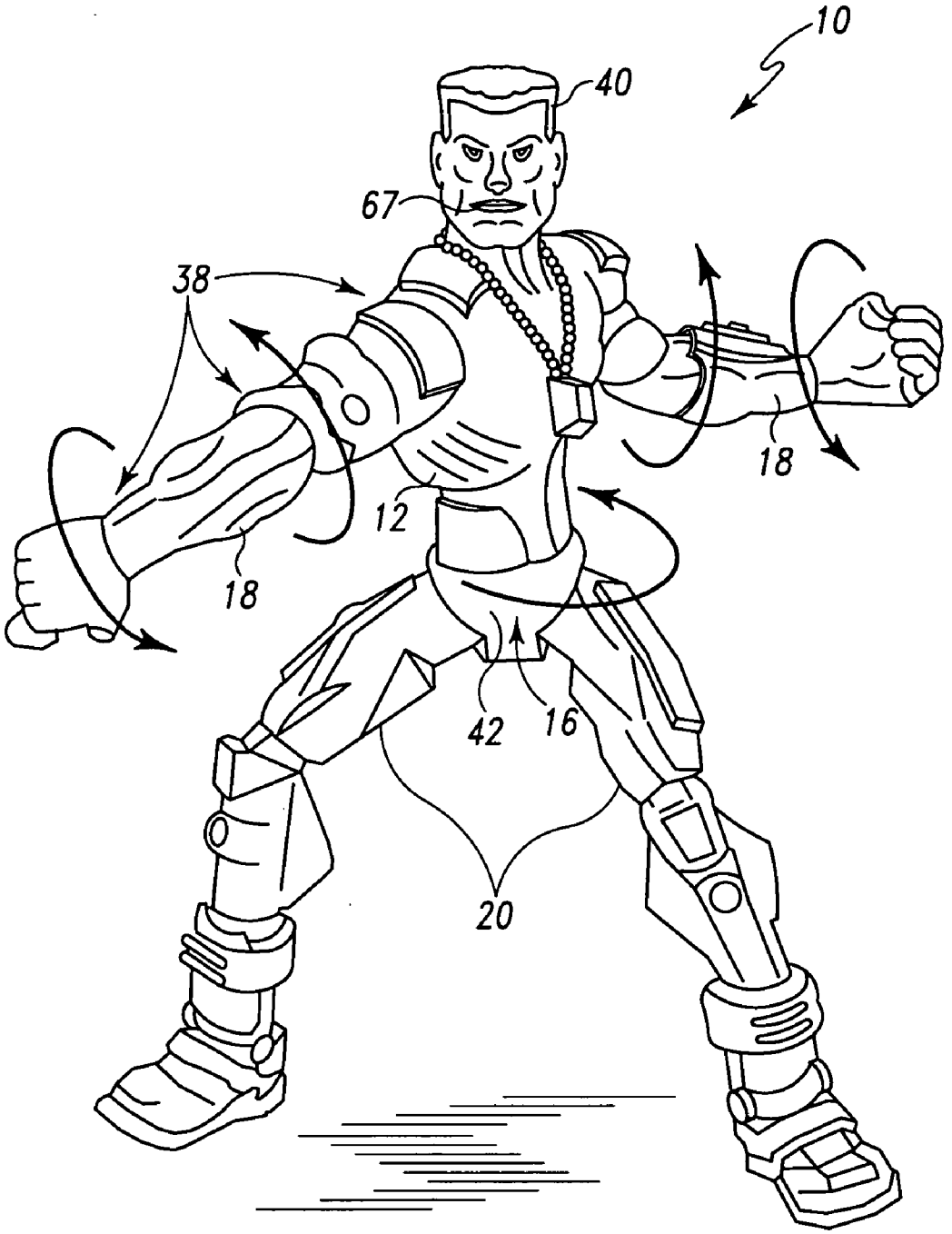


Fig. 1

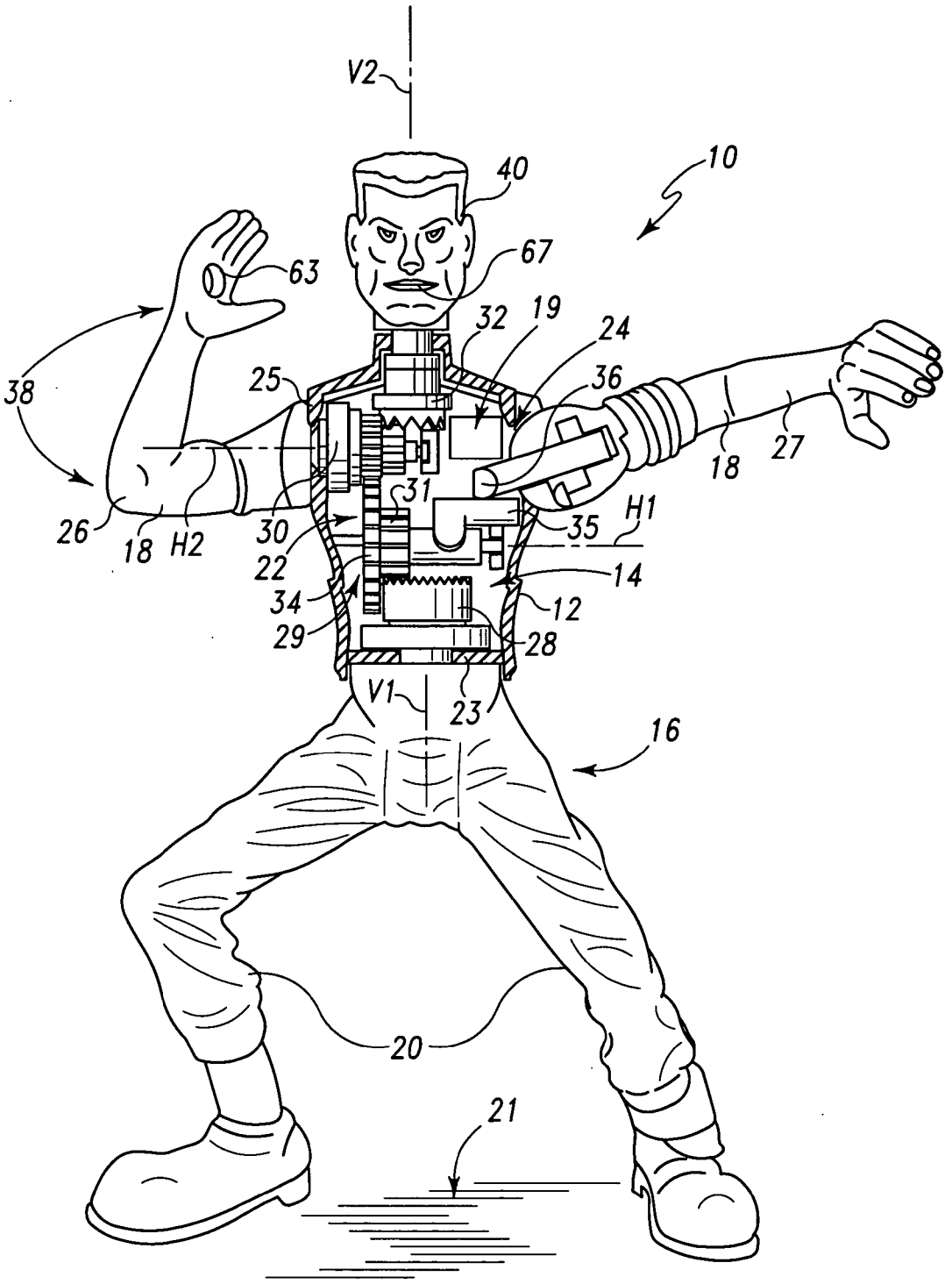

V2
40
10
63
67
32
19
24
25
36
38
31
18
27
26
18
H2
30
35
H1
22
14
34
12
29
28
V1
23
16
20
21

Fig. 2

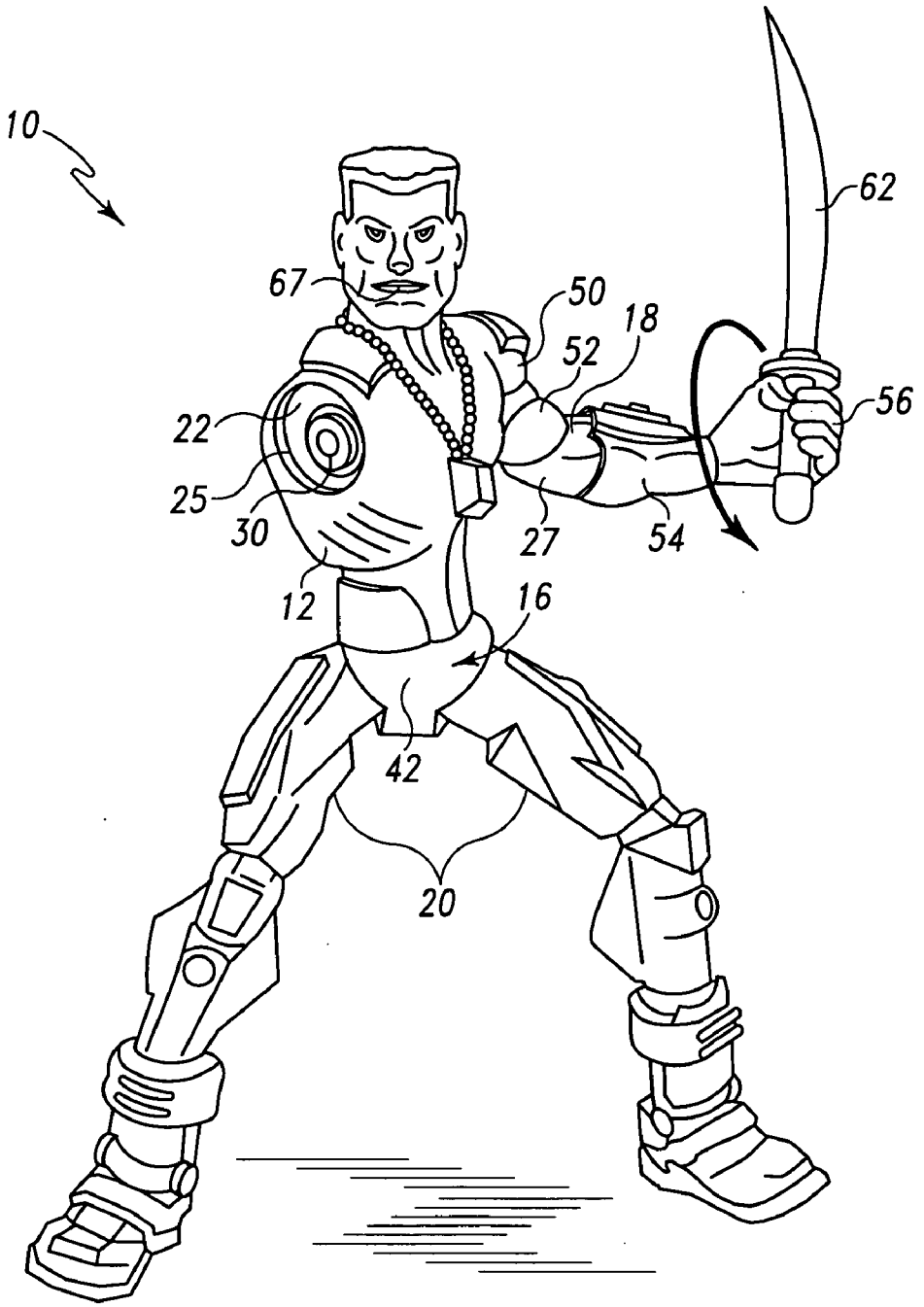


Fig. 3

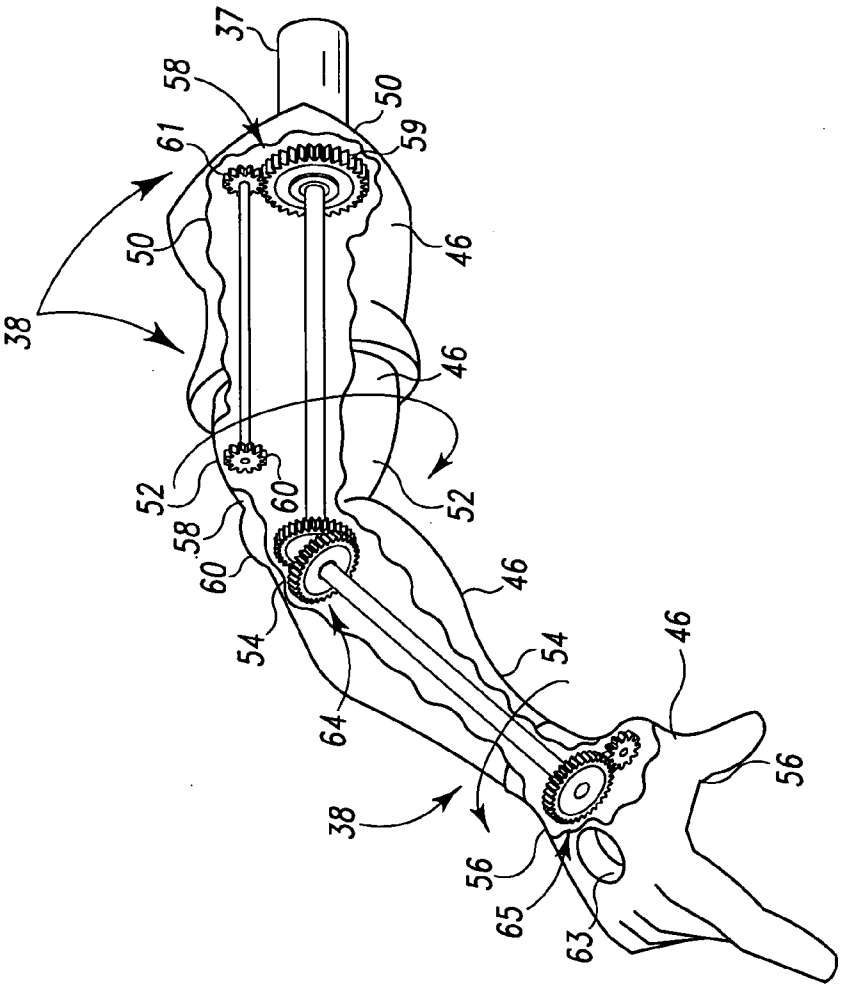


Fig. 4A

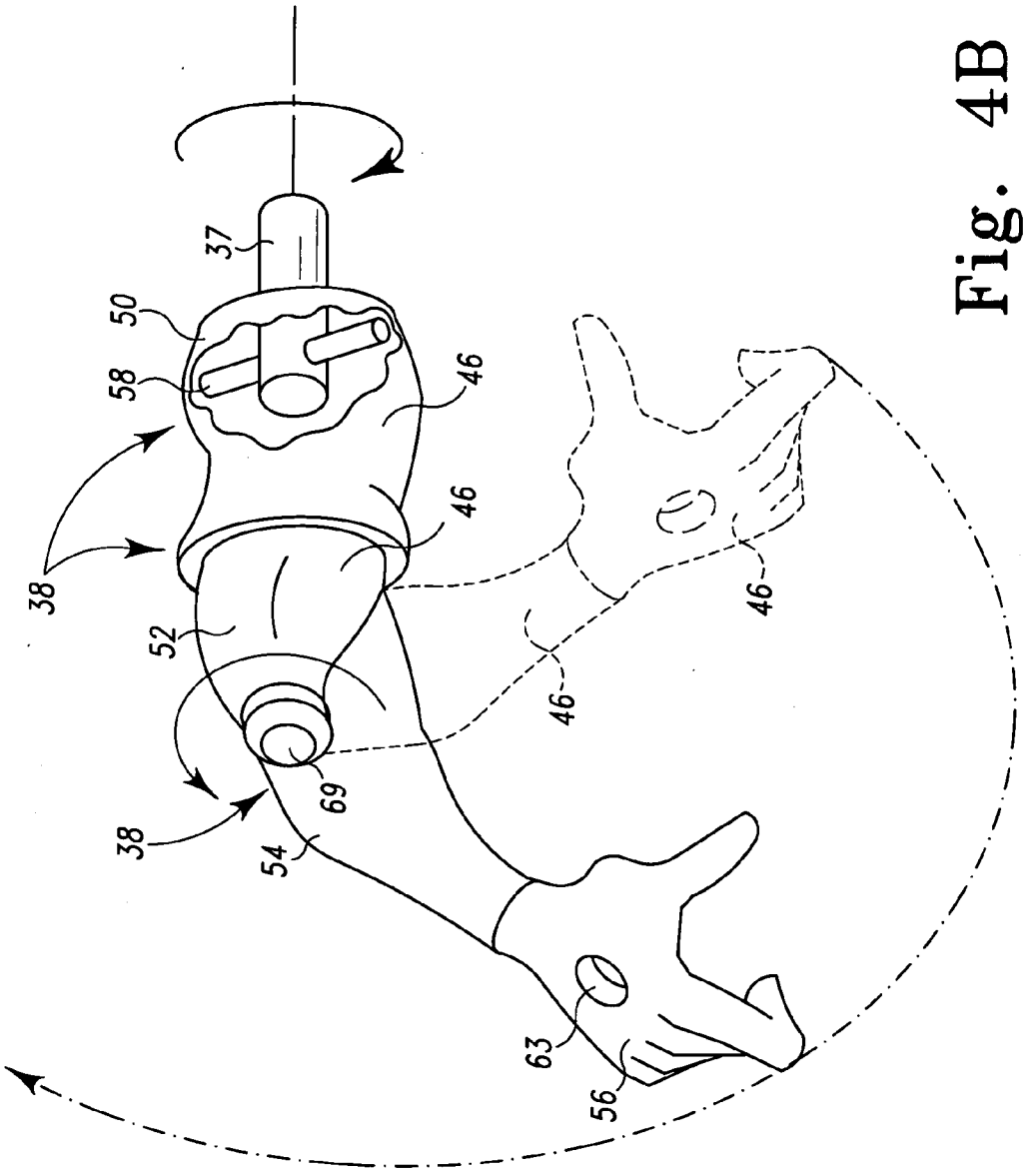


Fig. 4B

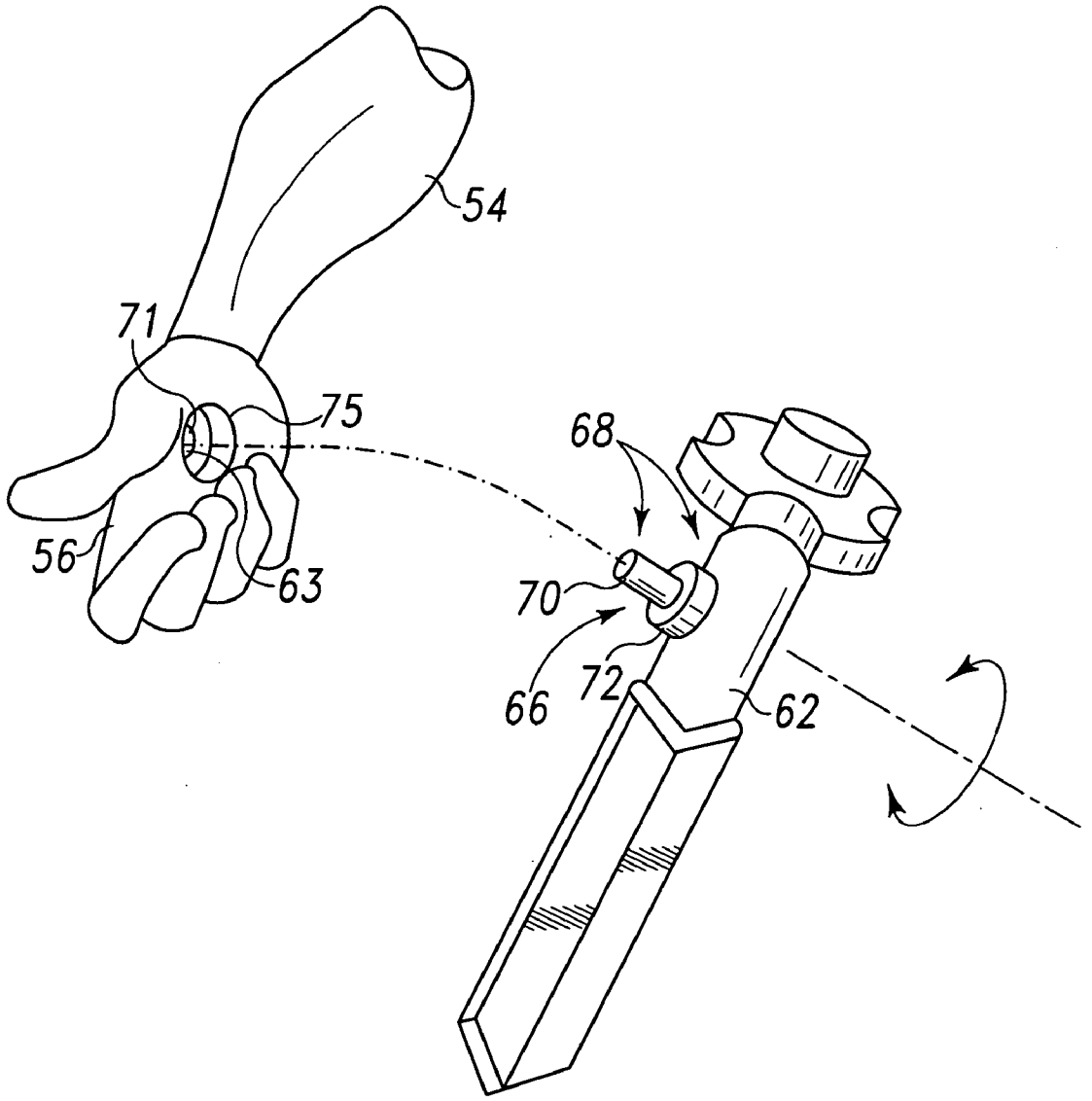


Fig. 5

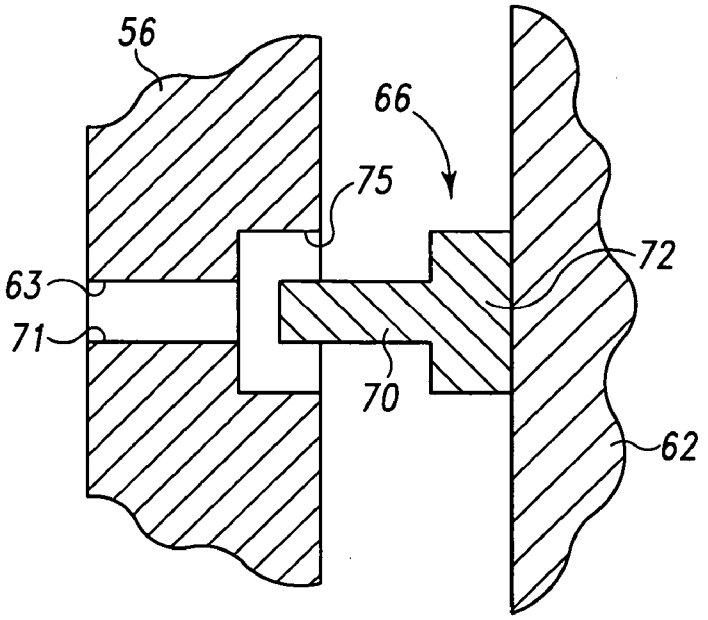


Fig. 5A

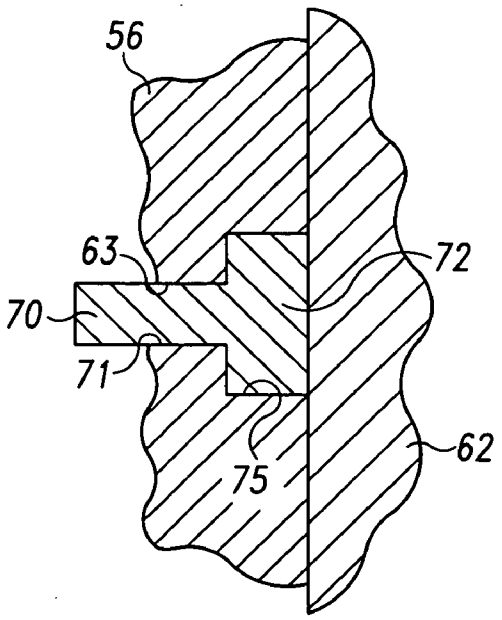


Fig. 5B

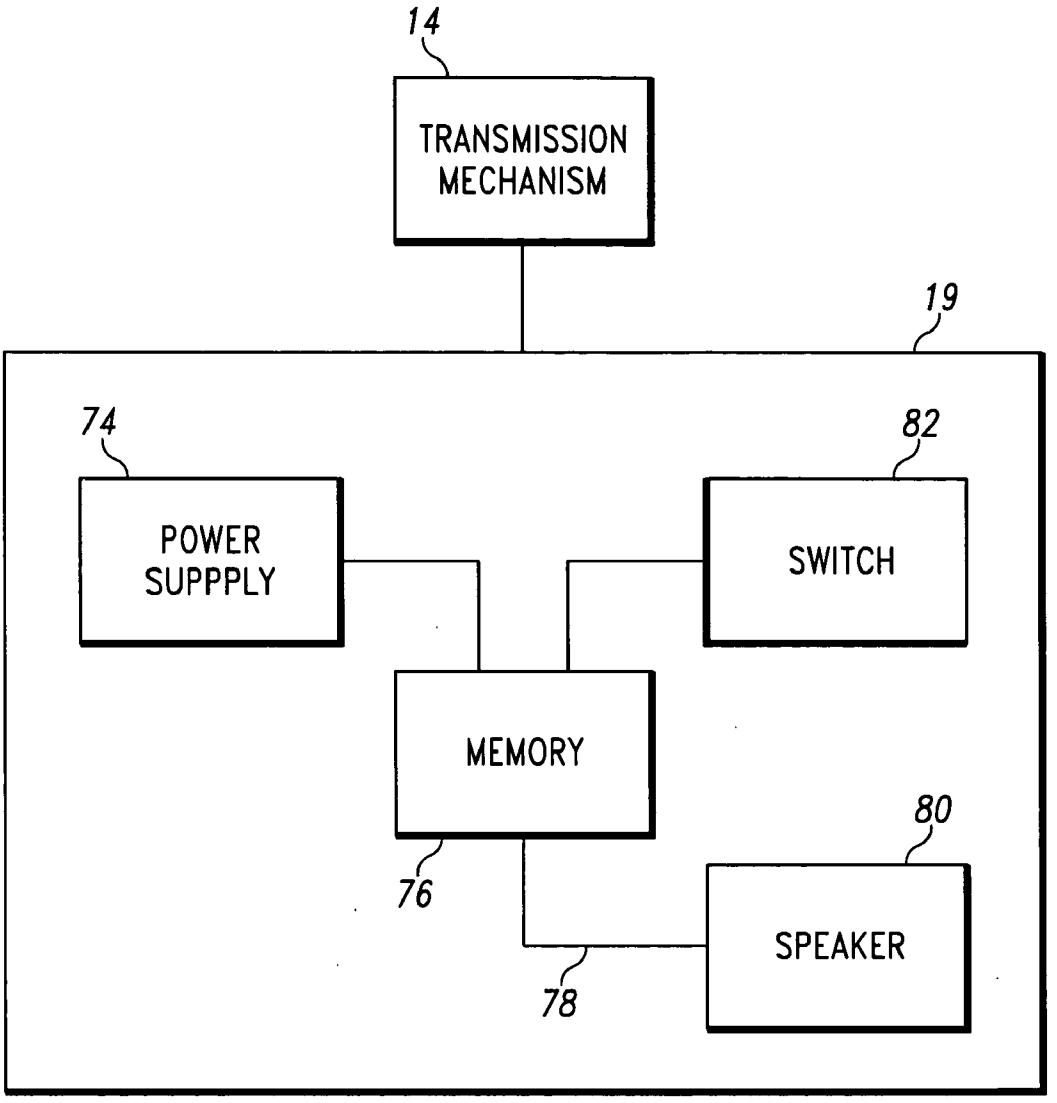

14
TRANSMISSION MECHANISM
19
74
POWER SUPPPLY
82
SWITCH
MEMORY
80
76
SPEAKER
78

Fig. 6

CUSTOMIZABLE ACTION FIGURES

RELATED APPLICATIONS

[0001] This application claims priority under 35 U.S.C. § 119(e) to U.S. Provisional Application No. 60/734,710 filed on Nov. 7, 2005, the disclosure of which is incorporated herein by reference for all purposes.

BACKGROUND

[0002] Action figures provide entertainment to persons using them. Customizable action figures may include a torso, a transmission mechanism supported in the torso, and an appendage operatively connected to the transmission mechanism. A torso may house the transmission mechanism. Action figures may have various shapes, such as the shape of a human, an animal, a robot, or a fanciful creature. A transmission mechanism may drive an appendage to move and may comprise interconnected gears and levers. The appendage may resemble an arm, leg, or other extremity, and it may have segments that move with one or more degrees of freedom.

[0003] Examples of customizable action figures are found in U.S. Pat. Nos. 1,270,781; 1,359,030; 1,456,422; 3,010,253; 3,425,155; 3,611,625; 3,648,405; 3,775,900; 3,858,353; 3,947,994; 3,955,311; 3,988,855; 4,003,158; 4,125,961; 4,135,327; 4,274,224; 4,571,209; 4,597,574; 4,601,672; 4,623,318; 4,655,725; 4,657,518; 4,669,998; 4,680,019; 4,723,932; 4,738,649; 4,790,789; 4,968,280; 4,988,324; 4,995,846; 5,044,960; 5,257,873; 5,394,766; 5,620,352; 5,727,982; 6,022,263; 6,106,359; 6,224,456; 6,296,543; 6,422,871; 6,422,916; 6,482,068; 6,494,763; 6,524,158; 6,579,143; 6,585,556; 6,601,326; 6,682,392; 6,685,530; 6,692,332; 6,817,921; 6,830,497; 6,869,331; and U.S. Published Applications 2002/0155; 2004/0198; and 2005/0020; and Foreign Patents CH 646612, CH 675081; FR 2666514; GB 2201899; JP 4288187; and JP 6023154. All of these references are incorporated herein by reference for all purposes.

SUMMARY

[0004] The present disclosure is directed to customizable action figures comprising a torso, a transmission mechanism supported in the torso, and an appendage operatively connected to the transmission mechanism. In some examples, the customizable action figures may include an upper torso rotatably connected to a lower torso. In some examples, the customizable action figures may include an appendage having a plurality of segments, with each segment configured to move relative to one or more neighboring segments. In some examples, the customizable action figures may include a set of arms, with each arm being configured to be selectively coupled to the transmission mechanism, or each arm may be configured to move differently than an other arm in the set.

BRIEF DESCRIPTION OF THE DRAWINGS

[0005] FIG. **1** is a perspective view of a customizable action figure.

[0006] FIG. **2** is a front view of the customizable action figure of FIG. **1** with a front portion of the torso removed.

[0007] FIG. **3** is a perspective view of the customizable action figure of FIG. **1** with an appendage removed.

[0008] FIG. **4**A is a front view of an appendage of the customizable action figure of FIG. **1**.

[0009] FIG. **4**B is a front view of a second appendage of the customizable action figure of FIG. **1**.

[0010] FIG. **5** is a perspective view of a hand of the customizable action figure of FIG. **1** and an object.

[0011] FIG. **5**A is a cross sectional view of a coupling member partially inserted into a socket of an object in a rotation position.

[0012] FIG. **5**B is a cross sectional view of a coupling member fully inserted into a socket of an object in a stationary position.

[0013] FIG. **6** is a schematic view of a sound mechanism of the customizable action figure.

DETAILED DESCRIPTION

[0014] A first customizable action FIG. **10** and components thereof is shown in FIG. **1**. A second customizable action FIG. **10** is shown in FIG. **2**. Similar components are given the same reference number. Customizable action FIG. **10** may include a housing or torso **12**, a transmission mechanism **14** (shown in FIG. **2**) supported in torso **12**, an actuator **16** operatively connected to transmission mechanism **14**, and one or more appendages **18** operatively connected to transmission mechanism **14**. Transmission mechanism **14** may also be drivingly connected to other appendages, such as legs, a head, wings, or other structures. In some examples, customizable action FIG. **10** includes a sound mechanism **19** (shown in FIGS. **2** and **6**) mounted in torso **12**. Legs **20** may support torso **12** from above a play surface **21**.

[0015] Torso **12** may house transmission mechanism **14** as shown in FIG. **2**. As shown in FIG. **2**, torso **12** may define a cavity **22** of sufficient size to contain transmission mechanism **14**. Various projections, apertures, and support members may be provided in torso **12** to support the various components of transmission mechanism **14**, such as base plate **25** supported on legs **20**. Torso **12** may include shoulder apertures **24** and **25**, through which transmission mechanism **14** may be connected to a right arm **26** and left arm **27**.

[0016] Transmission mechanism **14** may transmit energy applied to actuator **16** relative to torso **12** to appendages **18** through a series of gears. As shown in FIG. **2**, transmission mechanism **14** may include a waist gear **28**, a torso gear **29**, a shoulder gear **30**, and a neck gear **32**. Each of the aforementioned gears may be drivingly interconnected such that movement of one gear causes the other gears to move.

[0017] Waist gear **28** may be fixedly secured to actuator **16** and rotate about a vertical axis V**1** as actuator **16** is rotated relative to torso **12** by a user. Waist gear **28** may engage torso gear **29** having a horizontal axis of rotation H**1**. Rotation of waist gear **28** rotates torso gear **29** about a horizontal axis H**1**. Rotation of torso gear **29** causes shoulder gear **30** to rotate about a generally horizontal axis H**2**. Shoulder gear **30** may be mounted at either aperture **24** or **25** and, optionally, a different gear may be mounted in the other aperture. In some embodiments, customizable action FIG. **10** may include two shoulder gears. As shown in FIG. **2**, torso gear **29** may be a compound gear, including a first gear **31**

engaged by waist gear **28** and a larger diameter spur gear **34** configured to engage shoulder gear **30**.

[**0018**] In this example, shoulder gear **30** moves arm **27** when gear **30** is driven by torso gear **29**. Arm **26** may couple to shoulder gear **30** at shoulder aperture **24** or **25** by a drive rod **37** attached to the proximal end of arm **27** as shown in FIGS. **4**A and **4**B. Drive rod **37** is slidingly received in a channel in shoulder gear **30** with a friction fit. Shoulder gear **30** rotates drive rode **37**. As explained more fully below, drive rod **37** may engage movement mechanisms **38** drivingly connected to appendages **18**.

[**0019**] Shoulder gear **30** may also mesh with neck gear **32** causing neck gear **32** to rotate about a vertical axis V**2** when shoulder gear **30** rotates. Neck gear **32** may be rigidly attached to a head **40**. As a result, head **40** may rotate as neck gear **32** rotates. In some examples (not shown), the neck gear may be a mushroom gear with an articulation point located in the head.

[**0020**] Transmission mechanism **14** may be configured such that neck gear **32** and waist gear **28** rotate in the same direction. It is within the scope of this disclosure, however, that transmission mechanism **14** may configured such that neck gear **32** and waist gear **28** rotate in opposite directions. Further, transmission mechanism **14** and neck gear **32** may be configured such that neck gear **32** and waist gear **28** rotate at the same rate or at different rates.

[**0021**] A user may actuate actuator **16** to introduce energy into customizable action FIG. **10** by way of transmission mechanism **14**. Energy input into actuator **16** is transmitted through transmission mechanism **16** to appendage **18** to move appendage **18** relative to torso **12**.

[**0022**] Actuator **16** may take numerous forms. For example, actuator **16** may be a belt configured to slide around torso **12**, a button configured to move into and out of torso **12**, or a lever configured to pivot into and out of torso **12**. In the non-exclusive examples shown in FIGS. **1** and **3**, actuator **16** is a hip section **42** configured to rotate relative to torso **12**. In this example, legs **20** are pivotally attached to hip section **42**. To facilitate rotation, torso **12** may include a fin or other element (not shown) projecting therefrom against which a user may exert rotating force relative to actuator **16**. In one illustrative and non-exclusive example, a user may rotate lower torso **42** relative to torso **12** to rotate waist gear **28**, thus, driving transmission mechanism **14** and in turn driving movement of appendage **18**.

[**0023**] Appendage **18** may include a plurality of segments **46** and movement mechanisms **38**. Movement mechanisms **38** may include gearing configured to move one segment relative to another as explained more fully below. For example, movement mechanism **38** may rotate, bend, or extend one segment relative to another segment. Appendage **18** may include various combinations of movement mechanisms such that a first segment rotates relative to second segment, while a third segment bends relative to the second segment, etc. Different appendages may include different combinations of segments **46** and movement mechanisms **38**, such as shown in FIGS. **4**A-**4**B.

[**0024**] Sets of interchangeable appendages **18** may be provided to allow a user to interchangeably customize customizable action FIG. **10**. As shown in FIG. **3**, shoulder gear **30** may be configured to selectively receive and release appendages **18**. An aperture in shoulder gear **30** may be sized to receive drive rod **37** (shown in FIGS. **4**A-**4**B) of appendages **18**.

[**0025**] FIG. **4**A shows one example of right arm **26** configured to move in a certain manner. Right arm **26** shown in FIG. **4**A may include segments **46** including a shoulder or first segment **50**, an upper arm **52**, a forearm **54**, and a hand or third segment **56**. Upper arm **52** and forearm **54** may be rigidly connected in some examples and in such examples collectively define a second segment. Drive rod **37** may drivingly couple right arm **26** to shoulder gear **30** through shoulder aperture **25**.

[**0026**] Right arm **26** may include a first segment gear train **58** drivingly connected to first segment **50** and drive rod **37**. First segment gear train **58** may rotate first segment **50** when driven by drive rod **37**. As shown in FIG. **4**A, first segment gear train may include multiple gears, such as a main gear **59** and a transfer gear **61**. In the example depicted in FIG. **4**A, main gear **59** rotates first segment **50** and transfer gear drives a second segment gear **60**.

[**0027**] Second segment gear **60** may be drivingly connected to the second segment, such as in this example to upper arm **52**. Rotation of second segment gear **60** typically causes the second segment to rotate. As is well known in the art, the size and number of gears in first segment gear train **58** relative to second segment gear **60** may cause the second segment to rotate at the same rate or a different rate than first segment **50** as well in the same direction or in a different direction than first segment **50**.

[**0028**] In the example depicted in FIG. **4**A, right arm **26** includes a fourth segment gear train **65** drivingly connected to fourth segment **56** and to first segment gear train **58**. In some examples, such as depicted in FIG. **4**A, fourth segment gear train **65** is drivingly connected to first segment gear train **58** via a redirection mechanism **64**. Redirection mechanism **64** may account for the second segment having an angle and straight shafts being used to drivingly connect first segment gear train **58** with fourth segment gear train **65**. Redirection mechanism **64** may include gears having cooperatively angled teeth that facilitate coupled rotation of the gears at an angle.

[**0029**] Fourth segment gear train **65** may rotate fourth segment **56** relative to the second segment as main gear **59** of first segment gear train **58** rotates. Different combinations of gear sizes may be used in fourth segment gear train **65** to cause fourth segment **56** to rotate at the same rate or a different rate than first segment **50** and/or the second segment. Further, it is well known within the art that different numbers of gears may be used in fourth segment gear train **65** to cause fourth segment **56** to rotate in the same direction or a different direction than first segment **50** or the second segment.

[**0030**] FIG. **4**B shows another example of right arm **26** configured to move in a certain manner. Right arm **26** shown in FIG. **4**A may include segments **46** including a shoulder or first segment **50**, an upper arm **52**, a forearm **54**, and a hand or third segment **56**. In some examples, upper arm **52** is rigidly attached to first segment **50**. Drive rod **37** may drivingly couple right arm **26** to shoulder gear **30** through shoulder aperture **25**.

[**0031**] Right arm **26** in the example shown in FIG. **4**B may include first segment gear train **58** drivingly connected to

first segment **50** and to drive rod **37**. First segment gear train **58** in this example may rigidly attach to first segment **50** and cause first segment **50** to rotate as drive rod **37** rotates. Additionally or alternatively, first segment gear train **58** may include a plurality of gears (not pictured).

[**0032**] Forearm **54** of right arm **26** shown in FIG. **4**B may be pivotally connected to upper arm **52**. In the example shown in FIG. **4**B, upper arm **52** is rigidly attached to first segment **50**. A pin **69** may couple forearm **54** with upper arm **52** and allow forearm **54** to pivot relative to upper arm **52**. In the example shown in FIG. **4**B, forearm **54** freely pivots as first segment **50** rotates when driven by rotation of drive rod **37**.

[**0033**] In some examples, fourth segment **56** of right arm **26** shown in FIG. **4**B is rotatably connected to forearm **54**. In such an example, fourth segment **56** typically freely rotates as forearm **54** pivots relative to upper arm **52**. However, in some examples fourth segment is rigidly attached to forearm **54** and in some examples fourth segment is pivotally attached to forearm **54**.

[**0034**] Left arm **27** may be similarly configured as either right-arm **26** shown in FIG. **4**A or right arm **26** shown in FIG. **4**B. As described for right arm **26**, left arm **27** may include the same or similar segments and the same or similar gearing as shown and described for right arm **26**. As a result, in some examples left arm **27** may move the same or similarly to right arm **26** shown in FIG. **4**A and in other examples left arm **27** may move the same or similarly to right arm **26** shown in FIG. **4**B.

[**0035**] Appendage **18** may be configured to support a coupling member **66** attached to object **62** with hand or fourth segment **56** as shown in FIG. **5**. A socket **63** may be provided in hand **56** for receiving object **62**. Socket **63** may include a first socket region **71** and a second socket region **75**. Second socket region **75** typically has a different cross sectional area than first socket region **71**. In the examples shown in FIGS. **5**, **5**A, and **5**B, second socket region **75** has a larger cross sectional area than first socket region **71**.

[**0036**] Coupling member **66** may be rigidly attached to object **62** and may include different regions **68** for interfacing with different regions of socket **63**. For example, as shown in FIGS. **5**, **5**A, and **5**B, coupling member **66** may include two regions: a first coupling region **70** distal from object **62** and a second coupling region **72** proximate to object **62**. Coupling member **66** may be supported by socket **63** in two or more positions, such as a rotation position (shown in FIG. **5**A) and a stationary position (shown in FIG. **5**B).

[**0037**] In the rotation position shown in FIG. **5**A, coupling member **66**, and therefore object **62**, may rotate relative to fourth segment **56** when appendage **18** moves or when directly rotated by a user. In the rotation position shown in FIG. **5**A, first coupling region **70** is loosely supported by first socket region **71** and second socket region **75**. Second coupling member **72** may be disposed outside socket **63**. First socket region **71** may be sized to have a cross sectional area that receives first coupling region **70** with sufficient friction to retain first coupling region **70** therein, but not so much friction that rotation of first coupling region **70** is unduly restricted.

[**0038**] In the stationary position shown in FIG. **5**B, coupling member **66**, and therefore object **62**, may be held stationary relative to fourth segment **56**. In the stationary position shown in FIG. **5**B, first coupling member may extend into first socket region **71** and second coupling member **72** may extend into second socket region **75**. Second socket region **75** may be sized to have a cross sectional area that fits sufficiently tight against second coupling member **72** that rotation of second coupling member **72** is restricted.

[**0039**] Customizable action FIG. **10** may include a sound mechanism **19** for producing sounds as depicted in FIG. **6**. Sounds may include words, phrases, music, or sound effects, such as crashing or sword swooshing sounds. As is typical in the art, sound mechanism **19** may include a power supply **74**, such as a battery, a processor and memory **76** to store sound data, circuitry **78** to transfer sound data, a switch **82** to activate sound mechanism **19**, and a speaker **80** to convert sound data into sound waves. Sound mechanism **19** may be mounted in torso **12** and link to transmission mechanism **14** with via switch **82**.

[**0040**] Moving transmission mechanism **14** may activate sound mechanism **19** to produce sounds by means of switch **82**. Movement of a component, such as a projection on a rotating component (not shown), of transmission mechanism **14** may cause switch **82** to toggle sound mechanism **19** between active and inactive states. Additionally or alternatively, switch **82** may toggle sound mechanism between different active states. For example, sound mechanism **19** may be configured to produce different sounds each time transmission mechanism **14** is actuated or it may be configured to produce different sounds as actuator **16** is actuated in different directions.

[**0041**] Customizable action FIG. **10** may include legs **20** to support torso **12** from a play surface **21**. Legs **20** may be pivotally connected to torso **12** to enable the legs to simulate walking and to be positioned in different stances. The pivotal connections may comprise ball joints, a connection through transmission mechanism **14**, or any other suitable pivotal connection means.

[**0042**] As can be seen from the above description, an action figure may include a set of interconnected body segments, a transmission mechanism mounted in a housing and operatively coupled to the set of body segments, an actuator operatively connected to the transmission mechanism, wherein actuating the actuator drives the transmission mechanism, and an appendage operatively connected to the transmission mechanism and configured for selective removal from the transmission mechanism, the appendage having a plurality of adjacent segments with each segment configured to move relative to an adjacent segment when the appendage is driven by the transmission mechanism.

[**0043**] As can further be seen from the above description, an action figure may include a torso, a transmission mechanism supported in the torso, a hip section connected to the torso, rotation of the hip section relative to the torso driving the transmission mechanism, a first appendage drivingly connected to the transmission mechanism, the first appendage being configured to move in a first manner when the first appendage is driven by the transmission mechanism, and a second appendage drivingly connected to the transmission mechanism, the second appendage being configured to move in a second manner when the first appendage is driven by the transmission mechanism, wherein the first manner of motion and the second manner of motion are different.

[0044] The above description makes it further apparent that an action figure may include a housing, a transmission mechanism supported in the housing, a set of two or more arms, each arm in the set being configured to selectively couple with the transmission mechanism and including: a plurality of adjacent segments, each segment configured to move relative one or more to adjacent segments, and at least one movement mechanism mounted between adjacent segments, each movement mechanism being configured move one segment relative to an adjacent segment; wherein the movement mechanisms are configured to move the segments differently in at least two arms in the set.

[0045] While embodiments of a customizable action figure and methods of use thereof have been particularly shown and described, many variations may be made therein. This disclosure may include one or more independent or interdependent inventions directed to various combinations of features, functions, elements and/or properties, one or more of which may be defined in the following claims. Other combinations and sub-combinations of features, functions, elements and/or properties may be claimed later in this or a related application. Such variations, whether they are directed to different combinations or directed to the same combinations, whether different, broader, narrower or equal in scope, are also regarded as included within the subject matter of the present disclosure. An appreciation of the availability or significance of claims not presently claimed may not be presently realized. Accordingly, the foregoing embodiments are illustrative, and no single feature or element, or combination thereof, is essential to all possible combinations that may be claimed in this or a later application. Each claim defines an invention disclosed in the foregoing disclosure, but any one claim does not necessarily encompass all features or combinations that may be claimed.

[0046] Where the disclosure recites "a" or "a first" element or the equivalent thereof, such recitations include one or more such elements, neither requiring nor excluding two or more such elements. Further, ordinal indicators, such as first, second or third, for identified elements are used to distinguish between the elements, and do not indicate a required or limited number of such elements, and do not indicate a particular position or order of such elements unless otherwise specifically stated.

[0047] Inventions embodied in various combinations and subcombinations of features, functions, elements, and/or properties may be claimed through presentation of claims in a related application. Such claims, whether they are directed to different inventions or directed to the same invention, whether different, broader, narrower or equal in scope to the other claims, are also regarded as included within the subject matter of the present disclosure.

What is claimed is:

1. An action figure comprising:

a set of interconnected body segments;

a transmission mechanism mounted in a housing and operatively coupled to the set of body segments;

an actuator operatively connected to the transmission mechanism, wherein actuating the actuator drives the transmission mechanism; and

an appendage operatively connected to the transmission mechanism and configured for selective removal from the transmission mechanism, the appendage having a plurality of adjacent segments with each segment configured to move relative to an adjacent segment when the appendage is driven by the transmission mechanism.

2. The action figure of claim 1, wherein the housing is a torso segment and the actuator comprises a hip segment rotatably connected to the torso segment, the hip section being configured to actuate the transmission mechanism when rotated relative to the torso.

3. The action figure of claim 1, wherein the appendage includes:

a first segment proximate to the torso;

an second segment adjacent to the first segment; and

a third segment adjacent to the second segment and distal from the first segment.

4. The action figure of claim 3, wherein the appendage includes a first movement mechanism drivingly connected to the first segment and to the second segment, the first movement mechanism being configured to rotate the second segment relative to the first segment and including:

a first segment gear train drivingly connected to the transmission mechanism; and

a second segment gear drivingly connected to the first segment gear train.

5. The action figure of claim 4, wherein the first movement mechanism is configured to rotate the first segment in a first direction and is configured to rotate the second segment in a second direction opposite the first direction.

6. The action figure of claim 4, wherein the appendage includes a second movement mechanism drivingly connected to the third segment, the second movement mechanism being configured to rotate the third segment relative to the second segment and including a third segment gear drivingly connected to the first segment gear train.

7. The action figure of claim 5, wherein the appendage includes a second movement mechanism drivingly connected to the third segment, the second movement mechanism being configured to rotate the third segment relative to the second segment in the first direction and including a third segment gear drivingly connected to the first segment gear train.

8. The action figure of claim 3, wherein the appendage includes a third movement mechanism connected to the first segment, the third movement mechanism being configured to rotate the first segment relative to the housing and including a drive rod drivingly connected to the transmission mechanism.

9. The action figure of claim 8, wherein the second segment includes:

a fourth segment adjacent to the first segment,

a fifth segment pivotally connected to the fourth segment at an end distal from the first segment.

10. The action figure of claim 9, wherein the fourth segment includes a slot at an end distal from the first segment and the fifth segment includes a pin extending through the slot in the fourth segment.

11. The action figure of claim 4, wherein the third segment includes a socket for receiving an object inserted therein.

12. The action figure of claim 11, wherein the socket defines:

a first cavity having an opening with a first area; and

a second cavity adjacent to the first cavity, the second cavity having a second area which is smaller than the first area.

13. The action figure of claim 12, wherein the object includes:

a body; and

a projection having:

a first portion which is proximate to the body and which has a first cross sectional area; and

a second portion which is distal from the body and which has a second cross sectional area which is smaller than the first cross sectional area.

14. The action figure of claim 1, further comprising a sound mechanism configured to produce sound when the actuator is actuated.

15. An action figure comprising:

a torso;

a transmission mechanism supported in the torso;

a hip section connected to the torso, rotation of the hip section relative to the torso driving the transmission mechanism;

a first appendage drivingly connected to the transmission mechanism, the first appendage being configured to move in a first manner when the first appendage is driven by the transmission mechanism; and

a second appendage drivingly connected to the transmission mechanism, the second appendage being configured to move in a second manner when the first appendage is driven by the transmission mechanism;

wherein the first manner of motion and the second manner of motion are different.

16. The action figure of claim 15, wherein:

the first appendage includes:

a first segment proximate to the torso;

a second segment adjacent to the first segment; and

a third segment adjacent to the second segment and distal from the first segment; and

the second appendage includes:

a fourth segment proximate to the torso;

a fifth segment adjacent the fourth segment; and

a sixth segment adjacent to the fifth segment and distal from the fourth segment.

17. The action figure of claim 16, wherein:

a) the first appendage includes:

i) a first segment gear train drivingly connected to the first segment and to the transmission mechanism, the first segment gear train being configured to rotate the first segment relative to the torso; and

ii) a second segment gear drivingly connected to the second segment and to the first segment gear train, the second segment gear being configured to rotate the second segment relative to the first segment; and

b) the second appendage includes a drive rod drivingly connected to the fourth segment and to the transmission mechanism, the drive rod configured to rotate the fourth segment relative to the torso;

c) wherein the fifth segment is pivotally connected to the fourth segment, the fifth segment being configured to freely pivot relative to the fourth segment as the fourth segment rotates.

18. The action figure of claim 17, wherein the first appendage further comprises a third segment gear train drivingly connected the third segment and the first segment gear train, the third segment gear train being configured to rotate the third segment relative to the second segment.

19. An action figure comprising:

a housing;

a transmission mechanism supported in the housing;

an actuator operatively connected to the transmission mechanism, actuation of the actuator driving the transmission mechanism; and

a set of two or more arms, each arm in the set being configured to selectively couple with the transmission mechanism and including:

a plurality of adjacent segments, each segment configured to move relative one or more to adjacent segments, and

at least one movement mechanism mounted between adjacent segments, each movement mechanism being configured move one segment relative to an adjacent segment;

wherein the movement mechanisms are configured to move the segments differently in at least two arms in the set.

20. The action figure of claim 19, wherein a first arm in the set includes:

a first segment proximate to the housing;

a second segment adjacent to the first segment;

a third segment adjacent to the second segment and distal from the first segment;

a first movement mechanism comprising a first segment gear train drivingly connected to the first segment and to the transmission mechanism, the first segment gear train being configured to rotate the first segment relative to the housing; and

a second movement mechanism comprising a second segment gear drivingly connected to the second segment and to the first segment gear train, the second segment gear being configured to rotate the second segment relative to the first segment.

21. The action figure of claim 20, wherein a second arm in the set includes:

a fourth segment proximate to the housing;

a fifth segment pivotally connected to the fourth segment; and

a sixth segment adjacent to the fifth segment and distal from the fourth segment; and

a third movement mechanism comprising a drive rod drivingly connected to the fourth segment and to the transmission mechanism, the drive rod configured to rotate the fourth segment relative to the housing;

wherein the fifth segment is configured to freely pivot relative to the fourth segment as the fourth segment rotates.

* * * * *