CORRECTION

Correction to: Motion planning for redundant multi-bodied planar kinematic snake robots

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The online article presented the figures in black and white. The colored figures are presented here.

Fig. 1 Four-link planar nonholonomic snake robot

Fig. 2 Four-link snake with a variable body frame orientation

The online version of the original article can be found under
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Fig. 3 Flowchart of the proposed algorithm

Fig. 4 The gait designed using (17) to move solely along the x direction

Fig. 5 The four nonholonomic forces associated with gait $r_x(t)$ as a function of time t

Fig. 6 The motion of the snake under the gait $r_x(t)$

Fig. 7 Evolution of $r_\theta(t)$ as a function of time t

Fig. 8 The motion of the snake under the gait $r_\theta(t)$

Fig. 9 The four nonholonomic forces associated with the gait $r_\theta(t)$ as a function of time t

Fig. 10 The four nonholonomic forces associated with gait $r_c(t)$ as a function of time t

Fig. 11 **a** Evolution of $r_{tm}(t)$ components as a function of time. The dashed lines separate the gait into its three phases. **b** Evolution of $r_c(t)$ components as a function of time. **c** Evolution of $r_d(t)$ components as a function of time. The dashed lines separate

the gait into its three phases. **d** Snake performing the turn-and-move motion. **e** Snake performing the circular motion. **f** Snake performing the Dubins motion

Fig. 12 **a** Evolution of $r_{sin}(t)$ components as a function of time. **b** Snake traversing the sinusoidal trajectory in (25). **c** The four nonholonomic forces associated with gait $r_{sin}(t)$. **d** Evolution of

$r_{sin-param}(t)$ components as a function of time. **e** Snake traversing the sinusoidal trajectory in (28). **f** The four nonholonomic forces associated with gait $r_{sin-param}(t)$

Fig. 13 The evolution of $r_{5\text{-link}}(t)$ components along time t

Fig. 14 The trajectory due to gait $r_{5\text{-link}}(t)$

Fig. 15 The five nonholonomic forces associated with the gait $r_{5\text{-link}}(t)$ as a function of time t

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