

REFERENCES

- [1] S. Saha, Introduction to Robotics, New Delhi: Tata McGraw-Hill, 2008.
- [2] F. Fahimi, Autonomous Robots Modeling, Path Planning, and Control, Alberta: Springer, 2009.
- [3] J. G. Gomez, "Modular Robotics and Locomotion," Madrid, 2008.
- [4] S. Gibilisco, Concise Encycloedia of Robotics, McGraw-Hill, 2003.
- [5] G. S. Chirikjian, "The Kinematics of Hyper-Redundant Robot Locomotion," in *IEEE*, California, 1995.
- [6] A. A. Transeth, "Modelling and Control of Snake Robots," Trondheim, 2007.
- [7] G. S. Chirikjian and J. W. Burdick, "The Kinematics of Hyper-Redundant Robot Locomotion with Application to Grasping," in *IEEE*, California, 1991.
- [8] Nirmala, "Designing a Framework for Analyzing Mobile Robot Behaviour Using V-REP Simulator," Tangerang, 2013.
- [9] "V-rep: Create. Compose. Simulate. Any Robot," Coppelia Robotics. [Online]. [Accessed May 2014].
- [10] T. Niemuller, A. Ferrein and G. Lakemeyer, A Lua-Based Behaviour Engine for Controlling the Humanoid Robot Nao, 2009.
- [11] R. Ierusalimschy, L. H. d. Figueredo and W. Celes, The Evolution of Lua.
- [12] R. IERUSALIMSCHY, Programming in Lua, Rio de Janeiro, 2006.
- [13] R. Arkin, Behavior-Based Robotics, The MIT Press, 1998.
- [14] V. Tjondro, "Designing and Constructing and Snake Robot With Active Passive Wheel and Joint Combination," Swiss German University, Tangerang, 2014.

- [15] S. Kucuk and Z. Bingul, "Robot Kinematics: Forward and Inverse Kinematics," *Industrial Robotics: Theory, Modelling and Control*, 2006.
- [16] Y. Xu and M. C. Nechyba, "Fuzzy Inverse Kinematic Mapping," *Rule Generation, Efficiency, and Implementation*, 1993.

