AMENDMENTS TO PROOF

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CHAPTER TITLE: Locomotion Principles of 1D Topology Pitch and Pitch-Yaw-Connecting Modular Robots

Page No.	Section	Paragraph	Line No.	Delete	Add/amend
8	3.6	eq. 5	1	$\frac{2\pi\pi}{T} + \frac{2\pi\pi}{M}$	$\frac{2\pi t}{T} + \frac{2\pi k}{M}$
8	3.6	1	3	" has its own set of parameters A, k and xx"	"has its own set of parameters A, k and $\Delta\Phi$ "
7	3.5	1			The bullets have different sizes
10	4.3	1	1	"The step is the distance xx"	"The step is the distance Δx "
14	4.5	1	1	" <i>M</i> ∈3,4 "	" <i>M</i> ∈[3,4] "
16	5.4	2	1	"(15) can be rewritten as: $\Delta \Phi_V = 2 \Delta \Delta_H$ "	"(15) can be rewritten as: $\Delta \Phi_V = 2 \Delta \Phi_H$ "
19	5.7	Table 5.1	5	Entry in file 5, row 1	Should be: $\Delta \Phi_V$
19	5.7	Table 5.1	6	Entry in file 6, row 1	Should be: $\Delta \Phi_{VH}$