

# Publication Agreement

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Kinematic Invariant Parametric Snake Robot Gait Design for Enceladus Exploration

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("the article") to be published in PMLR ("the proceedings"). The parties to this Agreement are:

Jack Naish, Jacob Rodriguez, Jenny Zhang, Andrew Orekhov, Devansh Dhrafani, Howie Choset, Guglielmo Daddi, Bryson Jones, Rob Royce, Michael Paton, Masahiro Ono, Rohan Thakker

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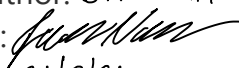
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