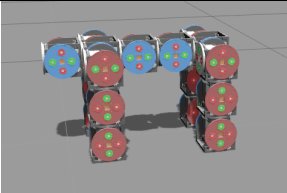
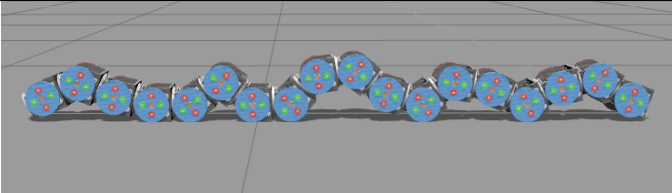
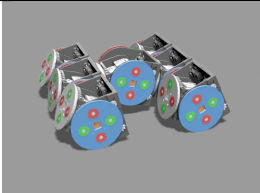
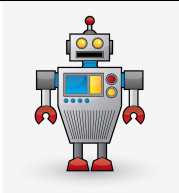


Configuration				
	WALK4	SNAKE18	CAR	DRIVER5
Components	BODY3 LEG3 $\times$ 4	SNAKE3 $\times$ 6	STEER3 DRIVER1 $\times$ 4	STEER3 DRIVER1 $\times$ 2
Behaviors	$Walk(t)$	$Slither()$	$DRIVE(v, t)$ $TURN(\theta)$	$DRIVE(v, t)$ $TURN(\theta)$