* Our robot combines the previous designes of four-flipper robots, improves the design to best suit for narrow-space navigation and combines the flipper design with sensors required for archaeological penetration missions.
* Our weight functions improve the control of fin configuration proposed with madeline.
* Description of wrench node has to be included
* U-CAT is smaller than ohter finned robots
* Add references to other types of biomimetic underwater robots and also traditional underwater robots. References can be taken from my PhD thesis.
* Define 3 groups of turtle-like vehicles
* Include the fin-force model
* Our robot is deliberately built stable in roll and pitch. Archaeologists dont care about robot doing saltos
* Sway control has to be demonstrated to differentiate from aqua
* Compare the previous robots from their application point of view
* We use model-based approach as opposed to aqua