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Tactile and Force Sensors for Dexterous Robotic Manipulation of Soft Objects

Guest Editors:

Dr. Mehdi Boukallel

CEA LIST, Ambient Intelligence and Interactive Systems Department, Sensory and Ambient Interfaces Laboratory, 91191 Palaiseau, France

Prof. Dr. Ramiro Velázquez

Facultad de Ingeniería, Universidad Panamericana, Aguascalientes 20296, Mexico

Deadline for manuscript submissions:

closed (30 December 2022)

Message from the Guest Editors

The preliminary objective of this Special Issue is to promote research contributions and position papers that go beyond the state-of-the-art to address the issue of the design and fabrication of tactile and force sensors for robotic systems dedicated to the manipulation of soft objects. Original papers describing completed and unpublished work that are not currently under review by any other journal, magazine or conference are solicited. The Special Issue encourages contributions in, among others, the following topics:

- Force and tactile sensing;
- Tactile sensor technologies;
- Distributed force sensors;
- Sensor fusion;
- Artificial skin;
- Robot tactile systems;
- Grasping and manipulation of soft objects;
- Deformable object manipulation;
- Slipping detection and strategy avoidance;
- Contact modeling;
- Object physical properties recognition.



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Special Issue



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Prof. Dr. Vittorio M. N. Passaro

Dipartimento di Ingegneria
Elettrica e dell'Informazione
(Department of Electrical and
Information Engineering),
Politecnico di Bari, Via Edoardo
Orabona n. 4, 70125 Bari, Italy

Message from the Editor-in-Chief

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Sensors Editorial Office
MDPI, Grosspeteranlage 5
4052 Basel, Switzerland

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