



Tactile Sensors for Robotic Applications

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Deadline for manuscript
submissions:

closed (30 April 2020)

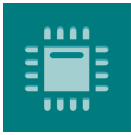
Message from the Guest Editor

In recent years, tactile sensing has become a key enabling technology to implement complex tasks by using robotic systems. For example, the successful execution of robotic grasping and manipulation tasks is strongly dependent on the knowledge of objects’ geometrical and physical characteristics, especially when objects are deformable and can change their shapes depending on their interaction with the environment. The aim of this Special Issue is to present robotic applications for which tactile sensing represents a solution that allows clear improvements for task automation.

This Special Issue invites contributions in the following topics (but is not limited to them):

- Tactile sensor technologies
- Tactile sensor modelling
- Tactile data interpretation
- Robot tactile systems
- Force and tactile sensing
- Grasping and manipulation
- Deformable object manipulation
- Contact modelling
- Dexterous manipulation
- Artificial skin
- Object features recognition
- Slipping detection and avoidance
- Physical human robot interaction
- Human machine interfaces





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Message from the Editor-in-Chief

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