Special Issue

Advances in Robot Motion and Control—In Memory of Professor Krzysztof Kozlowski

Message from the Guest Editors

This Special Issue addresses the control and trajectory tracking of different robots, including mobile, walking, and flying robots and sets of mobile robots. All these mechanical systems are described by highly nonlinear differential equations, and the geometric approach and the Lyapunov stability theory seem to be the most appropriate tools to be used to study control and trajectory tracking of these systems. It is highly interesting to know the limitations of these techniques in comparison with simple techniques such as Taylor's linearization or the first Lyapunov method. At the same time, we want to see their applications in practice; therefore, papers showing good theory with experiments are most welcome. We strongly believe that nontrivial theory supported by good experimental work may add new value and insights into the control of mechanical systems. Papers submitted to this Special Issue will be reviewed by no less than two independent experts. Based on the rigorous review process, we will be able to select the best papers to appear in the Special Issue, and we anticipate that they will be of great interest to *Applied Sciences* readers.

Guest Editors

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Deadline for manuscript submissions

closed (20 November 2022)

About the Journal

Message from the Editor-in-Chief

As the world of science becomes ever more specialized, researchers may lose themselves in the deep forest of the ever increasing number of subfields being created. This open access journal Applied Sciences has been started to link these subfields, so researchers can cut through the forest and see the surrounding, or quite distant fields and subfields to help develop his/her own research even further with the aid of this multi-dimensional network.

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