

Special Issue

Intelligent and Dynamic Control of Mobile, Aerial, and Underwater Robots

Message from the Guest Editors

This Special Issue aims to explore and showcase the latest advancements in the intelligent and dynamic control of mobile, aerial, and underwater robots, addressing the pressing need for adaptive and responsive robotic systems. This Special Issue invites contributions that delve into the intelligent and dynamic control of mobile, aerial, and underwater robots.

In this Special Issue, original research articles and reviews are welcome. Research areas may include (but are not limited to) the following:

- Real-time decision-making strategies for mobile, aerial, and underwater robots;
- Adaptive control approaches for mobile, aerial, and underwater robots;
- Machine learning approaches for robot planning and control;
- Navigation and path planning in dynamic and unstructured environments;
- Multi-robot coordination and collaboration;
- Human–robot interaction for enhanced control;
- Applications of mobile, aerial, and underwater robots.

We look forward to receiving your contributions.

Guest Editors

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Dr. Lin Zhang

Deadline for manuscript submissions

closed (15 September 2025)



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About the Journal

Message from the Editor-in-Chief

Electronics is a multidisciplinary journal designed to appeal to a diverse audience of research scientists, practitioners, and developers in academia and industry. The journal is devoted to fast publication of latest technological breakthroughs, cutting-edge developments, and timely reviews of current and emerging technologies related to the broad field of electronics. Experimental and theoretical results are published as regular peer-reviewed articles or as articles within Special Issues guestedited by leading experts in selected topics of interest.

Editor-in-Chief

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manuscripts are peer-reviewed and a first decision is provided to authors approximately 16.4 days after submission; acceptance to publication is undertaken in 2.6 days (median values for papers published in this journal in the second half of 2025).