

## Special Issue

# Advanced Grasping and Motion Control Solutions: 2nd Edition

### Message from the Guest Editors

Robotic systems are now present in all spheres of human life. Robots have shown great advantages for, and are used widely in, many controlled, simple, and repetitive applications such as grasping, pick-and-place operations, and manipulation tasks, including teleoperated systems. Applications for these types of systems have spanned the medical, industrial, manufacturing, and autonomous exploration fields. This Special Issue invites the submission of papers that present new methods, approaches, designs, concepts, and software tools for advanced robotic grasping and motion control solutions. Particular attention will be paid to solving grasping problems, modeling grippers, and robot motion control in various software environments, as well as improving the design of novel robotic solutions. Potential topics may include, but are not limited to: the design and prototyping of grippers; motion planning and control; modeling/simulation of robotic applications; robotic grasping and dexterous manipulation; human–robot interaction; the computation of robotic systems; and control systems in experiments.

### Guest Editors

Dr. Roman Mykhailyshyn

Dr. Ann Majewicz Fey

Dr. Charalampos P. Bechlioulis

Prof. Dr. Kensuke Harada

### Deadline for manuscript submissions

31 March 2026



## Robotics

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*Robotics*  
Editorial Office  
MDPI, Grosspeteranlage 5  
4052 Basel, Switzerland  
Tel: +41 61 683 77 34  
[robotics@mdpi.com](mailto:robotics@mdpi.com)

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## About the Journal

### Message from the Editor-in-Chief

It is my great pleasure to welcome you to our open access journal, *Robotics*, which is dedicated to both the foundations of artificial intelligence, bio-mechanics and mechatronics, and the real-world applications of robotic perception, cognition and actions. The 21st century is the robotics century and intelligent robots will change our lifestyle forever. Let us work together toward the realization of intelligent robots step by step. It is great fun to create intelligent robots and imagine their practical applications. *Robotics* is now ready to serve you in the long journey towards such a goal.

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### Editor-in-Chief

Prof. Dr. Marco Ceccarelli

LARM2: Laboratory of Robot Mechatronics, Department of Industrial Engineering, University of Rome Tor Vergata, Via del Politecnico 1, 00133 Roma, Italy

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