

## Special Issue

# State Estimation for Mobile Robotics

### Message from the Guest Editors

Robotic literature is often focused on advanced control strategies, and state estimation is often an afterthought when moving from simulation to experiment. This leads to many robotic platforms not being able to achieve their full potential. Typically, for a mobile robot, the state will include the position and velocity. Furthermore, it can include information such as joint forces and torques, center of masses, or even 3D maps. State estimation is the problem of estimating this state from sensor data and models. For most state estimation problems, there are no sensors that can directly measure them, and the sensors that can partially measure them are corrupted with noise. This Special Issue addresses all types of state estimation for mobile robotics.

Dr. Giuseppe Loianno

Dr. Guoquan Huang

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### Guest Editors

Dr. Geoff Fink

Dr. Claudio Semini

Dr. Giuseppe Loianno

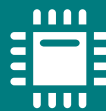
Dr. Laurent Kneip

Dr. Guoquan Huang

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### Deadline for manuscript submissions

closed (31 May 2022)



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

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### Editor-in-Chief

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

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