Special Issue

Tactile and Force Sensors for Dexterous Robotic Manipulation of Soft Objects

Message from the Guest Editors

The preliminary objective of this Special Issue is to promote research contributions and position papers that go beyond the state-of-the-art to address the issue of the design and fabrication of tactile and force sensors for robotic systems dedicated to the manipulation of soft objects. Original papers describing completed and unpublished work that are not currently under review by any other journal, magazine or conference are solicited. The Special Issue encourages contributions in, among others, the following topics: - Force and tactile sensing;
- Tactile sensor technologies;
- Distributed force sensors;
- Sensor fusion;
- Artificial skin;
- Robot tactile systems;
- Grasping and manipulation of soft objects;
- Deformable object manipulation;
- Slipping detection and strategy avoidance;
- Contact modeling;
- Object physical properties recognition.

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Message from the Editor-in-Chief

Sensors is a leading journal devoted to fast publication of the latest achievements of technological developments and scientific research in the huge area of physical, chemical and biochemical sensors, including remote sensing and sensor networks. Both experimental and theoretical papers are published, including all aspects of sensor design, technology, proof of concept and application. Sensors organizes Special Issues devoted to specific sensing areas and applications each year.

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