

Special Issue

Tactile Sensors for Robotic Applications

Message from the Guest Editor

In recent years, tactile sensing has become a key enabling technology to implement complex tasks by using robotic systems. For example, the successful execution of robotic grasping and manipulation tasks is strongly dependent on the knowledge of objects' geometrical and physical characteristics, especially when objects are deformable and can change their shapes depending on their interaction with the environment. The aim of this Special Issue is to present robotic applications for which tactile sensing represents a solution that allows clear improvements for task automation. This Special Issue invites contributions in the following topics (but is not limited to them):

- Tactile sensor technologies
- Tactile sensor modelling
- Tactile data interpretation
- Robot tactile systems
- Force and tactile sensing
- Grasping and manipulation
- Deformable object manipulation
- Contact modelling
- Dexterous manipulation
- Artificial skin
- Object features recognition
- Slipping detection and avoidance
- Physical human robot interaction
- Human machine interfaces

Guest Editor

Dr. Salvatore Pirozzi

Dipartimento di Ingegneria, Università degli Studi della Campania "Luigi Vanvitelli", Via Roma, 29, 81031 Aversa, CE, Italy

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Sensors
Editorial Office
MDPI, Grosspeteranlage 5
4052 Basel, Switzerland
Tel: +41 61 683 77 34
sensors@mdpi.com

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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.

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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