

# ROBOTICA

## Instructions for contributors

*Robotica* aims to be an outlet for publication of original papers of the highest quality in the field of Robotics and closely related areas. This includes: novel robotic mechanism and actuator design; robot kinematics, dynamics and control; computer vision; sensor fusion; teleoperation and haptic interfaces; robot motion planning; and artificial intelligence. In addition, papers that apply techniques from Robotics to other fields are also welcome. Examples include dynamics and control models applied to biological systems, the description of implementations of robots in factories, service and agricultural settings, and general mechatronic design. Works may be theoretical, computational or experimental, or some combination. Both short papers (rapid communications), and longer archival papers are welcome. Proposals for special issues on topics of current interest are welcome, and can be submitted via email to the editor.

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## **References**

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P.W. Anderson, "More is different" *Science* 177, 393-399 (1972);

C.V. Negoita, *Fuzzy Systems* (Abacus Press. Tunbridge Wells, UK, 1980).

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### **Online Supplementary Material**

Relevant material which is not suitable for inclusion in the main article body, such as computer code, large tables, additional figures or appendices, can be uploaded as supplementary material. If the article is accepted for publication in *Robotica*, these materials will be hosted online alongside the final published article. Note that:

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