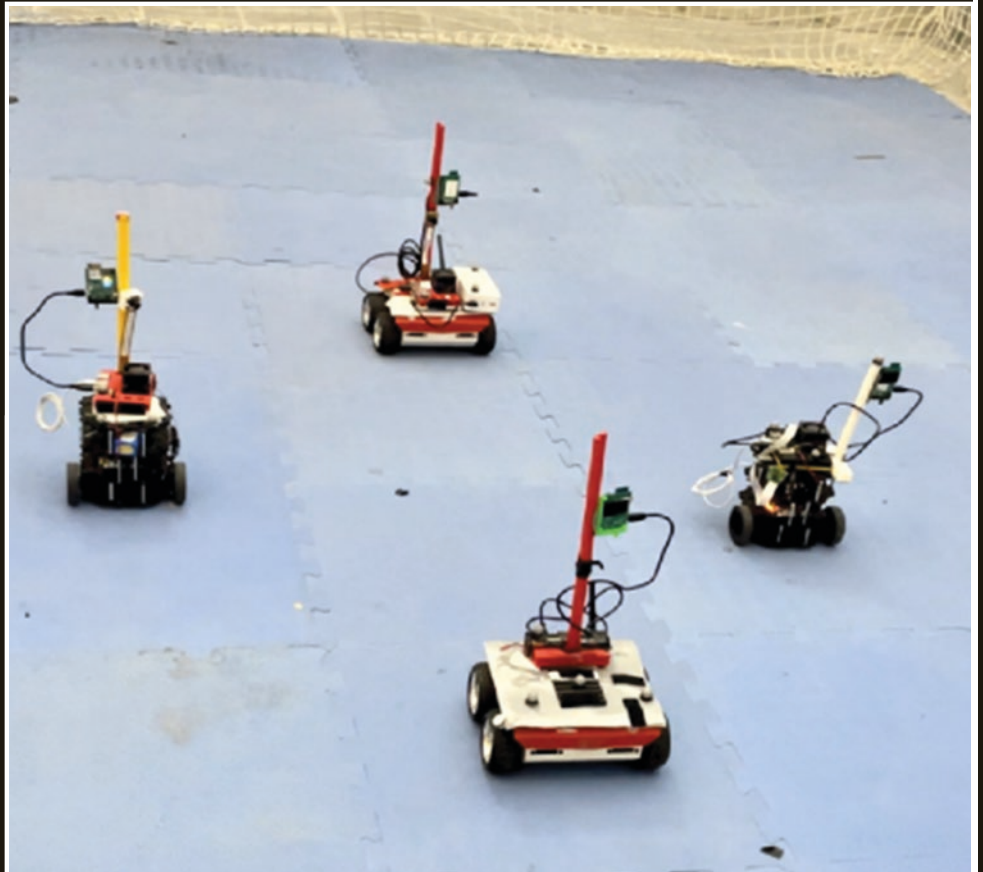


Volume **43** Part **4**

ROBOTICA



[cambridge.org/rob](https://www.cambridge.org/rob)



CAMBRIDGE
UNIVERSITY PRESS

ISSN 0263-5747

ROBOTICA

An IFAC-Affiliated Journal, and an
Official Journal of the IFR.

International Journal of Information, Education and Research
in Robotics and Artificial Intelligence

EDITORS

Professor Jian S. Dai, *Centre for Robotics Research, King's College London, United Kingdom*

E-mail: jian.dai@kcl.ac.uk

Professor Giuseppe Carbone, *Department of Mechanical, Energy and Management Engineering, University of Calabria, Rende, Italy*

E-mail: giuseppe.carbone@unical.it

EDITORIAL BOARD

See the following link for up to date editorial board details: <https://www.cambridge.org/core/journals/robotica/information/about-this-journal/editorial-board>

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.

COPYING

This journal is registered with the Copyright Clearance Center, 222 Rosewood Drive, Danvers, MA 01923. Organizations in the USA who

are also registered with CCC may therefore copy material (beyond the limits permitted by sections 107 and 108 of US copyright law) subject to payment to CCC of the per-copy fee of \$16.00. This consent does not extend to multiple copying for promotional or commercial purposes. Code 0263-5747/2021/\$16.00.

ISI Tear Sheet Service, 3501 Market Street, Philadelphia, Pennsylvania 19104, USA, is authorised to supply single copies of separate articles for private use only.

Organizations authorized by the Copyright Licensing Agency may also copy material subject to the usual conditions.

For all other use, permission should be sought from Cambridge or the American Branch of Cambridge University Press.

Information on *Robotica* and all other Cambridge journals can be accessed via [cambridge.org/core](https://www.cambridge.org/core).

Cover Image: Figure 18c. Kabore, K.M. and Güler, S. (2025) 'Efficient relative localization and coordination system for unmanned ground vehicle formations under directed graph structure', *Robotica*, pp. 1–23. doi:10.1017/S026357472500013X.