

# *Journal of Robotics and Mechatronics*

## **Instructions to Authors**

The *Journal of Robotics and Mechatronics* (JRM), founded in 1989, is the world's first journal devoted to this field of study. Since its first issue, the JRM has published over 2,500 works exclusively on robotics and mechatronics. A diverse range of articles that are essential to the journal's global readership are published 6 times a year and are freely available online.

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### **AIMS & SCOPE**

JRM is a peer-reviewed Open Access journal in fields such as robotics, mechatronics, automation, system integration and human-related technology. Its editorial board includes well-established researchers and engineers in the field from the world over.

The scope of the journal includes any and all topics on robotics and mechatronics. As a key technology in robotics and mechatronics, it includes actuator design, motion control, sensor design, sensor fusion, sensor networks, robot vision, audition, mechanism design, robot kinematics and dynamics, mobile robot, path planning, navigation, SLAM, robot hand, manipulator, nano/micro robot, humanoid, service and home robots, universal design, middleware, human-robot interaction, human interface, networked robotics, telerobotics, ubiquitous robot, learning, and intelligence.

The scope also includes, but is not limited to, applications of robotics and automation, and system integrations in the fields of manufacturing, construction, underwater, space, agriculture, sustainability, energy conservation, ecology, rescue, hazardous environments, safety and security, dependability, medical, and welfare.

### **MANUSCRIPT TYPES**

The journal welcomes 6 manuscript types, all of which are peer reviewed.

#### **Papers**

Papers should present new findings and original concepts with complete discussion. They should average be 8 printed pages.

#### **Development Reports**

Development Reports describe technical findings that will actually be useful in practical applications. They should normally be 6 printed pages.

## **Letters**

Letters describe a single result, experiment, or technique of general interest for which a letter treatment is appropriate. They should normally be 2 printed pages.

## **Junior Letters**

Junior Letters are a technical report or a concept proposal, described by students who are under 20 years old. They should normally be 2 printed pages.

## **Discussions**

Discussions are a separate class of short manuscripts. Appropriate items include (but are not limited to) rebuttals and/or counter examples of previously published papers.

## **Reviews**

Reviews summarize a specific subject by introducing the author's own opinions concerning recent progress and future prospects to give a balanced assessment.

## **JOURNAL & ETHICS POLICIES**

The *Journal of Robotics and Mechatronics* strives for the highest standards in scholarly publishing.

Before submitting a manuscript to the journal, authors must ensure that they have read and are compliant with the journal's policies. The journal reserves the right to reject without review any manuscript that the Editor-in-Chief believes may not comply with these policies.

The responsibilities of the journal's authors, editors, reviewers and publisher regarding research and publication ethics are described in this section.

The *Journal of Robotics and Mechatronics* welcomes manuscript submissions from authors who are anywhere in the world.

Authors of submitted manuscripts warrant that they have read and approved the manuscript, have agreed to its submission, and have the right to publish their work, and that the work contains no slanderous or libelous material. Authors alone are responsible for all statements in their manuscripts.

### **Journal abbreviation**

The journal title is *Journal of Robotics and Mechatronics*. It should be abbreviated as "*J. Robot. Mechatron.*"

### **Authorship**

The corresponding author warrants that all authors have seen and approved the author list and order. Changes to the author list after manuscript submission – such as the insertion or removal of author names, or a rearrangement of author order – must be approved by all authors and the relevant Associate Editor or Editor-in-Chief.

Authors are encouraged to consider the Council of Science Editors (CSE) principles governing authorship. According to the CSE guidelines, authors have made substantial contributions to the work; have agreed to be held accountable for their own contributions to

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The journal encourages authors to grant reasonable requests from colleagues to share any data, materials and experimental protocols described in their manuscript.

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The time required for peer review depends on many factors, including the time to locate reviewers and the timeliness of their responses. The median time from submission to first decision is 90 days. As an aside, the median time from acceptance to publication is 60 days.

When a manuscript is submitted to the journal, the Editor-in-Chief performs initial screening. Manuscripts that do not fit the journal's scope or are not deemed suitable for publication are rejected without review. The remaining manuscripts are assigned to an Associate Editor who assigns 2 reviewers to assess each manuscript. The Editor-in-Chief may manage the peer review process in some circumstances. The deadline for submission of the reviewers' reports varies by article type.

Once the reviewers' reports have been received, the Associate Editor makes the first decision: acceptance; conditional acceptance with minor revisions; revision and resubmission due to the need for major revisions; or reject. Decisions are made on the totality of the information

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#### **i) Originality and novelty**

Each submitted manuscript is evaluated for novelty and originality in the relevant field of research. Associate Editors assess if the manuscript presents original scholarship and data and draws valid and significant conclusions.

#### **ii) Usefulness**

An objective of the *Journal of Robotics and Mechatronics* is to introduce technologies that originate in academia to industry. Associate Editors therefore make judgements about a manuscript's contribution to technological development; potential and possible applications; and implications for broader societal benefit. In addition, they determine if the authors have attended to these issues in the best way possible.

iii) Academic rigor

Associate Editors judge the scientific or academic rigor of each submitted manuscript. The *Journal of Robotics and Mechatronics* only publishes manuscripts that are within the subject scope of the journal, demonstrably rigorous, and within academic norms, and that make valid and defensible conclusions.

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Manuscripts may be submitted in Japanese, which are translated by Fuji Technology Press Ltd., at the authors' expense, and undergo full peer review.

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Manuscripts should be prepared in LaTeX (preferred) or Microsoft Word based on the template file available at the journal's website.

Each article should consist of: Title, Authors' full names, Affiliations, Abstract, Keywords, Main text, References, and Figures/Tables.

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The title should describe the content of the article concisely and clearly to facilitate searching by third-party services. Do not use the same main title with numbered minor titles, even for a series of papers by the same authors. Do not use abbreviations in the title, except those used generally in related fields.

### *Authors*

Provide the full names of the author(s).

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Provide the full names and addresses of institutions (including laboratory, department, institute and/or university, city, state and country). When authors belong to more than one institution, their respective addresses should be indicated by superscript asterisks.

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A maximum of five keywords should be provided.

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### *Introduction*

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### *Acknowledgments*

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### **References:**

#### <Journal article>

- [1] T. Arai et al., “Development of a Direct-Drive Human-like Manipulator,” *J. Robotics Society of Japan*, Vol.5, No.1, pp. 27-35, 1985.
- [2] H. Yang, T. Takaki, and I. Ishii, “Simultaneous Dynamics-Based Visual Inspection Using Modal Parameter Estimation,” *J. Robot. Mechatron.*, Vol.23, No.1, pp. 180-195, 2011.

#### <Journal article with DOI>

- [3] O. Schneider, K. MacLean, C. Swindells, and K. Booth, “Haptic experience design: What hapticians do and where they need help,” *Int. J. of Human-Computer Studies*, Vol.107, pp. 5-21, doi: 10.1016/j.ijhcs.2017.04.004, 2017.

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- [4] T. Mouri and H. Kawasaki, “A novel anthropomorphic robot hand and its master slave system,” M. Hackel (Eds.), “*Humanoid Robots, Human-like Machines*,” I-Tech Education and Publishing, pp. 29-42, 2007.

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- [5] Rumelhart, McClelland and the PDP Research Group, “*Parallel Distributed Processing*,” The MIT Press, 1988.
- [6] M. Wisse and R. Q. v. d. Linde, “*Delft pneumatic bipeds*,” Springer-Verlag Berlin Heidelberg, 2007.

#### <Conference paper>

- [7] J. Furusho et al., “A Performance Evaluation Method of a Passive-Type Force Display and Rehabilitation System with Redundant Brakes,” *Proc. IEEE Int. Conf. on Rehabil. Robotics*, pp. 950-955, doi: 10.1109/ICORR.2009.5209504, 2009.
- [8] T. Yamada and T. Morimatsu, “Remarks on RBF Controller Induced from Neural Network Controller,” *Proc. of the 34th SICE Annual Conf.*, pp. 725-726, 1996.

#### <Patent>

- [9] “Three Dimension Motor,” Japanese Patent 1946377, 1985.
- [10] J. A. Norling, “Anaglyph stereoscopy,” U.S. Patent US2135197A, 1937.

### **Supporting Online Materials:**

<Website>

- [a] Department of Information and Tourism, Taipei City Government, Survey of tourist population by Scenic spots, <https://www.travel.taipei/zh-tw/statistical-bulletin/number-of-visitors> [Accessed June 6, 2019]
- [b] IES Virtual Environment, “Egress: Simulex User Guide,” 2014, [http://www.iesve.com/content/downloadasset\\_5633](http://www.iesve.com/content/downloadasset_5633) [Accessed August 1, 2018]

### *Tables*

A title and caption must be provided above each table. The caption should be brief, but informative, complete and clear.

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A title and caption must be provided below each figure. Figure captions should include enough experimental or other detail to make the figures easily interpretable; however, avoid duplicating detail from the Materials and Methods.

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