

CALL FOR PAPERS

Special Section on Autonomous Decision and Cooperative Control of UAV Swarms

UAV swarm intelligence technology is a research hotspot and has broad application prospects. Autonomous decision-making and cooperative control are the key technologies to realize swarm intelligence. Autonomous decision-making is an important embodiment of UAV swarm intelligence. Cooperative control is the key factor to determine the success or failure of swarm tasks. The purpose of this special section is to discuss the technical system of swarm autonomous decision-making and the theory and method of collaborative control.

Scope of Topics

This special section invites both review articles and original contributions on the theory and method of autonomous decision-making and collaborative control for unmanned system swarms. The topics of interest include, but are not limited to

- Overviews of autonomous decision-making, cooperative control and mission planning of unmanned system swarms
- Mathematical modeling of autonomous decision-making and cooperative control for unmanned system swarms
- Autonomous decision-making framework of unmanned system swarms
- Autonomous decision theory and algorithm for unmanned system swarms
- Collaborative control theory and algorithm for unmanned system swarms
- Theory and algorithm of intelligent mission planning for unmanned system swarms
- Theory and method for swarms antagonism game
- Simulation and test technology for unmanned system swarms

Important Dates

Manuscript Due

September 30, 2022

Final Review Notification

November 30, 2022

Possible Publication

March 31, 2023

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Submission

Authors should prepare papers according to the format requirements of Journal of Systems Engineering and Electronics, with reference to the Guide for Authors given at <http://www.jseepub.com>, and submit the Word version of the complete manuscript through the online submission system. When submitting the paper, the title format should be "Title (Special Section on **Autonomous Decision and Cooperative Control of UAV swarms**)".

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