

# Nikos G Tsagarakis

## List of Publications by Year in descending order

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Version: 2024-02-01

199  
papers

4,439  
citations

236925

25  
h-index

243625

44  
g-index

199  
all docs

199  
docs citations

199  
times ranked

2741  
citing authors

#	ARTICLE	IF	CITATIONS
1	Tele-impedance: Teleoperation with impedance regulation using a body-machine interface. International Journal of Robotics Research, 2012, 31, 1642-1656.	8.5	211
2	COMpliant huMANoid COMAN: Optimal joint stiffness tuning for modal frequency control. , 2013, , .		172
3	A Novel Intrinsically Energy Efficient Actuator With Adjustable Stiffness (AwAS). IEEE/ASME Transactions on Mechatronics, 2013, 18, 355-365.	5.8	169
4	A New Actuator With Adjustable Stiffness Based on a Variable Ratio Lever Mechanism. IEEE/ASME Transactions on Mechatronics, 2014, 19, 55-63.	5.8	143
5	AwAS-II: A new Actuator with Adjustable Stiffness based on the novel principle of adaptable pivot point and variable lever ratio. , 2011, , .		138
6	A new variable stiffness actuator (CompAct-VSA): Design and modelling. , 2011, , .		133
7	Detecting object affordances with Convolutional Neural Networks. , 2016, , .		120
8	CENTAURO: A Hybrid Locomotion and High Power Resilient Manipulation Platform. IEEE Robotics and Automation Letters, 2019, 4, 1595-1602.	5.1	120
9	Robot adaptation to human physical fatigue in human-robot co-manipulation. Autonomous Robots, 2018, 42, 1011-1021.	4.8	105
10	Object-based affordances detection with Convolutional Neural Networks and dense Conditional Random Fields. , 2017, , .		94
11	Anticipatory Robot Assistance for the Prevention of Human Static Joint Overloading in Human-Robot Collaboration. IEEE Robotics and Automation Letters, 2018, 3, 68-75.	5.1	85
12	THE DESIGN OF THE iCub HUMANOID ROBOT. International Journal of Humanoid Robotics, 2012, 09, 1250027.	1.1	81
13	On the Sensor Design of Torque Controlled Actuators: A Comparison Study of Strain Gauge and Encoder-Based Principles. IEEE Robotics and Automation Letters, 2017, 2, 1186-1194.	5.1	62
14	An Overview on Principles for Energy Efficient Robot Locomotion. Frontiers in Robotics and AI, 2018, 5, 129.	3.2	60
15	Design and Evaluation of a Wearable Skin Stretch Device for Haptic Guidance. IEEE Robotics and Automation Letters, 2018, 3, 524-531.	5.1	59
16	XBotCore: A Real-Time Cross-Robot Software Platform. , 2017, , .		57
17	Flexible Disaster Response of Tomorrow: Final Presentation and Evaluation of the CENTAURO System. IEEE Robotics and Automation Magazine, 2019, 26, 59-72.	2.0	49
18	Remote mobile manipulation with the centauro robot: Full-body telepresence and autonomous operator assistance. Journal of Field Robotics, 2020, 37, 889-919.	6.0	48

#	ARTICLE	IF	CITATIONS
19	OpenSoT: A whole-body control library for the compliant humanoid robot COMAN. , 2015, , .		47
20	Reduced-complexity representation of the human arm active endpoint stiffness for supervisory control of remote manipulation. International Journal of Robotics Research, 2018, 37, 155-167.	8.5	47
21	Teleoperation in cluttered environments using wearable haptic feedback. , 2017, , .		46
22	A passivity based admittance control for stabilizing the compliant humanoid COMAN. , 2012, , .		45
23	On-line estimation of variable stiffness in flexible robot joints. International Journal of Robotics Research, 2012, 31, 1556-1577.	8.5	43
24	Tele-Impedance based stiffness and motion augmentation for a knee exoskeleton device. , 2013, , .		43
25	Dynamic and Reactive Walking for Humanoid Robots Based on Foot Placement Control. International Journal of Humanoid Robotics, 2016, 13, 1550041.	1.1	43
26	Development and Control of a Compliant Asymmetric Antagonistic Actuator for Energy Efficient Mobility. IEEE/ASME Transactions on Mechatronics, 2016, 21, 1080-1091.	5.8	43
27	Towards multi-modal intention interfaces for human-robot co-manipulation. , 2016, , .		42
28	Robot control for dummies: Insights and examples using OpenSoT. , 2017, , .		42
29	YAW MOMENT COMPENSATION FOR BIPEDAL ROBOTS VIA INTRINSIC ANGULAR MOMENTUM CONSTRAINT. International Journal of Humanoid Robotics, 2012, 09, 1250033.	1.1	40
30	Design of a wearable skin stretch cutaneous device for the upper limb. , 2016, , .		40
31	Smart Collaborative Systems for Enabling Flexible and Ergonomic Work Practices [Industry Activities]. IEEE Robotics and Automation Magazine, 2020, 27, 169-176.	2.0	40
32	Online regeneration of bipedal walking gait pattern optimizing footstep placement and timing. , 2015, , .		39
33	Design, modeling and control of a series elastic actuator for an assistive knee exoskeleton. , 2012, , .		38
34	Comparison of various active impedance control approaches, modeling, implementation, passivity, stability and trade-offs. , 2012, , .		38
35	Overview of Gait Synthesis for the Humanoid COMAN. Journal of Bionic Engineering, 2017, 14, 15-25.	5.0	38
36	Choosing Poses for Force and Stiffness Control. IEEE Transactions on Robotics, 2017, 33, 1483-1490.	10.3	37

#	ARTICLE	IF	CITATIONS
37	Development of a human size and strength compliant bi-manual platform for realistic heavy manipulation tasks. , 2017, , .		37
38	CartesI/O: A ROS Based Real-Time Capable Cartesian Control Framework. , 2019, , .		37
39	Adaptive-Robust Control of a Class of EL Systems With Parametric Variations Using Artificially Delayed Input and Position Feedback. IEEE Transactions on Control Systems Technology, 2019, 27, 603-615.	5.2	36
40	Exploiting natural dynamics for energy minimization using an Actuator with Adjustable Stiffness (AwAS). , 2011, , .		35
41	Development of a dynamic simulator for a compliant humanoid robot based on a symbolic multibody approach. , 2013, , .		34
42	On the role of robot configuration in Cartesian stiffness control. , 2015, , .		34
43	Stabilization of bipedal walking based on compliance control. Autonomous Robots, 2016, 40, 1041-1057.	4.8	34
44	On the Stiffness Selection for Torque-Controlled Series-Elastic Actuators. IEEE Robotics and Automation Letters, 2017, 2, 2255-2262.	5.1	34
45	Analysis and Development of a Semiactive Damper for Compliant Actuation Systems. IEEE/ASME Transactions on Mechatronics, 2013, 18, 744-753.	5.8	33
46	A reduced-complexity description of arm endpoint stiffness with applications to teleimpedance control. , 2015, , .		32
47	iT-Knee: An exoskeleton with ideal torque transmission interface for ergonomic power augmentation. , 2016, , .		32
48	Translating Videos to Commands for Robotic Manipulation with Deep Recurrent Neural Networks. , 2018, , .		32
49	Walking pattern generation for a humanoid robot with compliant joints. Autonomous Robots, 2013, 35, 1-14.	4.8	30
50	Efficient self-collision avoidance based on focus of interest for humanoid robots. , 2015, , .		28
51	A human-like walking for the COmpliant huMANoid COMAN based on CoM trajectory reconstruction from kinematic Motion Primitives. , 2011, , .		27
52	Stabilization for the compliant humanoid robot COMAN exploiting intrinsic and controlled compliance. , 2012, , .		27
53	Online Model Based Estimation of Complete Joint Stiffness of Human Arm. IEEE Robotics and Automation Letters, 2018, 3, 84-91.	5.1	27
54	Multi-Contact Heavy Object Pushing With a Centaur-Type Humanoid Robot: Planning and Control for a Real Demonstrator. IEEE Robotics and Automation Letters, 2020, 5, 859-866.	5.1	27

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55	A compact model for the compliant humanoid robot COMAN. , 2012, , .		26
56	Bi-Manual Articulated Robot Teleoperation using an External RGB-D Range Sensor. , 2018, , .		24
57	Multi-Priority Cartesian Impedance Control Based on Quadratic Programming Optimization. , 2018, , .		24
58	An attractor-based Whole-Body Motion Control (WBMC) system for humanoid robots. , 2013, , .		23
59	Design Optimisation and Control of Compliant Actuation Arrangements in Articulated Robots for Improved Energy Efficiency. IEEE Robotics and Automation Letters, 2016, 1, 1110-1117.	5.1	23
60	The XBot Real-Time Software Framework for Robotics: From the Developer to the User Perspective. IEEE Robotics and Automation Magazine, 2020, 27, 133-143.	2.0	23
61	Water/air performance analysis of a fluidic muscle. , 2010, , .		22
62	Kinematic analysis and design considerations for optimal base frame arrangement of humanoid shoulders. , 2015, , .		22
63	Grasp Stiffness Control in Robotic Hands Through Coordinated Optimization of Pose and Joint Stiffness. IEEE Robotics and Automation Letters, 2018, 3, 3952-3959.	5.1	22
64	An efficient leg with series-parallel and biarticular compliant actuation: design optimization, modeling, and control of the eLeg. International Journal of Robotics Research, 2021, 40, 37-54.	8.5	21
65	Stiffness Design for a Spatial Three Degrees of Freedom Serial Compliant Manipulator Based on Impact Configuration Decomposition. Journal of Mechanisms and Robotics, 2013, 5, .	2.2	20
66	Reflex control of the Pisa/IIT SoftHand during object slippage. , 2016, , .		20
67	The mechatronic design of the new legs of the iCub robot. , 2012, , .		19
68	Compliance control for stabilizing the humanoid on the changing slope based on terrain inclination estimation. Autonomous Robots, 2016, 40, 955-971.	4.8	19
69	Footstep Planning in Rough Terrain for Bipedal Robots Using Curved Contact Patches. , 2018, , .		19
70	Compliant joint modification and real-time dynamic walking implementation on bipedal robot cCub. , 2011, , .		18
71	A decoupled impedance observer for a variable stiffness robot. , 2011, , .		18
72	A Variable Damping module for Variable Impedance Actuation. , 2012, , .		18

#	ARTICLE	IF	CITATIONS
73	Walking in the resonance with the COMAN robot with trajectories based on human kinematic motion primitives (kMPs). <i>Autonomous Robots</i> , 2014, 36, 331-347.	4.8	18
74	Vision-based foothold contact reasoning using curved surface patches. , 2017, , .		18
75	A Self-Tuning Impedance Controller for Autonomous Robotic Manipulation. , 2018, , .		18
76	How design can affect the energy required to regulate the stiffness in variable stiffness actuators. , 2012, , .		16
77	HERI II: A Robust and Flexible Robotic Hand based on Modular Finger design and Under Actuation Principles. , 2018, , .		16
78	Terrain Segmentation and Roughness Estimation using RGB Data: Path Planning Application on the CENTAURO Robot. , 2019, , .		16
79	Hopping at the resonance frequency: A trajectory generation technique for bipedal robots with elastic joints. , 2012, , .		15
80	HERI hand: A quasi dexterous and powerful hand with asymmetrical finger dimensions and under actuation. , 2017, , .		15
81	Quadrupedal walking motion and footstep placement through Linear Model Predictive Control. , 2018, , .		15
82	Online Relative Footstep Optimization for Legged Robots Dynamic Walking Using Discrete-Time Model Predictive Control. , 2019, , .		15
83	The role of physical damping in compliant actuation systems. , 2012, , .		14
84	Can active impedance protect robots from landing impact?. , 2014, , .		14
85	Human-like impedance and minimum effort control for natural and efficient manipulation. , 2013, , .		13
86	A passivity based compliance stabilizer for humanoid robots. , 2014, , .		13
87	Preparatory object reorientation for task-oriented grasping. , 2016, , .		13
88	Robust Model Predictive Control for humanoids standing balancing. , 2016, , .		12
89	A novel human effort estimation method for knee assistive exoskeletons. , 2017, 2017, 1266-1272.		12
90	Online impedance regulation techniques for compliant humanoid balancing. <i>Robotics and Autonomous Systems</i> , 2018, 104, 85-98.	5.1	12

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91	Design of a Novel 3-DoF Leg with Series and Parallel Compliant Actuation for Energy Efficient Articulated Robots. , 2018, , .		12
92	Outlier-Robust State Estimation for Humanoid Robots. , 2019, , .		12
93	Incomplete Orientation Mapping for Teleoperation With One DoF Master-Slave Asymmetry. IEEE Robotics and Automation Letters, 2020, 5, 5167-5174.	5.1	12
94	A Whole-Body Control Framework Based on the Operational Space Formulation Under Inequality Constraints via Task-Oriented Optimization. IEEE Access, 2021, 9, 39813-39826.	4.2	12
95	Gravity compensation control of compliant joint systems with multiple drives. , 2013, , .		11
96	A compliant humanoid walking strategy based on the switching of state feedback gravity compensation controllers. , 2013, , .		11
97	Lyapunov Stability Margins for humanoid robot balancing. , 2014, , .		11
98	The patched intrinsic tactile object: A tool to investigate human grasps. , 2014, , .		11
99	Online impedance parameter tuning for compliant biped balancing. , 2015, , .		11
100	Balance and impedance optimization control for COmpliant huMANoid stepping. , 2016, , .		11
101	On the Comprehensive Kinematics Analysis of a Humanoid Parallel Ankle Mechanism. Journal of Mechanisms and Robotics, 2018, 10, .	2.2	11
102	Learning to exploit passive compliance for energy-efficient gait generation on a compliant humanoid. Autonomous Robots, 2019, 43, 79-95.	4.8	11
103	Toward a Plug-and-Work Reconfigurable Cobot. IEEE/ASME Transactions on Mechatronics, 2022, 27, 3219-3231.	5.8	11
104	A new variable stiffness actuator (CompAct-VSA): Design and modelling. , 2011, , .		11
105	Variable impedance walking using Time-Varying Lyapunov Stability Margins. , 2017, , .		10
106	Designing a High Performance Humanoid Robot Based on Dynamic Simulation. , 2013, , .		9
107	Exploiting the redundancy for humanoid robots to dynamically step over a large obstacle. , 2015, , .		9
108	Straight leg walking strategy for torque-controlled humanoid robots. , 2016, , .		9

#	ARTICLE	IF	CITATIONS
109	Agile Legged-Wheeled Reconfigurable Navigation Planner Applied on the CENTAURO Robot. , 2020, , .		9
110	Walking trajectory generation for humanoid robots with compliant joints: Experimentation with COMAN humanoid. , 2012, , .		8
111	Optimal ankle compliance regulation for humanoid balancing control. , 2013, , .		8
112	Comparison study of two inverted pendulum models for balance recovery. , 2014, , .		8
113	What is the torque bandwidth of this actuator?. , 2017, , .		8
114	Synergy-Based Bilateral Port: A Universal Control Module for Tele-Manipulation Frameworks Using Asymmetric Master–Slave Systems. <i>Frontiers in Bioengineering and Biotechnology</i> , 2017, 5, 19.	4.1	8
115	Towards a Robot Hardware Abstraction Layer (R-Hal) Leveraging the XBot Software Framework. , 2018, , .		8
116	The eLeg: A Novel Efficient Leg Prototype Powered by Adjustable Parallel Compliant Actuation Principles. , 2018, , .		8
117	A Whole Body Attitude Stabilizer for Hybrid Wheeled-Legged Quadruped Robots. , 2018, , .		8
118	Versatile Reactive Bipedal Locomotion Planning Through Hierarchical Optimization. , 2019, , .		8
119	Design a Fall Recovery Strategy for a Wheel-Legged Quadruped Robot Using Stability Feature Space. , 2019, , .		8
120	Variable Configuration Planner for Legged-Rolling Obstacle Negotiation Locomotion: Application on the CENTAURO Robot. , 2019, , .		8
121	Stabilizing humanoids on slopes using terrain inclination estimation. , 2013, , .		7
122	Natural redundancy resolution in dual-arm manipulation using configuration dependent stiffness (CDS) control. , 2014, , .		7
123	Development of a hybrid actuator with controllable mechanical damping. , 2014, , .		7
124	XBotCloud: A Scalable Cloud Computing Infrastructure for XBot Powered Robots. , 2018, , .		7
125	Enhanced Tele-interaction in Unknown Environments Using Semi-Autonomous Motion and Impedance Regulation Principles. , 2018, , .		7
126	An open-source architecture for simulation, execution and analysis of real-time robotics systems. , 2018, , .		7



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127	A Study on Sparse Hierarchical Inverse Kinematics Algorithms for Humanoid Robots. IEEE Robotics and Automation Letters, 2020, 5, 235-242.	5.1	7
128	Optimal human-inspired ankle stiffness regulation for humanoid balancing control. , 2014, , .		6
129	A torque-controlled humanoid robot riding on a two-wheeled mobile platform. , 2017, , .		6
130	Neural-Network-Controlled Spring Mass Template for Humanoid Running. , 2018, , .		6
131	A Fail-Safe Semi-Centralized Impedance Controller: Validation on a Parallel Kinematics Ankle. , 2018, , .		6
132	A Simple Yet Effective Whole-Body Locomotion Framework for Quadruped Robots. Frontiers in Robotics and AI, 2020, 7, 528473.	3.2	6
133	Exo-Muscle: A Semi-Rigid Assistive Device for the Knee. IEEE Robotics and Automation Letters, 2021, 6, 8514-8521.	5.1	6
134	A Workspace Limit Approach for Teleoperation Based on Signed Distance Function. IEEE Robotics and Automation Letters, 2021, 6, 5589-5596.	5.1	6
135	Reconfigurable and Agile Legged-Wheeled Robot Navigation in Cluttered Environments With Movable Obstacles. IEEE Access, 2022, 10, 2429-2445.	4.2	6
136	TelePhysicalOperation: Remote Robot Control Based on a Virtual "Marionette" Type Interaction Interface. IEEE Robotics and Automation Letters, 2022, 7, 2479-2486.	5.1	6
137	Exploration of virtual surface features with a high performance tactile and force feedback interface. , 2012, , .		5
138	A push recovery strategy for a passively compliant humanoid robot using decentralized LQR controllers. , 2013, , .		5
139	Upper limb compliant strategy exploiting external physical constraints for humanoid fall avoidance. , 2013, , .		5
140	Online Joint Stiffness Transfer from Human Arm to Anthropomorphic Arm. , 2018, , .		5
141	Online Falling-Over Control of Humanoids Exploiting Energy Shaping and Distribution Methods. , 2018, , .		5
142	A Rolling Flexure Mechanism for Progressive Stiffness Actuators. , 2019, , .		5
143	Reactive Walking Based on Upper-Body Manipulability: An application to Intention Detection and Reaction. , 2019, , .		5
144	A Self-Modulated Impedance Multimodal Interaction Framework for Human-Robot Collaboration. , 2019, , .		5

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145	A Disturbance-Aware Trajectory Planning Scheme Based on Model Predictive Control. IEEE Robotics and Automation Letters, 2020, 5, 5779-5786.	5.1	5
146	On the efficient control of series-parallel compliant articulated robots. , 2020, , .		5
147	Mechatronic Design and Control of a Light Weight Manipulator Arm for Mobile Platforms. , 2021, , .		5
148	Locomotion Adaptation in Heavy Payload Transportation Tasks with the Quadruped Robot CENTAURO. , 2021, , .		5
149	Orientation discrimination of patterned surfaces through an actuated and non-actuated tactile display. , 2011, , .		4
150	Efficient human-like walking for the compliant huMANoid COMAN based on linematic Motion Primitives (kMPs). , 2012, , .		4
151	Internal model control for improving the gait tracking of a compliant humanoid robot. , 2012, , .		4
152	Optically-regulated impedance-based balancing for humanoid robots. , 2015, , .		4
153	A Study on Low-Drift State Estimation for Humanoid Locomotion, Using LiDAR and Kinematic-Inertial Data Fusion. , 2018, , .		4
154	Enhanced Explosive Motion for Torque Controlled Actuators Through Field Weakening Control. , 2018, , .		4
155	A mixed real-time robot hardware abstraction layer (R-HAL). Encyclopedia With Semantic Computing and Robotic Intelligence, 2018, 02, 1850010.	0.2	4
156	Whole-Body Stabilization for Visual-Based Box Lifting with the COMAN+ Robot. , 2019, , .		4
157	Sparse Optimization of Contact Forces for Balancing Control of Multi-Legged Humanoids. IEEE Robotics and Automation Letters, 2019, 4, 1117-1124.	5.1	4
158	Study on operational space control of a redundant robot with un-actuated joints: experiments under actuation failure scenarios. Nonlinear Dynamics, 2021, 105, 331-344.	5.2	4
159	NSPG: An Efficient Posture Generator Based on Null-Space Alteration and Kinetostatics Constraints. Frontiers in Robotics and AI, 2021, 8, 715325.	3.2	4
160	FOOT PLACEMENT CONTROL FOR BIPEDAL WALKING ON UNEVEN TERRAIN: AN ONLINE LINEAR REGRESSION ANALYSIS APPROACH. , 2015, , .		4
161	MPC strategy for dynamic stabilization of preplanned walking gaits. , 2017, , .		3
162	Compliant Humanoids Moving Toward Rehabilitation Applications: Transparent Integration of Real-Time Control, Whole-Body Motion Generation, and Virtual Reality. IEEE Robotics and Automation Magazine, 2019, 26, 83-93.	2.0	3

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163	Exploitation of Environment Support Contacts for Manipulation Effort Reduction of a Robot Arm. , 2019, , .		3
164	Agile Standing-up Control of Humanoids: Energy-based Reactive Contact Wrench Optimization with Strict Dynamic Consistency. , 2019, , .		3
165	A Compliant Mechanism with Progressive Stiffness for Robotic Actuation. , 2021, , .		3
166	NEXT-GENERATION COLLABORATIVE ROBOTIC SYSTEMS FOR INDUSTRIAL SAFETY AND HEALTH. , 2017, , .		3
167	Minimum-Effort Task-based Design Optimization of Modular Reconfigurable Robots. , 2021, , .		3
168	Robust Gait Synthesis Combining Constrained Optimization and Imitation Learning. , 2020, , .		3
169	Human Tactile Ability to Discriminate Variations in Small Ridge Patterns through a Portable-Wearable Tactile Display. , 2010, , .		2
170	A new foot sole design for humanoids robots based on viscous air damping mechanism. , 2015, , .		2
171	A general whole-body compliance framework for humanoid robots. , 2015, , .		2
172	A study of nonlinear forward models for dynamic walking. , 2017, , .		2
173	RRT-based motion planning with sampling in Redundancy space for robots with anthropomorphic arms. , 2017, , .		2
174	Humanoid running based on centroidal dynamics and heuristic foot placement. , 2017, , .		2
175	Blending of Series-Parallel Compliant Actuation With Field Weakening Control for Explosive Motion Generation. IEEE Robotics and Automation Letters, 2021, 6, 2076-2083.	5.1	2
176	Modeling and Optimal Control for Rope-Assisted Rappelling Maneuvers. , 2021, , .		2
177	A Generalized Index for Fault-Tolerant Control in Operational Space Under Free-Swinging Actuation Failure. IEEE Robotics and Automation Letters, 2022, 7, 1486-1493.	5.1	2
178	Towards an Open-Source Hardware Agnostic Framework for Robotic End-Effectors Control. , 2021, , .		2
179	Towards a Generic Grasp Planning Pipeline using End-Effector Specific Primitive Grasping Actions. , 2021, , .		2
180	Variable physical damping actuators (VPDAs): Facilitating the control and improving the performance of compliant actuation systems. , 2012, , .		1

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181	Dynamically transitioning between surfaces of varying inclinations to achieve uneven-terrain walking. , 2014, , .		1
182	Design of a variable compliant humanoid foot with a new toe mechanism. , 2016, , .		1
183	New Cross-Step Enabled Configurations for Humanoid Robot. , 2018, , .		1
184	From Non-Reactive to Reactive Walking in Humanoid Robots. , 2018, , .		1
185	Flux Regulation for Torque-controlled Robotics Actuators. , 2019, , .		1
186	An Angle- Axis Space-Based Orientability Index Characterizing Complete Orientations. IEEE/ASME Transactions on Mechatronics, 2022, 27, 880-891.	5.8	1
187	Omnidirectional Walking Pattern Generator Combining Virtual Constraints and Preview Control for Humanoid Robots. Frontiers in Robotics and AI, 2021, 8, 660004.	3.2	1
188	The Math of Tasks: A Domain Specific Language for Constraint-Based Task Specification. International Journal of Humanoid Robotics, 2021, 18, 2150008.	1.1	1
189	Agile Actions with a Centaur-Type Humanoid: A Decoupled Approach. , 2021, , .		1
190	On Perpendicular Curve-Based Task Space Trajectory Tracking Control With Incomplete Orientation Constraint. IEEE Transactions on Automation Science and Engineering, 2023, 20, 1244-1261.	5.2	1
191	Actuation principles for robots with high power and enhance physical interaction capabilities. , 2017, , .		0
192	A Novel Joint Torque Estimation Method and Sensory System for Assistive Lower Limb Exoskeletons. , 2018, , .		0
193	Ctrl-MORE: A Framework to Integrate Controllers of Multi-DoF Robot for Developers and Users. , 2018, , .		0
194	An analysis of the effect of gravity compensation on compliant biped walking controllers. , 2018, , .		0
195	Editorial: Advances in Mechatronics and Biomechanics Towards Efficient Robot Actuation. Frontiers in Robotics and AI, 2019, 6, 19.	3.2	0
196	Synchronizing Virtual Constraints and Preview Controller: a Walking Pattern Generator for the Humanoid Robot COMAN+. , 2019, , .		0
197	XBot: A Cross-Robot Software Framework for Real-Time Control. , 0, , .		0
198	A mixed real-time robot hardware abstraction layer (R-HAL). World Scientific Encyclopedia With Semantic Computing and Robotic Intelligence, 2019, , 153-159.	0.0	0

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199	Grasping with Embedded Synergies through a Reconfigurable Electric Actuation Topology. , 2021, , .		0