Nikos G Tsagarakis

List of Publications by Year
in descending order

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	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
2	An Angleâ€“Axis Space-Based Orientability Index Characterizing Complete Orientations. IEEE/ASME Transactions on Mechatronics, 2022, 27, 880-891.	5.8	1
3	Toward a Plug-and-Work Reconfigurable Cobot. IEEE/ASME Transactions on Mechatronics, 2022, 27, 3219-3231.	5.8	11
4	Reconfigurable and Agile Legged-Wheeled Robot Navigation in Cluttered Environments With Movable Obstacles. IEEE Access, 2022, 10, 2429-2445.	4.2	6
5	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
6	TelePhysicalOperation: Remote Robot Control Based on a Virtual â€œMarionetteâ€•Type Interaction Interface. IEEE Robotics and Automation Letters, 2022, 7, 2479-2486.	5.1	6
7	An efficient leg with seriesâ€“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
8	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
9	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
10	Omnidirectional Walking Pattern Generator Combining Virtual Constraints and Preview Control for Humanoid Robots. Frontiers in Robotics and AI, 2021, 8, 660004.	3.2	1
11	The Math of Tasks: A Domain Specific Language for Constraint-Based Task Specification. International Journal of Humanoid Robotics, 2021, 18, 2150008.	1.1	1
12	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
13	A Compliant Mechanism with Progressive Stiffness for Robotic Actuation. , 2021, , .		3
14	Mechatronic Design and Control of a Light Weight Manipulator Arm for Mobile Platforms. , 2021, , .		5
15	NSPG: An Efficient Posture Generator Based on Null-Space Alteration and Kinetostatics Constraints. Frontiers in Robotics and AI, 2021, 8, 715325.	3.2	4
16	Exo-Muscle: A Semi-Rigid Assistive Device for the Knee. IEEE Robotics and Automation Letters, 2021, 6, 8514-8521.	5.1	6
17	Locomotion Adaptation in Heavy Payload Transportation Tasks with the Quadruped Robot CENTAURO. , 2021, , .		5
18	Modeling and Optimal Control for Rope-Assisted Rappelling Maneuvers. , 2021, , .		2

#	Article	IF	Citations
19	Minimum-Effort Task-based Design Optimization of Modular Reconfigurable Robots. , 2021, , .		3
20	Agile Actions with a Centaur-Type Humanoid: A Decoupled Approach. , 2021, , .		1
21	A Workspace Limit Approach for Teleoperation Based on Signed Distance Function. IEEE Robotics and Automation Letters, 2021, 6, 5589-5596.	5.1	6
22	Grasping with Embedded Synergies through a Reconfigurable Electric Actuation Topology. , 2021, , .		0
23	Towards an Open-Source Hardware Agnostic Framework for Robotic End-Effectors Control. , 2021, , .		2
24	Towards a Generic Grasp Planning Pipeline using End-Effector Specific Primitive Grasping Actions. , 2021, , .		2
25	Remote mobile manipulation with the centauro robot: Fullâ€body telepresence and autonomous operator assistance. Journal of Field Robotics, 2020, 37, 889-919.	6.0	48
26	A Study on Sparse Hierarchical Inverse Kinematics Algorithms for Humanoid Robots. IEEE Robotics and Automation Letters, 2020, 5, 235-242.	5.1	7
27	A Disturbance-Aware Trajectory Planning Scheme Based on Model Predictive Control. IEEE Robotics and Automation Letters, 2020, 5, 5779-5786.	5.1	5
28	A Simple Yet Effective Whole-Body Locomotion Framework for Quadruped Robots. Frontiers in Robotics and AI, 2020, 7, 528473.	3.2	6
29	Agile Legged-Wheeled Reconfigurable Navigation Planner Applied on the CENTAURO Robot. , 2020, , .		9
30	On the efficient control of series-parallel compliant articulated robots. , 2020, , .		5
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	Incomplete Orientation Mapping for Teleoperation With One DoF Master-Slave Asymmetry. IEEE Robotics and Automation Letters, 2020, 5, 5167-5174.	5.1	12
33	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
34	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
35	Robust Gait Synthesis Combining Constrained Optimization and Imitation Learning. , 2020, , .		3
36	CartesI/O: A ROS Based Real-Time Capable Cartesian Control Framework. , 2019, , .		37

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37	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
38	Whole-Body Stabilization for Visual-Based Box Lifting with the COMAN+ Robot. , 2019, , .		4
39	A Rolling Flexure Mechanism for Progressive Stiffness Actuators. , 2019, , .		5
40	Reactive Walking Based on Upper-Body Manipulability: An application to Intention Detection and Reaction. , 2019, , .		5
41	Versatile Reactive Bipedal Locomotion Planning Through Hierarchical Optimization. , 2019, , .		8
42	A Self-Modulated Impedance Multimodal Interaction Framework for Human-Robot Collaboration. , 2019, , .		5
43	Exploitation of Environment Support Contacts for Manipulation Effort Reduction of a Robot Arm. , 2019, , .		3
44	Sparse Optimization of Contact Forces for Balancing Control of Multi-Legged Humanoids. IEEE Robotics and Automation Letters, 2019, 4, 1117-1124.	5.1	4
45	Editorial: Advances in Mechatronics and Biomechanics Towards Efficient Robot Actuation. Frontiers in Robotics and AI, 2019, 6, 19.	3.2	0
46	CENTAURO: A Hybrid Locomotion and High Power Resilient Manipulation Platform. IEEE Robotics and Automation Letters, 2019, 4, 1595-1602.	5.1	120
47	Online Relative Footstep Optimization for Legged Robots Dynamic Walking Using Discrete-Time Model Predictive Control. , 2019, , .		15
48	Design a Fall Recovery Strategy for a Wheel-Legged Quadruped Robot Using Stability Feature Space. , 2019, , .		8
49	Synchronizing Virtual Constraints and Preview Controller: a Walking Pattern Generator for the Humanoid Robot COMAN+. , 2019, , .		0
50	Variable Configuration Planner for Legged-Rolling Obstacle Negotiation Locomotion: Application on the CENTAURO Robot. , 2019, , .		8
51	Terrain Segmentation and Roughness Estimation using RGB Data: Path Planning Application on the CENTAURO Robot. , 2019, , .		16
52	Agile Standing-up Control of Humanoids: Energy-based Reactive Contact Wrench Optimization with Strict Dynamic Consistency. , 2019, , .		3
53	Outlier-Robust State Estimation for Humanoid Robots. , 2019, , .		12
54	Flux Regulation for Torque-controlled Robotics Actuators. , 2019, , .		1

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55	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
56	Learning to exploit passive compliance for energy-efficient gait generation on a compliant humanoid. Autonomous Robots, 2019, 43, 79-95.	4.8	11
57	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
58	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
59	Design and Evaluation of a Wearable Skin Stretch Device for Haptic Guidance. IEEE Robotics and Automation Letters, 2018, 3, 524-531.	5.1	59
60	Towards a Robot Hardware Abstraction Layer (R-Hal) Leveraging the XBot Software Framework. , 2018, , .		8
61	Online impedance regulation techniques for compliant humanoid balancing. Robotics and Autonomous Systems, 2018, 104, 85-98.	5.1	12
62	Online Model Based Estimation of Complete Joint Stiffness of Human Arm. IEEE Robotics and Automation Letters, 2018, 3, 84-91.	5.1	27
63	Anticipatory Robot Assistance for the Prevention of Human Static Joint Overloading in Humanâ€“Robot Collaboration. IEEE Robotics and Automation Letters, 2018, 3, 68-75.	5.1	85
64	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
65	Robot adaptation to human physical fatigue in humanâ€“robot co-manipulation. Autonomous Robots, 2018, 42, 1011-1021.	4.8	105
66	New Cross-Step Enabled Configurations for Humanoid Robot. , 2018, , .		1
67	Translating Videos to Commands for Robotic Manipulation with Deep Recurrent Neural Networks. , 2018, , .		32
68	A Self-Tuning Impedance Controller for Autonomous Robotic Manipulation. , 2018, , .		18
69	HERI II: A Robust and Flexible Robotic Hand based on Modular Finger design and Under Actuation Principles. , 2018, , .		16
70	From Non-Reactive to Reactive Walking in Humanoid Robots. , 2018, , .		1
71	XBotCloud: A Scalable Cloud Computing Infrastructure for XBot Powered Robots. , 2018, , .		7
72	The eLeg: A Novel Efficient Leg Prototype Powered by Adjustable Parallel Compliant Actuation Principles. , 2018, , .		8

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73	An Overview on Principles for Energy Efficient Robot Locomotion. Frontiers in Robotics and AI, 2018, 5, 129.	3.2	60
74	Online Joint Stiffness Transfer from Human Arm to Anthropomorphic Arm. , 2018, , .		5
75	A Study on Low-Drift State Estimation for Humanoid Locomotion, Using LiDAR and Kinematic-Inertial Data Fusion. , 2018, , .		4
76	Bi-Manual Articulated Robot Teleoperation using an External RGB-D Range Sensor. , 2018, , .		24
77	Neural-Network-Controlled Spring Mass Template for Humanoid Running. , 2018, , .		6
78	Quadrupedal walking motion and footstep placement through Linear Model Predictive Control. , 2018, , .		15
79	Enhanced Explosive Motion for Torque Controlled Actuators Through Field Weakening Control. , 2018, , .		4
80	A Fail-Safe Semi-Centralized Impedance Controller: Validation on a Parallel Kinematics Ankle. , 2018, , .		6
81	A Novel Joint Torque Estimation Method and Sensory System for Assistive Lower Limb Exoskeletons. , 2018, , .		0
82	Ctrl-MORE: A Framework to Integrate Controllers of Multi-DoF Robot for Developers and Users. , 2018, , .		0
83	Online Falling-Over Control of Humanoids Exploiting Energy Shaping and Distribution Methods. , 2018, , .		5
84	Footstep Planning in Rough Terrain for Bipedal Robots Using Curved Contact Patches. , 2018, , .		19
85	Enhanced Tele-interaction in Unknown Environments Using Semi-Autonomous Motion and Impedance Regulation Principles. , 2018, , .		7
86	Design of a Novel 3-DoF Leg with Series and Parallel Compliant Actuation for Energy Efficient Articulated Robots. , 2018, , .		12
87	Multi-Priority Cartesian Impedance Control Based on Quadratic Programming Optimization. , 2018, , .		24
88	A Whole Body Attitude Stabilizer for Hybrid Wheeled-Legged Quadruped Robots. , 2018, , .		8
89	On the Comprehensive Kinematics Analysis of a Humanoid Parallel Ankle Mechanism. Journal of Mechanisms and Robotics, 2018, 10, .	2.2	11
90	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

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91	A mixed real-time robot hardware abstraction layer (R-HAL). Encyclopedia With Semantic Computing and Robotic Intelligence, 2018, 02, 1850010.	0.2	4
92	An analysis of the effect of gravity compensation on compliant biped walking controllers. , 2018, , .		0
93	An open-source architecture for simulation, execution and analysis of real-time robotics systems. , 2018, , .		7
94	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
95	Choosing Poses for Force and Stiffness Control. IEEE Transactions on Robotics, 2017, 33, 1483-1490.	10.3	37
96	XBotCore: A Real-Time Cross-Robot Software Platform. , 2017, , .		57
97	Overview of Gait Synthesis for the Humanoid COMAN. Journal of Bionic Engineering, 2017, 14, 15-25.	5.0	38
98	A study of nonlinear forward models for dynamic walking. , 2017, , .		2
99	On the Stiffness Selection for Torque-Controlled Series-Elastic Actuators. IEEE Robotics and Automation Letters, 2017, 2, 2255-2262.	5.1	34
100	RRT-based motion planning with sampling in Redundancy space for robots with anthropomorphic arms. , 2017, , .		2
101	A novel human effort estimation method for knee assistive exoskeletons. , 2017, 2017, 1266-1272.		12
102	Development of a human size and strength compliant bi-manual platform for realistic heavy manipulation tasks. , 2017, , .		37
103	Humanoid running based on centroidal dynamics and heuristic foot placement. , 2017, , .		2
104	Actuation principles for robots with high power and enhance physical interaction capabilities. , 2017, , .		0
105	HERI hand: A quasi dexterous and powerful hand with asymmetrical finger dimensions and under actuation. , 2017, , .		15
106	A torque-controlled humanoid robot riding on a two-wheeled mobile platform. , 2017, , .		6
107	What is the torque bandwidth of this actuator?. , 2017, , .		8
108	Object-based affordances detection with Convolutional Neural Networks and dense Conditional Random Fields. , 2017, , .		94

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109	MPC strategy for dynamic stabilization of preplanned walking gaits. , 2017, , .		3
110	Variable impedance walking using Time-Varying Lyapunov Stability Margins. , 2017, , .		10
111	Robot control for dummies: Insights and examples using OpenSoT. , 2017, , .		42
112	Teleoperation in cluttered environments using wearable haptic feedback. , 2017, , .		46
113	Synergy-Based Bilateral Port: A Universal Control Module for Tele-Manipulation Frameworks Using Asymmetric Masterâ€“Slave Systems. Frontiers in Bioengineering and Biotechnology, 2017, 5, 19.	4.1	8
114	Vision-based foothold contact reasoning using curved surface patches. , 2017, , .		18
115	NEXT-GENERATION COLLABORATIVE ROBOTIC SYSTEMS FOR INDUSTRIAL SAFETY AND HEALTH. , 2017, , .		3
116	Design of a variable compliant humanoid foot with a new toe mechanism. , 2016, , .		1
117	Reflex control of the Pisa/IIT SoftHand during object slippage. , 2016, , .		20
118	Straight leg walking strategy for torque-controlled humanoid robots. , 2016, , .		9
119	iT-Knee: An exoskeleton with ideal torque transmission interface for ergonomic power augmentation. , 2016, , .		32
120	Preparatory object reorientation for task-oriented grasping. , 2016, , .		13
121	Balance and impedance optimization control for COmpliant huMANoid stepping. , 2016, , .		11
122	Towards multi-modal intention interfaces for human-robot co-manipulation. , 2016, , .		42
123	Detecting object affordances with Convolutional Neural Networks. , 2016, , .		120
124	Robust Model Predictive Control for humanoids standing balancing. , 2016, , .		12
125	Design of a wearable skin stretch cutaneous device for the upper limb. , 2016, , .		40
126	Dynamic and Reactive Walking for Humanoid Robots Based on Foot Placement Control. International Journal of Humanoid Robotics, 2016, 13, 1550041.	1.1	43

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127	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
128	Compliance control for stabilizing the humanoid on the changing slope based on terrain inclination estimation. Autonomous Robots, 2016, 40, 955-971.	4.8	19
129	Stabilization of bipedal walking based on compliance control. Autonomous Robots, 2016, 40, 1041-1057.	4.8	34
130	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
131	A new foot sole design for humanoids robots based on viscous air damping mechanism. , 2015, , .		2
132	Optically-regulated impedance-based balancing for humanoid robots. , 2015, , .		4
133	A reduced-complexity description of arm endpoint stiffness with applications to teleimpedance control. , 2015, , .		32
134	Exploiting the redundancy for humanoid robots to dynamically step over a large obstacle. , 2015, , .		9
135	OpenSoT: A whole-body control library for the compliant humanoid robot COMAN. , 2015, , .		47
136	A general whole-body compliance framework for humanoid robots. , 2015, , .		2
137	Efficient self-collision avoidance based on focus of interest for humanoid robots. , 2015, , .		28
138	Kinematic analysis and design considerations for optimal base frame arrangement of humanoid shoulders. , 2015, , .		22
139	Online regeneration of bipedal walking gait pattern optimizing footstep placement and timing. , 2015, , .		39
140	Online impedance parameter tuning for compliant biped balancing. , 2015, , .		11
141	On the role of robot configuration in Cartesian stiffness control. , 2015, , .		34
142	FOOT PLACEMENT CONTROL FOR BIPEDAL WALKING ON UNEVEN TERRAIN: AN ONLINE LINEAR REGRESSION ANALYSIS APPROACH. , 2015, , .		4
143	Comparison study of two inverted pendulum models for balance recovery. , 2014, , .		8
144	Optimal human-inspired ankle stiffness regulation for humanoid balancing control. , 2014, , .		6

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145	Lyapunov Stability Margins for humanoid robot balancing. , 2014, , .		11
146	Can active impedance protect robots from landing impact?. , 2014, , .		14
147	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
148	Walking in the resonance with the COMAN robot with trajectories based on human kinematic motion primitives (kMPs). Autonomous Robots, 2014, 36, 331-347.	4.8	18
149	Natural redundancy resolution in dual-arm manipulation using configuration dependent stiffness (CDS) control. , 2014, , .		7
150	A passivity based compliance stabilizer for humanoid robots. , 2014, , .		13
151	Development of a hybrid actuator with controllable mechanical damping. , 2014, , .		7
152	Dynamically transitioning between surfaces of varying inclinations to achieve uneven-terrain walking. , 2014, , .		1
153	The patched intrinsic tactile object: A tool to investigate human grasps. , 2014, , .		11
154	Development of a dynamic simulator for a compliant humanoid robot based on a symbolic multibody approach. , 2013, , .		34
155	A Novel Intrinsically Energy Efficient Actuator With Adjustable Stiffness (AwAS). IEEE/ASME Transactions on Mechatronics, 2013, 18, 355-365.	5.8	169
156	A push recovery strategy for a passively compliant humanoid robot using decentralized LQR controllers. , 2013, , .		5
157	Analysis and Development of a Semiactive Damper for Compliant Actuation Systems. IEEE/ASME Transactions on Mechatronics, 2013, 18, 744-753.	5.8	33
158	Walking pattern generation for a humanoid robot with compliant joints. Autonomous Robots, 2013, 35, 1-14.	4.8	30
159	Optimal ankle compliance regulation for humanoid balancing control. , 2013, , .		8
160	Designing a High Performance Humanoid Robot Based on Dynamic Simulation. , 2013, , .		9
161	COMpliant huMANoid COMAN: Optimal joint stiffness tuning for modal frequency control. , 2013, , .		172
162	Stabilizing humanoids on slopes using terrain inclination estimation. , 2013, , .		7

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163	Human-like impedance and minimum effort control for natural and efficient manipulation. , 2013, , .		13
164	Upper limb compliant strategy exploiting external physical constraints for humanoid fall avoidance. , 2013, , .		5
165	An attractor-based Whole-Body Motion Control (WBMC) system for humanoid robots. , 2013, , .		23
166	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
167	Gravity compensation control of compliant joint systems with multiple drives. , 2013, , .		11
168	A compliant humanoid walking strategy based on the switching of state feedback gravity compensation controllers. , 2013, , .		11
169	Tele-Impedance based stiffness and motion augmentation for a knee exoskeleton device. , 2013, , .		43
170	A compact model for the compliant humanoid robot COMAN. , 2012, , .		26
171	A Variable Damping module for Variable Impedance Actuation. , 2012, , .		18
172	Variable physical damping actuators (VPDAs): Facilitating the control and improving the performance of compliant actuation systems. , 2012, , .		1
173	On-line estimation of variable stiffness in flexible robot joints. International Journal of Robotics Research, 2012, 31, 1556-1577.	8.5	43
174	Exploration of virtual surface features with a high performance tactile and force feedback interface. , 2012, , .		5
175	THE DESIGN OF THE iCub HUMANOID ROBOT. International Journal of Humanoid Robotics, 2012, 09, 1250027.	1.1	81
176	The role of physical damping in compliant actuation systems. , 2012, , .		14
177	Efficient human-like walking for the compliant huMANoid COMAN based on linematic Motion Primitives (kMPs). , 2012, , .		4
178	YAW MOMENT COMPENSATION FOR BIPEDAL ROBOTS VIA INTRINSIC ANGULAR MOMENTUM CONSTRAINT. International Journal of Humanoid Robotics, 2012, 09, 1250033.	1.1	40
179	Stabilization for the compliant humanoid robot COMAN exploiting intrinsic and controlled compliance. , 2012, , .		27
180	The mechatronic design of the new legs of the iCub robot. , 2012, , .		19

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181	A passivity based admittance control for stabilizing the compliant humanoid COMAN. , 2012, , .		45
182	Hopping at the resonance frequency: A trajectory generation technique for bipedal robots with elastic joints. , 2012, , .		15
183	Walking trajectory generation for humanoid robots with compliant joints: Experimentation with COMAN humanoid. , 2012, , .		8
184	How design can affect the energy required to regulate the stiffness in variable stiffness actuators. , 2012, , .		16
185	Tele-impedance: Teleoperation with impedance regulation using a bodyâ€“machine interface. International Journal of Robotics Research, 2012, 31, 1642-1656.	8.5	211
186	Internal model control for improving the gait tracking of a compliant humanoid robot. , 2012, , .		4
187	Design, modeling and control of a series elastic actuator for an assistive knee exoskeleton. , 2012, , .		38
188	Comparison of various active impedance control approaches, modeling, implementation, passivity, stability and trade-offs. , 2012, , .		38
189	A human-like walking for the COmpliant huMANoid COMAN based on CoM trajectory reconstruction from kinematic Motion Primitives. , 2011, , .		27
190	Orientation discrimination of patterned surfaces through an actuated and non-actuated tactile display. , 2011, , .		4
191	AwAS-II: A new Actuator with Adjustable Stiffness based on the novel principle of adaptable pivot point and variable lever ratio. , 2011, , .		138
192	Exploiting natural dynamics for energy minimization using an Actuator with Adjustable Stiffness (AwAS). , 2011, , .		35
193	A new variable stiffness actuator (CompAct-VSA): Design and modelling. , 2011, , .		133
194	Compliant joint modification and real-time dynamic walking implementation on bipedal robot cCub. , 2011, , .		18
195	A decoupled impedance observer for a variable stiffness robot. , 2011, , .		18
196	A new variable stiffness actuator (CompAct-VSA): Design and modelling. , 2011, , .		11
197	Water/air performance analysis of a fluidic muscle. , 2010, , .		22
198	Human Tactile Ability to Discriminate Variations in Small Ridge Patterns thorugh a Portable-Wearable Tactile Display. , 2010, , .		2

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199	XBot: A Cross-Robot Software Framework for Real-Time Control. , 0, , .		0