Norihiro Kamamichi

List of Publications by Year
in descending order

29	304	933447 10	940533 16
papers	citations	h-index	g-index

29	29	29	303
all docs	docs citations	times ranked	citing authors

#	Article	IF	Citations
1	Development of an artificial muscle linear actuator using ionic polymerâ€“metal composites. Advanced Robotics, 2004, 18, 383-399.	1.8	69
2	Earthworm muscle driven bio-micropump. Sensors and Actuators B: Chemical, 2017, 242, 1186-1192.	7.8	40
3	Displacement control of an antagonistic-type twisted and coiled polymer actuator. Smart Materials and Structures, 2018, 27, 035003.	3.5	26
4	Printing Fabrication of a Bucky Gel Actuator/Sensor and Its Application to Three-Dimensional Patterned Devices. Advanced Robotics, 2010, 24, 1471-1487.	1.8	19
5	Fabrication of bucky gel actuator/sensor devices based on printing method. , 2008, , .		16
6	Integrated Design of an Ionic Polymerâ€“Metal Composite Actuator/Sensor. Advanced Robotics, 2008, 22, 913-928.	1.8	15
7	An electric generator using living Torpedo electric organs controlled by fluid pressure-based alternative nervous systems. Scientific Reports, 2016, 6, 25899.	3.3	14
8	Doping effects on robotic systems with ionic polymerâ€“metal composite actuators. Advanced Robotics, 2007, 21, 65-85.	1.8	13
9	Control of twisted and coiled polymer actuator with anti-windup compensator. Smart Materials and Structures, 2018, 27, 075014.	3.5	13
10	Friction compensation using time variant disturbance observer based on the LuGre model. , 2012, , .		12
11	IDC Robocon: A Transnational Teaming Competition for Project-Based Design Education in Undergraduate Robotics. Robotics, 2016, 5, 12.	3.5	11
12	Flexible Pneumatic Bending Actuator for a Robotic Tongue. Journal of Robotics and Mechatronics, 2020, 32, 894-902.	1.0	11
13	Simple Controller Design Based on Internal Model Control for Twisted and Coiled Polymer Actuator. Actuators, 2018, 7, 33.	2.3	8
14	A valve powered by earthworm muscle with both electrical and 100% chemical control. Scientific Reports, 2019, 9, 8042.	3.3	8
15	Swinging up and stabilization control of double Furuta pendulums by safe manual control. , 2009, , .		5
16	Positioning control of a capsule robot using sliding mode control. , 2009, , .		5
17	Control system design and experimental verification of Capsubot. , 2008, , .		4
18	Force control of ionic polymer-metal composite actuators with cellular actuator method. , 2014, , .		3

#	Article	IF	Citations
19	2P1-F04 Motion Analysis of Lizard Type Quadruped Robots(Biorobotics (2)). The Proceedings of JSME Annual Conference on Robotics and Mechatronics (Robomec), 2013, 2013, _2P1-F04_1-_2P1-F04_3.	0.0	3
20	Motion control of lizard-type quadruped. The Proceedings of JSME Annual Conference on Robotics and Mechatronics (Robomec), 2016, 2016, 1A2-07b6.	0.0	3
21	Wide-bandwidth bilateral control using two-stage actuator system. Transactions of the JSME (in) Tj ETQq1 1 0.784314 rgBT /Overlock	0.2	2
22	Design and Implementation of a Lizard-Inspired Robot. Applied Sciences (Switzerland), 2021, 11, 7898.	2.5	2
23	Modeling and Control of a Lizard-Inspired Single-Actuated Robot. IEEE Robotics and Automation Letters, 2022, 7, 6399-6406.	5.1	1
24	Locomotion analysis of self-propelled board by inclined internal mass motion with slider-crank mechanism. Meccanica, 2023, 58, 473-492.	2.0	1
25	Experimental verification of a tactile sensor based on ionic polymer-metal composites. , 2015, , .		0
26	Displacement control of integrated ionic polymer-metal composite actuator with stochastic ON/OFF controller. Transactions of the JSME (in Japanese), 2017, 83, 17-00328-17-00328.	0.2	0
27	Cytotoxicity Test and Mass Spectrometry of IPMC. IEEJ Transactions on Electronics, Information and Systems, 2008, 128, 1029-1035.	0.2	0
28	Modeling and motion control of manipulator with twisted and coiled polymer actuator. The Proceedings of Mechanical Engineering Congress Japan, 2018, 2018, J1120101.	0.0	0
29	Linearizing compensation by PWM driving and feedback control of fishing line artificial muscle. Transactions of the JSME (in Japanese), 2020, 86, 19-00285-19-00285.	0.2	0