

# George Konidaris

## List of Publications by Year in descending order

Source: <https://exaly.com/author-pdf/10725871/publications.pdf>

Version: 2024-02-01

16  
papers

755  
citations

1684188

5  
h-index

2053705

5  
g-index

16  
all docs

16  
docs citations

16  
times ranked

659  
citing authors

| #  | ARTICLE   | IF  | CITATIONS |
|----|---|-----|-----------|
| 1  | IKFlow: Generating Diverse Inverse Kinematics Solutions. IEEE Robotics and Automation Letters, 2022, 7, 7177-7184.                              | 5.1 | 7         |
| 2  | RMPs for Safe Impedance Control in Contact-Rich Manipulation. , 2022, , .   |     | 3         |
| 3  | Generalizing to New Domains by Mapping Natural Language to Lifted LTL. , 2022, , .  |     | 3         |
| 4  | Robustly Learning Composable Options in Deep Reinforcement Learning. , 2021, , .  |     | 5         |
| 5  | Modeling and Planning with Macro-Actions in Decentralized POMDPs. Journal of Artificial Intelligence Research, 2019, 64, 817-859.               | 7.0 | 34        |
| 6  | Representing, learning, and controlling complex object interactions. Autonomous Robots, 2018, 42, 1355-1367.                                    | 4.8 | 0         |
| 7  | Active Exploration for Learning Symbolic Representations. Advances in Neural Information Processing Systems, 2017, 30, 5009-5019.               | 2.8 | 0         |
| 8  | Policy search for multi-robot coordination under uncertainty. International Journal of Robotics Research, 2016, 35, 1760-1778.                  | 8.5 | 35        |
| 9  | The microarchitecture of a real-time robot motion planning accelerator. , 2016, , .   |     | 39        |
| 10 | Nonparametric Bayesian reward segmentation for skill discovery using inverse reinforcement learning. , 2015, , .                                |     | 23        |
| 11 | Learning grounded finite-state representations from unstructured demonstrations. International Journal of Robotics Research, 2015, 34, 131-157. | 8.5 | 131       |
| 12 | Optimal sampling-based planning for linear-quadratic kinodynamic systems. , 2013, , .   |     | 46        |
| 13 | Behavioral Hierarchy: Exploration and Representation. , 2013, , 13-46.  |     | 7         |
| 14 | Robot learning from demonstration by constructing skill trees. International Journal of Robotics Research, 2012, 31, 360-375.                   | 8.5 | 180       |
| 15 | Learning and generalization of complex tasks from unstructured demonstrations. , 2012, , .  |     | 111       |
| 16 | LQR-RRT*: Optimal sampling-based motion planning with automatically derived extension heuristics. , 2012, , .                                   |     | 131       |