

Gustavo A Medrano-Cerda

List of Publications by Year in descending order

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Version: 2024-02-01

23
papers

719
citations

1684188

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h-index

1720034

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g-index

23
all docs

23
docs citations

23
times ranked

617
citing authors

| # | ARTICLE | IF | CITATIONS |
|----|---|-----|-----------|
| 1 | Stability analysis for time delay control of nonlinear systems in discrete-time domain with a standard discretisation method. <i>Control Theory and Technology</i> , 2020, 18, 92-106. | 1.6 | 2 |
| 2 | Design of a variable compliant humanoid foot with a new toe mechanism. , 2016, , . | | 1 |
| 3 | A design method of a robust controller for hydraulic actuation with disturbance observers. , 2016, , . | | 2 |
| 4 | Dynamics for variable length multisection continuum arms. <i>International Journal of Robotics Research</i> , 2016, 35, 695-722. | 8.5 | 112 |
| 5 | Corrections for "Discretisation method and stability criteria for non-linear systems under discrete-time time delay control". <i>IET Control Theory and Applications</i> , 2016, 10, 1751-1754. | 2.1 | 5 |
| 6 | Robot impedance control and passivity analysis with inner torque and velocity feedback loops. <i>Control Theory and Technology</i> , 2016, 14, 97-112. | 1.6 | 56 |
| 7 | Development and Control of a Compliant Asymmetric Antagonistic Actuator for Energy Efficient Mobility. <i>IEEE/ASME Transactions on Mechatronics</i> , 2016, 21, 1080-1091. | 5.8 | 43 |
| 8 | Modal kinematics for multisection continuum arms. <i>Bioinspiration and Biomimetics</i> , 2015, 10, 035002. | 2.9 | 76 |
| 9 | On the use of positive feedback for improved torque control. <i>Control Theory and Technology</i> , 2015, 13, 266-285. | 1.6 | 2 |
| 10 | Development of a dynamic simulator for a compliant humanoid robot based on a symbolic multibody approach. , 2013, , . | | 34 |
| 11 | Stability and performance of the compliance controller of the quadruped robot HyQ. , 2013, , . | | 64 |
| 12 | A push recovery strategy for a passively compliant humanoid robot using decentralized LQR controllers. , 2013, , . | | 5 |
| 13 | Octopus inspired walking robot: Design, control and experimental validation. , 2013, , . | | 6 |
| 14 | Optimal ankle compliance regulation for humanoid balancing control. , 2013, , . | | 8 |
| 15 | Gravity compensation control of compliant joint systems with multiple drives. , 2013, , . | | 11 |
| 16 | A compliant humanoid walking strategy based on the switching of state feedback gravity compensation controllers. , 2013, , . | | 11 |
| 17 | On the role of load motion compensation in high-performance force control. , 2012, , . | | 45 |
| 18 | Dynamic continuum arm model for use with underwater robotic manipulators inspired by octopus vulgaris. , 2012, , . | | 29 |

| # | ARTICLE | IF | CITATIONS |
|----|--|----|-----------|
| 19 | Comparison of various active impedance control approaches, modeling, implementation, passivity, stability and trade-offs. , 2012, , . | | 38 |
| 20 | Shape function-based kinematics and dynamics for variable length continuum robotic arms. , 2011, , . | | 75 |
| 21 | Dynamics for biomimetic continuum arms: A modal approach. , 2011, , . | | 30 |
| 22 | Novel modal approach for kinematics of multisection continuum arms. , 2011, , . | | 63 |
| 23 | Nonlinear structure of escape-times to falls for a passive dynamic walker on an irregular slope: Anomaly detection using multi-class support vector machine and latent state extraction by canonical correlation analysis. , 2011, , . | | 1 |