

Mehdi Tale-Masouleh

List of Publications by Year in Descending Order

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The third column is the impact factor (IF) of the journal, and the fourth column is the number of citations of the article.

78
papers

733
citations

18
h-index

22
g-index

95
ext. papers

954
ext. citations

3
avg, IF

4.72
L-index

#	Paper	IF	Citations
78	Dynamics analysis, offline-online tuning and identification of base inertia parameters for the 3-DOF Delta parallel robot under insufficient excitations. <i>Meccanica</i> , 2022 , 57, 473-506	2.1	2
77	Design and practical implementation of a Neural Network self-tuned Inverse Dynamic Controller for a 3-DoF Delta parallel robot based on Arc Length Function for smooth trajectory tracking. <i>Mechatronics</i> , 2022 , 84, 102772	3	0
76	Design and development of a multi-axis force sensor based on the hall effect with decouple structure. <i>Mechatronics</i> , 2022 , 84, 102766	3	
75	Dynamic modeling, identification, and a comparative experimental study on position control of a pneumatic actuator based on Soft Switching and Backstepping Sliding Mode controllers 2021 , 261-289		1
74	Modeling, identification and minimum length integral sliding mode control of a 3-DOF cartesian parallel robot by considering virtual flexible links. <i>Mechanism and Machine Theory</i> , 2021 , 157, 104183	4	7
73	Dynamic model estimating and designing controller for the 2-DoF planar robot in interaction with cable-driven robot based on adaptive neural network. <i>Journal of Intelligent and Fuzzy Systems</i> , 2021 , 41, 1261-1280	1.6	2
72	Control of a two-DOF parallel robot with unknown parameters using a novel robust adaptive approach. <i>ISA Transactions</i> , 2021 , 117, 70-84	5.5	3
71	A complete analytical solution for the dimensional synthesis of 3-DOF delta parallel robot for a prescribed workspace. <i>Mechanism and Machine Theory</i> , 2020 , 153, 103991	4	11
70	Kinematic Analysis of an Under-constrained Cable-driven Robot Using Neural Networks 2020 ,		1
69	Design and Evaluation of Adaptive and Sliding Mode Control for a 3-DOF Delta Parallel Robot 2020 ,		1
68	Reconstructing 3-D Graphical Model Using an Under-Constrained Cable-Driven Parallel Robot 2020 ,		1
67	Design & characterization of a bio-inspired 3-DOF Tactile/Force sensor and implementation on a 3-DOF decoupled parallel mechanism for human-robot interaction purposes. <i>Mechatronics</i> , 2020 , 66, 102325	3	6
66	Optimal wrench-closure configuration of spatial reconfigurable cable-driven parallel robots. <i>Proceedings of the Institution of Mechanical Engineers, Part C: Journal of Mechanical Engineering Science</i> , 2020 , 095440622097616	1.3	1
65	Experimental study on robust adaptive control with insufficient excitation of a 3-DOF spherical parallel robot for stabilization purposes. <i>Mechanism and Machine Theory</i> , 2020 , 153, 104026	4	3
64	Experimental Study on Shared-Control of a Mobile Robot via a Haptic Device with an Optimal Velocity Obstacle Based Receding Horizon Control Approach. <i>Journal of Intelligent and Robotic Systems: Theory and Applications</i> , 2020 , 97, 357-372	2.9	5
63	Dynamic and static object detection and tracking in an autonomous surface vehicle. <i>Ships and Offshore Structures</i> , 2020 , 15, 711-721	1.4	1
62	Kinematic and Dynamic Analysis of 3-DOF Delta Parallel Robot Based on the Screw Theory and Principle of Virtual Work 2019 ,		3

61	Experimental kinematic identification and position control of a 3-DOF decoupled parallel robot. <i>Proceedings of the Institution of Mechanical Engineers, Part C: Journal of Mechanical Engineering Science</i> , 2019 , 233, 1841-1855	1.3	6
60	Collision-free workspace and kinetostatic performances of a 4-DOF delta parallel robot. <i>Journal of the Brazilian Society of Mechanical Sciences and Engineering</i> , 2019 , 41, 1	2	23
59	Generating Synthetic Medical Images by Using GAN to Improve CNN Performance in Skin Cancer Classification 2019 ,		9
58	Localization of an indoor mobile robot using decentralized data fusion 2019 ,		2
57	An experimental oscillation damping impedance control for the Novint Falcon haptic device based on the phase trajectory length function concept. <i>Proceedings of the Institution of Mechanical Engineers, Part C: Journal of Mechanical Engineering Science</i> , 2019 , 233, 2663-2672	1.3	4
56	Forward Kinematic Analysis of Parallel Mechanisms in Seven-Dimensional Kinematic Space by Considering Limitation of Passive Joints motion. <i>Iranian Journal of Science and Technology - Transactions of Mechanical Engineering</i> , 2019 , 43, 315-329	1.2	1
55	Experimental study on the kinematic control of a cable suspended parallel robot for object tracking purpose. <i>Mechatronics</i> , 2018 , 50, 160-176	3	24
54	An experimental dynamic identification & control of an overconstrained 3-DOF parallel mechanism in presence of variable friction and feedback delay. <i>Robotics and Autonomous Systems</i> , 2018 , 102, 27-43	3.5	10
53	Oscillation damping of nonlinear control systems based on the phase trajectory length concept: An experimental case study on a cable-driven parallel robot. <i>Mechanism and Machine Theory</i> , 2018 , 126, 377-396	4	19
52	Experimental dynamic identification and model feed-forward control of Novint Falcon haptic device. <i>Mechatronics</i> , 2018 , 51, 19-30	3	18
51	A new neural gas network approach for obtaining the singularity-free workspace of 3-DOF planar parallel manipulators. <i>Proceedings of the Institution of Mechanical Engineers, Part C: Journal of Mechanical Engineering Science</i> , 2018 , 232, 174-189	1.3	4
50	Experimental study on the model-based control of a 2-degree-of-freedom spherical parallel robot camera stabilizer based on multi-thread programming concept. <i>Proceedings of the Institution of Mechanical Engineers, Part C: Journal of Mechanical Engineering Science</i> , 2018 , 232, 1882-1897	1.3	5
49	Dynamic analysis of Hexarot: axis-symmetric parallel manipulator. <i>Robotica</i> , 2018 , 36, 225-240	2.1	28
48	Trajectory tracking control of a pneumatically actuated 6-DOF Gough-Stewart parallel robot using Backstepping-Sliding Mode controller and geometry-based quasi forward kinematic method. <i>Robotics and Computer-Integrated Manufacturing</i> , 2018 , 54, 96-114	9.2	29
47	Experimental study on the visual servoing of a 4-DOF parallel robot for pick-and-place purpose 2018 ,		3
46	A statistical weighted method for kinematic sensitivity analysis of parallel robots. <i>Journal of the Brazilian Society of Mechanical Sciences and Engineering</i> , 2018 , 40, 1	2	0
45	The Collision-Free Workspace of the Tripteron Parallel Robot Based on a Geometrical Approach. <i>Mechanisms and Machine Science</i> , 2018 , 357-364	0.3	7
44	Kinematics and Control of a 4-DOF Delta Parallel Manipulator 2018 ,		1

43	Design and Control of a Suspended Cable-Driven Parallel Robot with Four Cables 2018 ,		3
42	Stabilization of a Two-DOF Spherical Parallel Robot via a Novel Adaptive Approach 2018 ,		3
41	Design, Development and Control of a Three Flexible-Fingers Gripper Based On Hand Gesture 2018		1
40	Dynamic modeling and base inertial parameters determination of a 2-DOF spherical parallel mechanism. <i>Multibody System Dynamics</i> , 2017 , 41, 367-390	2.8	22
39	An experimental study on the direct & indirect dynamic identification of an over-constrained 3-DOF decoupled parallel mechanism. <i>Mechanism and Machine Theory</i> , 2017 , 116, 178-202	4	15
38	On human-robot interaction of a 3-DOF decoupled parallel mechanism based on the design and construction of a novel and low-cost 3-DOF force sensor. <i>Meccanica</i> , 2017 , 52, 2471-2489	2.1	6
37	An optimal motion planning and obstacle avoidance algorithm based on the finite time velocity obstacle approach 2017 ,		4
36	Kinetostatic Performance and Collision-free Workspace Analysis of a 3-DOF Delta Parallel Robot 2017 ,		1
35	Kinematic Sensitivity Evaluation of Revolute and Prismatic 3-DOF Delta Robots 2017 ,		2
34	An Experimental Study on Control of a Pneumatic 6-DoF Gough-Stewart Robot Using Backstepping-Sliding Mode and Geometry-Based Quasi-Forward Kinematic Method 2017 ,		3
33	Dynamic Modeling and Base Inertial Parameters Determination of 3- DoF Planar Parallel Manipulator 2017 ,		1
32	A general approach on collision-free workspace determination via triangle-to-triangle intersection test. <i>Robotics and Computer-Integrated Manufacturing</i> , 2017 , 44, 230-241	9.2	14
31	Collision-free workspace of parallel mechanisms based on an interval analysis approach. <i>Robotica</i> , 2017 , 35, 1747-1760	2.1	18
30	Vision based control and simulation of a spherical rolling robot based on ROS and Gazebo 2017 ,		2
29	An experimental study on the vision-based control and identification of planar cable-driven parallel robots. <i>Robotics and Autonomous Systems</i> , 2016 , 75, 187-202	3.5	31
28	Determining the maximal singularity-free circle or sphere of parallel mechanisms using interval analysis. <i>Robotica</i> , 2016 , 34, 135-149	2.1	11
27	Controller tuning based on optimization algorithms of a novel spherical rolling robot. <i>Journal of Mechanical Science and Technology</i> , 2016 , 30, 5207-5216	1.6	10
26	Gr�ner basis and resultant method for the forward displacement of 3-DoF planar parallel manipulators in seven-dimensional kinematic space. <i>Robotica</i> , 2016 , 34, 2610-2628	2.1	2

25	Avoiding the singularities of 3-RPR parallel mechanisms via dimensional synthesis and self-reconfigurability. <i>Mechanism and Machine Theory</i> , 2016 , 99, 189-206	4	19
24	Optimal motion planning of redundant planar serial robots using a synergy-based approach of convex optimization, disjunctive programming and receding horizon. <i>Proceedings of the Institution of Mechanical Engineers Part I: Journal of Systems and Control Engineering</i> , 2016 , 230, 211-221	1	3
23	Optimal motion planning for parallel robots via convex optimization and receding horizon. <i>Advanced Robotics</i> , 2016 , 30, 1145-1163	1.7	2
22	A simple and fast geometric kinematic solution for imitation of human arms by a NAO humanoid robot 2016 ,		9
21	An experimental study on friction identification of a pneumatic actuator and dynamic modeling of a proportional valve 2016 ,		5
20	Dynamic identification of the Novint Falcon Haptic device 2016 ,		9
19	Experimental study on optimal motion planning of wheeled mobile robot using convex optimization and receding horizon concept 2016 ,		4
18	Optimal design of a spherical parallel manipulator based on kinetostatic performance using evolutionary techniques. <i>Journal of Mechanical Science and Technology</i> , 2016 , 30, 1323-1331	1.6	9
17	Determination of the maximal singularity-free workspace of 3-DOF parallel mechanisms with a constructive geometric approach. <i>Mechanism and Machine Theory</i> , 2015 , 84, 25-36	4	25
16	Optimization of Stirling engine design parameters using neural networks. <i>Renewable Energy</i> , 2015 , 74, 855-866	8.1	37
15	On the maximal singularity-free ellipse of planar 3-RPR parallel mechanisms via convex optimization. <i>Robotics and Computer-Integrated Manufacturing</i> , 2014 , 30, 218-227	9.2	19
14	Singularity-free workspace analysis of general 6-UPS parallel mechanisms via convex optimization. <i>Mechanism and Machine Theory</i> , 2014 , 80, 17-34	4	18
13	On the determination of the maximal inscribed ellipsoid in the Wrench-Feasible Workspace of the cable-driven parallel robots 2014 ,		4
12	Collision-Free Workspace of 3-RPR Planar Parallel Mechanism via Interval Analysis 2014 , 327-334		3
11	Workspace analysis of 5-PRUR parallel mechanisms (3T2R). <i>Robotics and Computer-Integrated Manufacturing</i> , 2012 , 28, 437-448	9.2	14
10	Singularity analysis of 3T2R parallel mechanisms using Grassmann-Cayley algebra and Grassmann geometry. <i>Mechanism and Machine Theory</i> , 2012 , 52, 326-340	4	33
9	SINGULARITY ANALYSIS OF THE 4 RUU PARALLEL MANIPULATOR USING GRASSMANN-CAYLEY ALGEBRA. <i>Transactions of the Canadian Society for Mechanical Engineering</i> , 2011 , 35, 515-528	1.1	3
8	GEOMETRIC ANALYSIS OF THE KINEMATIC SENSITIVITY OF PLANAR PARALLEL MECHANISMS. <i>Transactions of the Canadian Society for Mechanical Engineering</i> , 2011 , 35, 477-490	1.1	13

7	Kinematic analysis of 5-RPUR (3T2R) parallel mechanisms. <i>Meccanica</i> , 2011 , 46, 131-146	2.1	25
6	Singularity analysis of 5-RPUR parallel mechanisms (3T2R). <i>International Journal of Advanced Manufacturing Technology</i> , 2011 , 57, 1107-1121	3.2	16
5	Forward kinematic problem of 5-RPUR parallel mechanisms (3T2R) with identical limb structures. <i>Mechanism and Machine Theory</i> , 2011 , 46, 945-959	4	31
4	Parallel Mechanisms of the Multipteron Family: Kinematic Architectures and Benchmarking. <i>Proceedings - IEEE International Conference on Robotics and Automation</i> , 2007 ,		35
3	Dynamic modeling and design of controller for the 2-DoF serial chain actuated by a cable-driven robot based on feedback linearization. <i>Proceedings of the Institution of Mechanical Engineers, Part C: Journal of Mechanical Engineering Science</i> ,095440622110279	1.3	1
2	Experimental study on the control of a suspended cable-driven parallel robot for object tracking purpose. <i>Robotica</i> ,1-15	2.1	0
1	The synergy of the multi-modal MPC and Q-learning approach for the navigation of a three-wheeled omnidirectional robot based on the dynamic model with obstacle collision avoidance purposes. <i>Proceedings of the Institution of Mechanical Engineers, Part C: Journal of Mechanical Engineering Science</i> ,095440622210954	1.3	