

# Carlos Aguilar-Avelar

## List of Publications by Year in descending order

Source: <https://exaly.com/author-pdf/247109/publications.pdf>

Version: 2024-02-01

22  
papers

338  
citations

932766

10  
h-index

839053

18  
g-index

27  
all docs

27  
docs citations

27  
times ranked

375  
citing authors

| #  | ARTICLE  | IF  | CITATIONS |
|----|--|-----|-----------|
| 1  | Motion Control of Underactuated Mechanical Systems. Intelligent Systems, Control and Automation: Science and Engineering, 2018, , .  | 0.3 | 59        |
| 2  | Adaptive Neural Network Control for the Trajectory Tracking of the Furuta Pendulum. IEEE Transactions on Cybernetics, 2016, 46, 3439-3452.   | 6.2 | 49        |
| 3  | Observer based nonlinear control design for glucose regulation in type 1 diabetic patients: An LMI approach. Biomedical Signal Processing and Control, 2019, 47, 7-15.   | 3.5 | 42        |
| 4  | New Feedback Linearization-Based Control for Arm Trajectory Tracking of the Furuta Pendulum. IEEE/ASME Transactions on Mechatronics, 2016, 21, 638-648.  | 3.7 | 34        |
| 5  | A composite controller for trajectory tracking applied to the Furuta pendulum. ISA Transactions, 2015, 57, 286-294.  | 3.1 | 33        |
| 6  | Two adaptive control strategies for trajectory tracking of the inertia wheel pendulum: neural networks <i>vis-à-vis</i> model regressor. Intelligent Automation and Soft Computing, 2017, 23, 63-73.               | 1.6 | 18        |
| 7  | A <sc>matlab</sc>-based identification procedure applied to a two-degrees-of-freedom robot manipulator for engineering students. International Journal of Electrical Engineering and Education, 2017, 54, 319-340. | 0.4 | 16        |
| 8  | High-Throughput Automated Microscopy of Circulating Tumor Cells. Scientific Reports, 2019, 9, 13766.   | 1.6 | 14        |
| 9  | Effects of nonlinear friction compensation in the inertia wheel pendulum. Journal of Mechanical Science and Technology, 2017, 31, 4425-4433.   | 0.7 | 12        |
| 10 | Automated ELISA On-Chip for the Detection of Anti-SARS-CoV-2 Antibodies. Sensors, 2021, 21, 6785.  | 2.1 | 12        |
| 11 | Characterization of a novel automated microfiltration device for the efficient isolation and analysis of circulating tumor cells from clinical blood samples. Scientific Reports, 2020, 10, 7543.                  | 1.6 | 9         |
| 12 | A feedback linearization controller for trajectory tracking of the Furuta pendulum. , 2014, , .  |     | 6         |
| 13 | On trajectory tracking control of the inertia wheel pendulum. , 2014, , .  |     | 5         |
| 14 | Identification of Underactuated Mechanical Systems. Intelligent Systems, Control and Automation: Science and Engineering, 2018, , 27-49.   | 0.3 | 5         |
| 15 | Feedback Linearization Control of the Furuta Pendulum. Intelligent Systems, Control and Automation: Science and Engineering, 2018, , 69-92.  | 0.3 | 5         |
| 16 | Tracking of periodic oscillations in an underactuated system via adaptive neural networks. Journal of Low Frequency Noise Vibration and Active Control, 2018, 37, 128-143.   | 1.3 | 4         |
| 17 | A MRAC Principle for a Single-Link Electrically Driven Robot with Parameter Uncertainties. Complexity, 2017, 2017, 1-13.   | 0.9 | 3         |
| 18 | Fully Embedded Flow Control Device for Microfluidic Applications. IEEE Latin America Transactions, 2019, 18, 446-454.  | 1.2 | 1         |

| #  | ARTICLE  | IF  | CITATIONS |
|----|--|-----|-----------|
| 19 | Discussion on Generalizations and Further Research. Intelligent Systems, Control and Automation: Science and Engineering, 2018, , 177-187. | 0.3 | 1         |
| 20 | Composite Control of the Furuta Pendulum. Intelligent Systems, Control and Automation: Science and Engineering, 2018, , 51-68.             | 0.3 | 1         |
| 21 | Adaptive Control of the IWP. Intelligent Systems, Control and Automation: Science and Engineering, 2018, , 159-176.                        | 0.3 | 1         |
| 22 | Fully Embedded Flow Control Device for Microfluidic Applications. IEEE Latin America Transactions, 2020, 18, 446-454.                      | 1.2 | 0         |