

Christine Chevallereau

List of Publications by Year in descending order

Source: <https://exaly.com/author-pdf/3319550/publications.pdf>

Version: 2024-02-01

64
papers

1,834
citations

516215

16
h-index

395343

33
g-index

67
all docs

67
docs citations

67
times ranked

1044
citing authors

#	ARTICLE	IF	CITATIONS
1	Identification and Control of a 3-X Cable-Driven Manipulator Inspired From the Bird's Neck. Journal of Mechanisms and Robotics, 2022, 14, .	1.5	7
2	Motion Strategies for a Cobot in a Context of Intermittent Haptic Interface. Journal of Mechanisms and Robotics, 2022, 14, .	1.5	1
3	Kinematic and Static Analysis of a Cable-Driven 2-X Tensegrity Manipulator for Two Actuation Strategies. Springer Proceedings in Advanced Robotics, 2022, , 149-159.	0.9	1
4	Design and Optimization of a Planar Biped Leg Based on Direct Drive Linear Actuators. Mathematical Problems in Engineering, 2022, 2022, 1-15.	0.6	0
5	Safety in a Human Robot Interactive: Application to Haptic Perception. Lecture Notes in Computer Science, 2020, , 562-574.	1.0	4
6	Optimal Design of Tensegrity Mechanisms Used in a Bird Neck Model. Mechanisms and Machine Science, 2019, , 365-375.	0.3	4
7	Dynamic modeling and control of a tensegrity manipulator mimicking a bird neck. Mechanisms and Machine Science, 2019, , 2087-2097.	0.3	5
8	Walking Stability of a Variable Length Inverted Pendulum Controlled with Virtual Constraints. International Journal of Humanoid Robotics, 2019, 16, 1950040.	0.6	5
9	Virtual Constraints and Hybrid Zero Dynamics for Realizing Underactuated Bipedal Locomotion. , 2019, , 1045-1075.		4
10	An essential model for generating walking motions for humanoid robots. Robotics and Autonomous Systems, 2019, 112, 229-243.	3.0	12
11	Dynamic Analysis and Control of an Antagonistically Actuated Tensegrity Mechanism. CISM International Centre for Mechanical Sciences, Courses and Lectures, 2019, , 481-490.	0.3	6
12	Preliminary Survey of Backdrivable Linear Actuators for Humanoid Robots. CISM International Centre for Mechanical Sciences, Courses and Lectures, 2019, , 304-313.	0.3	4
13	Study of the Walking Efficiency of a Human with a Cane. CISM International Centre for Mechanical Sciences, Courses and Lectures, 2019, , 370-379.	0.3	0
14	Toward optimal mapping of human dual-arm motion to humanoid motion for tasks involving contact with the environment. International Journal of Advanced Robotic Systems, 2018, 15, 172988141875737.	1.3	3
15	Human to humanoid motion conversion for dual-arm manipulation tasks. Robotica, 2018, 36, 1167-1187.	1.3	10
16	Self-synchronization and self-stabilization of 3D bipedal walking gaits. Robotics and Autonomous Systems, 2018, 100, 43-60.	3.0	12
17	Self-Synchronization and Self-Stabilization of Walking Gaits Modeled by the Three-Dimensional LIP Model. IEEE Robotics and Automation Letters, 2018, 3, 3332-3339.	3.3	7
18	Orbital stabilization of an underactuated bipedal gait via nonlinear H_{∞} control using measurement feedback. Autonomous Robots, 2017, 41, 1277-1295.	3.2	9

#	ARTICLE	IF	CITATIONS
19	Morphological self stabilization of locomotion gaits: illustration on a few examples from bio-inspired locomotion. <i>Bioinspiration and Biomimetics</i> , 2017, 12, 046006.	1.5	1
20	Symmetry in legged locomotion: a new method for designing stable periodic gaits. <i>Autonomous Robots</i> , 2017, 41, 1119-1142.	3.2	25
21	Virtual Constraints and Hybrid Zero Dynamics for Realizing Underactuated Bipedal Locomotion. , 2017, , 1-31.		8
22	Robust stabilization of a fully actuated 3D bipedal locomotion via nonlinear H ∞ -control under unilateral constraints. , 2016, , .		2
23	A Top-Down and Bottom-Up Visual Attention Model for Humanoid Object Approaching and Obstacle Avoidance. , 2016, , .		1
24	Grounding humanoid visually guided walking: From action-independent to action-oriented knowledge. <i>Information Sciences</i> , 2016, 352-353, 79-97.	4.0	7
25	Nonlinear orbital ∞ -stabilization of underactuated mechanical systems with unilateral constraints. , 2015, , .		2
26	Arm swing effects on walking bipedal gaits composed of impact, single and double support phases. <i>Robotics and Autonomous Systems</i> , 2015, 66, 104-115.	3.0	15
27	Underwater navigation based on passive electric sense: New perspectives for underwater docking. <i>International Journal of Robotics Research</i> , 2015, 34, 1228-1250.	5.8	39
28	Self-stabilization of 3D walking via vertical oscillations of the hip. , 2015, , .		7
29	Restricted discrete invariance and self-synchronization for stable walking of bipedal robots. , 2015, , .		11
30	Finite time tracking of a fully actuated biped robot with pre-specified settling time: A second order sliding mode synthesis. , 2014, , .		9
31	Computational morphology for a soft micro air vehicle in hovering flight. , 2014, , .		1
32	Stable walking control of a 3D biped robot with foot rotation. <i>Robotica</i> , 2014, 32, 551-570.	1.3	10
33	Models, feedback control, and open problems of 3D bipedal robotic walking. <i>Automatica</i> , 2014, 50, 1955-1988.	3.0	236
34	Continuous second order sliding mode based robust finite time tracking of a fully actuated biped robot. , 2014, , .		4
35	Electric Sensor-Based Control of Underwater Robot Groups. <i>IEEE Transactions on Robotics</i> , 2014, 30, 604-618.	7.3	17
36	Underwater Reflex Navigation in Confined Environment Based on Electric Sense. <i>IEEE Transactions on Robotics</i> , 2013, 29, 945-956.	7.3	40

#	ARTICLE	IF	CITATIONS
37	Environment reconstruction and navigation with electric sense based on a Kalman filter. International Journal of Robotics Research, 2013, 32, 172-188.	5.8	35
38	ESTIMATION OF THE TRUNK ATTITUDE OF A HUMANOID BY DATA FUSION OF INERTIAL SENSORS AND JOINT ENCODERS. , 2013, , .		7
39	Underwater electro-navigation in the dark. , 2012, , .		13
40	Dynamic motion imitation of two articulated systems using nonlinear time scaling of joint trajectories. , 2012, , .		8
41	From stable walking to steering of a 3D bipedal robot with passive point feet. Robotica, 2012, 30, 1119-1130.	1.3	48
42	Arms Swing Effects on a Walking Planar Biped. , 2012, , .		3
43	Walking and steering control for a 3D biped robot considering ground contact and stability. Robotics and Autonomous Systems, 2012, 60, 962-977.	3.0	16
44	Modelling and Trajectory Planning for a Four Legged Walking Robot with High Payload. Lecture Notes in Computer Science, 2012, , 552-561.	1.0	2
45	ON PASSIVE MOTION OF THE ARMS FOR A WALKING PLANAR BIPED. , 2012, , 335-342.		1
46	Finite Time Stabilization of a Perturbed Double Integrator"Part I: Continuous Sliding Mode-Based Output Feedback Synthesis. IEEE Transactions on Automatic Control, 2011, 56, 614-618.	3.6	126
47	Human-Like Walking: Optimal Motion of a Bipedal Robot With Toe-Rotation Motion. IEEE/ASME Transactions on Mechatronics, 2011, 16, 310-320.	3.7	66
48	Stability analysis and time-varying walking control for an under-actuated planar biped robot. Robotics and Autonomous Systems, 2011, 59, 444-456.	3.0	19
49	3D Bipedal Robotic Walking: Models, Feedback Control, and Open Problems. IFAC Postprint Volumes IPPV / International Federation of Automatic Control, 2010, 43, 505-532.	0.4	74
50	Design of a walking cyclic gait with single support phases and impacts for the locomotor system of a thirteen-link 3D biped using the parametric optimization. Multibody System Dynamics, 2010, 23, 33-56.	1.7	51
51	Steering of a 3D bipedal robot with an underactuated ankle. , 2010, , .		9
52	Underwater robot navigation around a sphere using electrolocation sense and Kalman filter. , 2010, , .		26
53	Distribution of Forces Between Synergistics and Antagonistics Muscles Using an Optimization Criterion Depending on Muscle Contraction Behavior. Journal of Biomechanical Engineering, 2010, 132, 041009.	0.6	17
54	Stability of time-varying control for an underactuated biped robot based on choice of controlled outputs. , 2010, , .		2

#	ARTICLE	IF	CITATIONS
55	A new control law for a 3D biped robot based on regulation of the zero moment point and joint path. , 2010, , .		4
56	A penalty-based approach for contact forces computation in bipedal robots. , 2009, , .		6
57	Choice of output for time-variant walking control for a five-link underactuated planar biped robot. , 2009, , .		3
58	HZD-based control of a five-link underactuated 3D bipedal robot. , 2008, , .		20
59	Stable Bipedal Walking With Foot Rotation Through Direct Regulation of the Zero Moment Point. IEEE Transactions on Robotics, 2008, 24, 390-401.	7.3	84
60	Virtual quadruped: Mechanical design, control, simulation, and experimentation. Journal of Mathematical Sciences, 2007, 147, 6552-6568.	0.1	3
61	Online adaptation of reference trajectories for the control of walking systems. Robotics and Autonomous Systems, 2006, 54, 559-566.	3.0	35
62	Numerical and experimental study of the virtual quadrupedal walking robot-semiquad. Multibody System Dynamics, 2006, 16, 1-20.	1.7	18
63	Tracking a joint path for the walk of an underactuated biped. Robotica, 2004, 22, 15-28.	1.3	59
64	Effect of Circular Arc Feet on a Control Law for a Biped. , 0, , .		0