# Erol Sahin

## List of Publications by Citations



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|---|---|---|---|
| 47 papers | 1,701 citations | 18 h-index | 41 g-index |
| 54 ext. papers | 2,026 ext. citations | 2 avg, IF | 4.84 L-index |

| # | Paper | IF | Citations |
|---|---|---|---|
| 47 | Swarm Robotics: From Sources of Inspiration to Domains of Application. *Lecture Notes in Computer Science*, **2005**, 10-20 | 0.9 | 301 |
| 46 | Evolving Self-Organizing Behaviors for a Swarm-Bot. *Autonomous Robots*, **2004**, 17, 223-245 | 3 | 200 |
| 45 | Self-organized flocking in mobile robot swarms. *Swarm Intelligence*, **2008**, 2, 97-120 | 3 | 175 |
| 44 | Goal emulation and planning in perceptual space using learned affordances. *Robotics and Autonomous Systems*, **2011**, 59, 580-595 | 3.5 | 56 |
| 43 | Evolving Aggregation Behaviors in a Swarm of Robots. *Lecture Notes in Computer Science*, **2003**, 865-874 | 0.9 | 54 |
| 42 | Steering self-organized robot flocks through externally guided individuals. *Neural Computing and Applications*, **2010**, 19, 849-865 | 4.8 | 52 |
| 41 | Probabilistic aggregation strategies in swarm robotic systems | | 51 |
| 40 | . *IEEE Transactions on Autonomous Mental Development*, **2015**, 7, 119-139 | | 48 |
| 39 | Vision-Based Detection and Distance Estimation of Micro Unmanned Aerial Vehicles. *Sensors*, **2015**, 15, 23805-46 | 3.8 | 47 |
| 38 | Traversability: A Case Study for Learning and Perceiving Affordances in Robots. *Adaptive Behavior*, **2010**, 18, 258-284 | 1.1 | 46 |
| 37 | Special issue on swarm robotics. *Swarm Intelligence*, **2008**, 2, 69-72 | 3 | 46 |
| 36 | Swarm Robotics. *Natural Computing Series*, **2008**, 87-100 | 2.5 | 40 |
| 35 | The learning and use of traversability affordance using range images on a mobile robot. *Proceedings - IEEE International Conference on Robotics and Automation*, **2007**, | | 30 |
| 34 | A Macroscopic Model for Self-organized Aggregation in Swarm Robotic Systems **2006**, 27-42 | | 29 |
| 33 | Modeling self-organized aggregation in swarm robotic systems **2009**, | | 21 |
| 32 | Self-discovery of motor primitives and learning grasp affordances **2012**, | | 20 |
| 31 | Verb concepts from affordances. *Interaction Studies*, **2014**, 15, 1-37 | 1.3 | 18 |

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|---|---|---|---|
| 30 | The learning of adjectives and nouns from affordance and appearance features. *Adaptive Behavior*, **2013**, 21, 437-451 | 1.1 | 16 |
| 29 | . *IEEE Transactions on Cognitive and Developmental Systems*, **2016**, 8, 42-59 | 3 | 14 |
| 28 | Curiosity-driven learning of traversability affordance on a mobile robot **2007**, | | 14 |
| 27 | Evolving aggregation behaviors for swarm robotic systems: a systematic case study | | 12 |
| 26 | From primitive behaviors to goal-directed behavior using affordances **2007**, | | 11 |
| 25 | Learning Affordances for Categorizing Objects and Their Properties **2010**, | | 10 |
| 24 | Going beyond the perception of affordances: Learning how to actualize them through behavioral parameters **2011**, | | 10 |
| 23 | Unsupervised learning of object affordances for planning in a mobile manipulation platform **2011**, | | 8 |
| 22 | Learning and using context on a humanoid robot using latent dirichlet allocation **2014**, | | 7 |
| 21 | Learning to grasp with parental scaffolding **2011**, | | 7 |
| 20 | Modeling Phase Transition in Self-organized Mobile Robot Flocks. *Lecture Notes in Computer Science*, **2008**, 108-119 | 0.9 | 7 |
| 19 | Co-learning nouns and adjectives **2013**, | | 6 |
| 18 | The pros and cons of flocking in the long-range migration of mobile robot swarms. *Theoretical Computer Science*, **2010**, 411, 2140-2154 | 1.1 | 6 |
| 17 | Using learned affordances for robotic behavior development **2008**, | | 6 |
| 16 | Learning Adjectives and Nouns from Affordances on the iCub Humanoid Robot. *Lecture Notes in Computer Science*, **2012**, 330-340 | 0.9 | 6 |
| 15 | Predicting future object states using learned affordances **2009**, | | 5 |
| 14 | Dispersion of a swarm of robots based on realistic wireless intensity signals **2007**, | | 5 |
| 13 | Designing Social Cues for Collaborative Robots **2020**, | | 5 |

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| 12 | Closed-loop primitives: A method to generate and recognize reaching actions from demonstration **2012**, | | 4 |
| 11 | The MACS Project: An Approach to Affordance-Inspired Robot Control **2008**, 173-210 | | 4 |
| 10 | Unsupervised learning of affordance relations on a humanoid robot **2009**, | | 3 |
| 9 | Area measurement of large closed regions with a mobile robot. *Autonomous Robots*, **2006**, 21, 255-266 | 3 | 3 |
| 8 | Development of a visual object localization module for mobile robots | | 3 |
| 7 | Integrating spatial concepts into a probabilistic concept web **2015**, | | 2 |
| 6 | Human and robotics hands grasping danger **2012**, | | 2 |
| 5 | PES: A System for Parallelized Fitness Evaluation of Evolutionary Methods. *Lecture Notes in Computer Science*, **2003**, 900-907 | 0.9 | 2 |
| 4 | Guiding a Robot Flock via Informed Robots **2009**, 215-225 | | 2 |
| 3 | ANTS 2010 special issue. *Swarm Intelligence*, **2011**, 5, 143-147 | 3 | 1 |
| 2 | Affordance prediction of hand tools using interactive perception **2012**, | | 1 |
| 1 | Towards an On-Line Neural Conditioning Model for Mobile Robots. *Lecture Notes in Computer Science*, **2001**, 524-530 | 0.9 | |