Chris Macnab

List of Publications by Year
in descending order

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31 papers	444 citations	933264 10 h-index	752573 20 g-index
32 all docs	32 docs citations	32 times ranked	396 citing authors

#	Article	IF	Citations
1	Robust adaptive control of a quadrotor helicopter. Mechatronics, 2011, 21, 927-938.	2.0	213
2	Application of neural networks for optimal-setpoint design and MPC control in biological wastewater treatment. Computers and Chemical Engineering, 2018, 115, 150-160.	2.0	61
3	The dynamic optimization approach to locomotion dynamics: human-like gaits from a minimally-constrained biped model. Advanced Robotics, 2013, 27, 845-859.	1.1	35
4	Neural-adaptive control using alternate weights. Neural Computing and Applications, 2011, 20, 211-221.	3.2	12
5	Design of a generalized predictive controller for a biological wastewater treatment plant. Water Science and Technology, 2016, 73, 1986-2006.	1.2	12
6	Using RBFs in a CMAC to prevent parameter drift in adaptive control. Neurocomputing, 2016, 205, 45-52.	3.5	12
7	Preventing bursting in approximate-adaptive control when using local basis functions. Fuzzy Sets and Systems, 2009, 160, 439-462.	1.6	11
8	Stable active running of a planar biped robot using Poincare map control. Advanced Robotics, 2014, 28, 231-244.	1.1	11
9	Near-optimal neural-network robot control with adaptive gravity compensation. Neurocomputing, 2020, 389, 83-92.	3.5	10
10	Improved Output Tracking of a Flexible-Joint Arm using Neural Networks. Neural Processing Letters, 2010, 32, 201-218.	2.0	9
11	Discrete-time weight updates in neural-adaptive control. Soft Computing, 2013, 17, 431-444.	2.1	8
12	SLIP-Based Control of Bipedal Walking Based on Two-Level Control Strategy. Robotica, 2020, 38, 1434-1449.	1.3	6
13	Hopping on Even Ground and Up Stairs with a Single Articulated Leg. Journal of Intelligent and Robotic Systems: Theory and Applications, 2008, 53, 331-358.	2.0	5
14	Generating efficient rigid biped running gaits with calculated take-off velocities. Robotica, 2011, 29, 627-640.	1.3	4
15	Compliant Leg Architectures and a Linear Control Strategy for the Stable Running of Planar Biped Robots. International Journal of Advanced Robotic Systems, 2013, 10, 320.	1.3	4
16	Creating a CMAC with overlapping basis functions in order to prevent weight drift. Soft Computing, 2017, 21, 4593-4600.	2.1	4
17	Preventing Overlearning in CMAC by Using a Short-Term Memory. International Journal of Fuzzy Systems, 2017, 19, 2020-2032.	2.3	3
18	Modifying CMAC adaptive control with weight smoothing in order to avoid overlearning and bursting. Neural Computing and Applications, 2019, 31, 2207-2216.	3.2	3

#	Article	IF	Citations
19	Stable fuzzy-adaptive control using an introspective algorithm. , 2012, , .		2
20	Neural-adaptive backstepping for flexible-joint robots with neither extra parameters, extra networks, nor robust terms. , 2017, , .		2
21	Arbitrary Symmetric Running Gait Generation for an Underactuated Biped Model. PLoS ONE, 2017, 12, e0170122.	1.1	2
22	Global optimum human-like gaits for an articulated one-legged hopper. , 2010, , .		1
23	Finding a near-optimal neural-adaptive control solution without increasing the training time. , 2017, , .		1
24	Control of a quadrotor helicopter using a stable introspective-CMAC adaptive control. , 2017, , .		1
25	Nonlinear adaptive control of a transcritical Organic Rankine Cycle. , 2017, , .		1
26	Bipedal running with nearly-passive flight phases. , 2008, , .		0
27	Hopping with Nearly-Passive Flight Phases. , 2008, , .		0
28	Force-force bilateral haptic control using adaptive backstepping with tuning functions. , 2010, , .		0
29	A novel adaptive controller using radial basis function neural network for the wind energy conversion system. , 2017, , .		0
30	Experimental evaluation of adaptive CMAC haptic control for teleoperation of compliant-joint manipulators. , 2017, , .		0
31	Stability for feedback loops containing complex algorithms. Soft Computing, 2020, 24, 7113-7124.	2.1	0