

# Pedro X La Hera

## List of Publications by Year in descending order

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Version: 2024-02-01

29  
papers

340  
citations

1163117

8  
h-index

888059

17  
g-index

29  
all docs

29  
docs citations

29  
times ranked

262  
citing authors

#	ARTICLE	IF	CITATIONS
1	Design, rapid manufacturing and modeling of a reduced-scale forwarder crane with closed kinematic chain. <i>Mechanics Based Design of Structures and Machines</i> , 2023, 51, 6748-6773.	4.7	3
2	A study case of Dynamic Motion Primitives as a motion planning method to automate the work of forestry cranes. <i>Computers and Electronics in Agriculture</i> , 2021, 183, 106037.	7.7	8
3	Simulation-based comparison between two crane-bunk systems for loading work when considering energy-optimal motion planning. <i>International Journal of Forest Engineering</i> , 2020, 31, 70-77.	0.8	3
4	Modelling Dynamics of a Log-Yard through Discrete-Event Mathematics. <i>Forests</i> , 2020, 11, 155.	2.1	4
5	Comparison of Alternative Pulpwood Inventory Strategies and Machine Systems at a Log-Yard Using Simulations. <i>Forests</i> , 2020, 11, 373.	2.1	1
6	What Do We Observe When We Equip a Forestry Crane with Motion Sensors?. <i>Croatian Journal of Forest Engineering</i> , 2019, 40, 259-280.	1.9	7
7	Advances in using robots in forestry operations. <i>Burleigh Dodds Series in Agricultural Science</i> , 2019, , 233-260.	0.2	5
8	Model-Based Development of Control Systems for Forestry Cranes. <i>Journal of Control Science and Engineering</i> , 2015, 2015, 1-15.	1.0	11
9	Path-Constrained Motion Analysis: An Algorithm to Understand Human Performance on Hydraulic Manipulators. <i>IEEE Transactions on Human-Machine Systems</i> , 2015, 45, 187-199.	3.5	13
10	Increasing the Level of Automation in the Forestry Logging Process with Crane Trajectory Planning and Control. <i>Journal of Field Robotics</i> , 2014, 31, 343-363.	6.0	61
11	A pilot user's prospective in mobile robotic telepresence system. , 2014, , .		2
12	Non-linear dynamics modelling description for simulating the behaviour of forestry cranes. <i>International Journal of Modelling, Identification and Control</i> , 2014, 21, 125.	0.2	9
13	Generating periodic motions for the butterfly robot. , 2013, , .		0
14	Electro-hydraulically actuated forestry manipulator: Modeling and Identification. , 2012, , .		7
15	Design of energy efficient walking gaits for a three-link planar biped walker with two unactuated degrees of freedom. , 2012, , .		6
16	Open-loop control experiments on driver assistance for crane forestry machines. , 2011, , .		9
17	Traversing from point-to-point along a straight line with a ballbot. <i>IFAC Postprint Volumes IPPV / International Federation of Automatic Control</i> , 2010, 43, 125-130.	0.4	1
18	Gait synthesis for a three-link planar biped walker with one actuator. , 2010, , .		1

#	ARTICLE	IF	CITATIONS
19	Parallel Elastic Actuators as a Control Tool for Preplanned Trajectories of Underactuated Mechanical Systems. International Journal of Robotics Research, 2010, 29, 1186-1198.	8.5	72
20	Steps in trajectory planning and controller design for a hydraulically driven crane with limited sensing. , 2010, , .		3
21	New approach for swinging up the Furuta pendulum: Theory and experiments. Mechatronics, 2009, 19, 1240-1250.	3.3	46
22	Shaping stable periodic motions of inertia wheel pendulum: theory and experiment. Asian Journal of Control, 2009, 11, 548-556.	3.0	21
23	Analysis of human-operated motions and trajectory replanning for kinematically redundant manipulators. , 2009, , .		5
24	Motion planning for humanoid robots based on virtual constraints extracted from recorded human movements. Intelligent Service Robotics, 2008, 1, 289-301.	2.6	8
25	How springs can help to stabilize motions of underactuated systems with weak actuators. , 2008, , .		1
26	Virtual environment teleoperation of a hydraulic forestry crane. , 2008, , .		20
27	Identification and Control of a Hydraulic Forestry Crane. IFAC Postprint Volumes IPPV / International Federation of Automatic Control, 2008, 41, 2306-2311.	0.4	8
28	Generating human-like motions for an underactuated three-link robot based on the virtual constraints approach. , 2007, , .		5
29	Achievable balancing motions for a humanoid robot. , 2007, , .		0