Mahsa A Golkar

List of Publications by Year in descending order

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1478505 1474206 11 106 9 6 citations h-index g-index papers 11 11 11 104 docs citations times ranked citing authors all docs

| # | Article | IF | CITATIONS |
|----|--|-----|-----------|
| 1 | A Novel Cross-Case Electric Vehicle Demand Modeling Based on 3D Convolutional Generative Adversarial Networks. IEEE Transactions on Power Systems, 2022, 37, 1173-1183. | 6.5 | 10 |
| 2 | Optimal participation of a virtual power plant in electricity market considering renewable energy: A deep learning-based approach. Sustainable Energy, Grids and Networks, 2021, 26, 100448. | 3.9 | 35 |
| 3 | EMG-Torque Dynamics Change With Contraction Bandwidth. IEEE Transactions on Neural Systems and Rehabilitation Engineering, 2018, 26, 807-816. | 4.9 | 7 |
| 4 | Measurement of Dynamic Joint Stiffness from Multiple Short Data Segments. IEEE Transactions on Neural Systems and Rehabilitation Engineering, 2017, 25, 925-934. | 4.9 | 12 |
| 5 | Physiological tremor increases when skeletal muscle is shortened: implications for fusimotor control. Journal of Physiology, 2017, 595, 7331-7346. | 2.9 | 13 |
| 6 | Linear Parameter Varying Identification of Dynamic Joint Stiffness during Time-Varying Voluntary Contractions. Frontiers in Computational Neuroscience, 2017, 11, 35. | 2.1 | 17 |
| 7 | Identification of time-varying dynamics of reflex EMG in the ankle plantarflexors during time-varying, isometric contractions., 2015, 2015, 6744-7. | | 2 |
| 8 | Closed-loop identification of the dynamic relation between surface EMG and torque at the human ankle. IFAC-PapersOnLine, 2015, 48, 263-268. | 0.9 | 5 |
| 9 | Methods for the Identification of Time-Varying Hammerstein Systems with Applications to the Study of Dynamic Joint Stiffness. IFAC-PapersOnLine, 2015, 48, 1023-1028. | 0.9 | 2 |
| 10 | Parametric Methods for Identification of Time-Invariant and Time-Varying Joint Stiffness Models. IFAC-PapersOnLine, 2015, 48, 1375-1380. | 0.9 | 3 |
| 11 | Convergence analysis and controller design for a team of mobile robots subject to measurement error. , $2011, \ldots$ | | 0 |