

Chun-Ta Chen

List of Publications by Year in descending order

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citing authors

#	ARTICLE	IF	CITATIONS
1	Hysteresis modeling and tracking control for a dual pneumatic artificial muscle system using Prandtl–Ishlinskii model. <i>Mechatronics</i> , 2015, 28, 35-45.	3.3	86
2	A hybrid strategy for the time- and energy-efficient trajectory planning of parallel platform manipulators. <i>Robotics and Computer-Integrated Manufacturing</i> , 2011, 27, 72-81.	9.9	43
3	Trajectory planning in parallel kinematic manipulators using a constrained multi-objective evolutionary algorithm. <i>Nonlinear Dynamics</i> , 2012, 67, 1669-1681.	5.2	38
4	Implementation of an Upper-Limb Exoskeleton Robot Driven by Pneumatic Muscle Actuators for Rehabilitation. <i>Actuators</i> , 2020, 9, 106.	2.3	31
5	Dynamic Modeling and Motion Control of a Cable-Driven Robotic Exoskeleton With Pneumatic Artificial Muscle Actuators. <i>IEEE Access</i> , 2020, 8, 149796-149807.	4.2	23
6	Reconfiguration of a parallel kinematic manipulator for the maximum dynamic load-carrying capacity. <i>Mechanism and Machine Theory</i> , 2012, 54, 62-75.	4.5	18
7	A Lagrangian Formulation in Terms of Quasi-Coordinates for the Inverse Dynamics of the General 6-6 Stewart Platform Manipulator. <i>JSME International Journal Series C-Mechanical Systems Machine Elements and Manufacturing</i> , 2003, 46, 1084-1090.	0.3	17
8	Optimal Path Programming of the Stewart Platform Manipulator Using the Boltzmann–Hamel–d'Alembert Dynamics Formulation Model. <i>Advanced Robotics</i> , 2008, 22, 705-730.	1.8	16
9	Trajectory planning of parallel kinematic manipulators for the maximum dynamic load-carrying capacity. <i>Meccanica</i> , 2016, 51, 1653-1674.	2.0	12
10	Force reflection in a pneumatic artificial muscle actuated haptic system. <i>Mechatronics</i> , 2019, 61, 37-48.	3.3	11
11	Singularity-free trajectory planning of platform-type parallel manipulators for minimum actuating effort and reactions. <i>Robotica</i> , 2008, 26, 371-384.	1.9	10
12	Hybrid approach for dynamic model identification of an electro-hydraulic parallel platform. <i>Nonlinear Dynamics</i> , 2012, 67, 695-711.	5.2	10
13	On Climbing Winding Stairs in an Open Mode for a New Robotic Wheelchair. <i>Advanced Robotics</i> , 2012, 26, 63-82.	1.8	8
14	Design and Implementation of a Robotic Hip Exoskeleton for Gait Rehabilitation. <i>Actuators</i> , 2021, 10, 212.	2.3	8
15	Reconfiguration for the Maximum Dynamic Wrench Capability of a Parallel Robot. <i>Applied Sciences (Switzerland)</i> , 2016, 6, 80.	2.5	5
16	The effects of ultrasonic vibration on mechanical properties of tungsten particle-reinforced copper-matrix composites. <i>Canadian Metallurgical Quarterly</i> , 2017, 56, 450-458.	1.2	3
17	Pneumatic Artificial Muscle-Driven Control Loading System (iFUZZY2017). <i>International Journal of Fuzzy Systems</i> , 2018, 20, 1779-1789.	4.0	3
18	Optimal reconfiguration of parallel manipulators for the maximum dynamic wrench capability. , 2013, , .		0