

Josefa Linares-Pérez

List of Publications by Year in descending order

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116
papers

1,636
citations

361045

20
h-index

360668

35
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116
all docs

116
docs citations

116
times ranked

462
citing authors

#	ARTICLE	IF	CITATIONS
1	Optimal state estimation for networked systems with random parameter matrices, correlated noises and delayed measurements. <i>International Journal of General Systems</i> , 2015, 44, 142-154.	1.2	101
2	Extended and unscented filtering algorithms using one-step randomly delayed observations. <i>Applied Mathematics and Computation</i> , 2007, 190, 1375-1393.	1.4	95
3	Distributed fusion filters from uncertain measured outputs in sensor networks with random packet losses. <i>Information Fusion</i> , 2017, 34, 70-79.	11.7	78
4	Unscented filtering algorithm using two-step randomly delayed observations in nonlinear systems. <i>Applied Mathematical Modelling</i> , 2009, 33, 3705-3717.	2.2	73
5	Networked distributed fusion estimation under uncertain outputs with random transmission delays, packet losses and multi-packet processing. <i>Signal Processing</i> , 2019, 156, 71-83.	2.1	68
6	Recursive estimators of signals from measurements with stochastic delays using covariance information. <i>Applied Mathematics and Computation</i> , 2005, 162, 65-79.	1.4	65
7	Information fusion algorithms for state estimation in multi-sensor systems with correlated missing measurements. <i>Applied Mathematics and Computation</i> , 2014, 226, 548-563.	1.4	65
8	Networked fusion estimation with multiple uncertainties and time-correlated channel noise. <i>Information Fusion</i> , 2020, 54, 161-171.	11.7	55
9	Fusion estimation using measured outputs with random parameter matrices subject to random delays and packet dropouts. <i>Signal Processing</i> , 2016, 127, 12-23.	2.1	51
10	Signal estimation with multiple delayed sensors using covariance information. , 2010, 20, 528-540.		44
11	Optimal linear filter design for systems with correlation in the measurement matrices and noises: recursive algorithm and applications. <i>International Journal of Systems Science</i> , 2014, 45, 1548-1562.	3.7	44
12	A new approach to distributed fusion filtering for networked systems with random parameter matrices and correlated noises. <i>Information Fusion</i> , 2019, 45, 324-332.	11.7	44
13	Distributed fusion estimation in networked systems with uncertain observations and Markovian random delays. <i>Signal Processing</i> , 2015, 106, 114-122.	2.1	33
14	Linear estimation for discrete-time systems in the presence of time-correlated disturbances and uncertain observations. <i>IEEE Transactions on Automatic Control</i> , 1994, 39, 1636-1638.	3.6	28
15	Linear recursive discrete-time estimators using covariance information under uncertain observations. <i>Signal Processing</i> , 2003, 83, 1553-1559.	2.1	28
16	Distributed and centralized fusion estimation from multiple sensors with Markovian delays. <i>Applied Mathematics and Computation</i> , 2012, 219, 2932-2948.	1.4	28
17	New design of estimators using covariance information with uncertain observations in linear discrete-time systems. <i>Applied Mathematics and Computation</i> , 2003, 135, 429-441.	1.4	26
18	Least-squares linear filtering using observations coming from multiple sensors with one- or two-step random delay. <i>Signal Processing</i> , 2009, 89, 2045-2052.	2.1	25

#	ARTICLE	IF	CITATIONS
19	New distributed fusion filtering algorithm based on covariances over sensor networks with random packet dropouts. International Journal of Systems Science, 2017, 48, 1805-1817.	3.7	24
20	Linear smoothing for discrete-time systems in the presence of correlated disturbances and uncertain observations. IEEE Transactions on Automatic Control, 1995, 40, 1486-1488.	3.6	21
21	Second-order polynomial estimators from uncertain observations using covariance information. Applied Mathematics and Computation, 2003, 143, 319-338.	1.4	21
22	Different approaches for state filtering in nonlinear systems with uncertain observations. Applied Mathematics and Computation, 2007, 187, 708-724.	1.4	21
23	Covariance-based estimation algorithms in networked systems with mixed uncertainties in the observations. Signal Processing, 2014, 94, 163-173.	2.1	21
24	Centralized, distributed and sequential fusion estimation from uncertain outputs with correlation between sensor noises and signal. International Journal of General Systems, 2019, 48, 713-737.	1.2	20
25	Signal estimation based on covariance information from observations featuring correlated uncertainty and coming from multiple sensors. Signal Processing, 2008, 88, 2998-3006.	2.1	18
26	Optimal Fusion Filtering in Multisensor Stochastic Systems with Missing Measurements and Correlated Noises. Mathematical Problems in Engineering, 2013, 2013, 1-14.	0.6	18
27	Linear and quadratic estimation using uncertain observations from multiple sensors with correlated uncertainty. Signal Processing, 2011, 91, 330-337.	2.1	17
28	Least squared estimation for distributed parameter systems with uncertain observations: Part 1: linear prediction and filtering. , 1998, 14, 11-18.		16
29	Linear estimation from uncertain observations with white plus coloured noises using covariance information. , 2003, 13, 552-568.		16
30	Recursive estimation of discrete-time signals from nonlinear randomly delayed observations. Computers and Mathematics With Applications, 2009, 58, 1160-1168.	1.4	16
31	Linear estimation based on covariances for networked systems featuring sensor correlated random delays. International Journal of Systems Science, 2013, 44, 1233-1244.	3.7	16
32	Quadratic Estimation of Multivariate Signals from Randomly Delayed Measurements*. Multidimensional Systems and Signal Processing, 2005, 16, 417-438.	1.7	14
33	A New Estimation Algorithm from Measurements with Multiple-Step Random Delays and Packet Dropouts. Mathematical Problems in Engineering, 2010, 2010, 1-18.	0.6	14
34	Least-squares linear estimators using measurements transmitted by different sensors with packet dropouts. , 2012, 22, 1118-1125.		14
35	Networked Fusion Filtering from Outputs with Stochastic Uncertainties and Correlated Random Transmission Delays. Sensors, 2016, 16, 847.	2.1	14
36	Estimation from a multisensor environment for systems with multiple packet dropouts and correlated measurement noises. Applied Mathematical Modelling, 2017, 45, 802-812.	2.2	14

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37	Covariance-based fusion filtering for networked systems with random transmission delays and non-consecutive losses. <i>International Journal of General Systems</i> , 2017, 46, 752-771.	1.2	14
38	Optimal Fusion Estimation with Multi-Step Random Delays and Losses in Transmission. <i>Sensors</i> , 2017, 17, 1151.	2.1	14
39	Polynomial Filtering With Uncertain Observations in Stochastic Linear Systems. <i>International Journal of Modelling and Simulation</i> , 2003, 23, 22-28.	2.3	13
40	Linear and quadratic least-squares estimation using measurements with correlated one-step random delay. , 2008, 18, 450-464.		13
41	Quadratic estimation problem in discrete-time stochastic systems with random parameter matrices. <i>Applied Mathematics and Computation</i> , 2016, 273, 308-320.	1.4	13
42	Centralized filtering and smoothing algorithms from outputs with random parameter matrices transmitted through uncertain communication channels. , 2019, 85, 77-85.		13
43	Fixed-point smoothing with non-independent uncertainty using covariance information. <i>International Journal of Systems Science</i> , 2003, 34, 439-452.	3.7	11
44	New recursive estimators from correlated interrupted observations using covariance information. <i>International Journal of Systems Science</i> , 2005, 36, 617-629.	3.7	11
45	Fusion Estimation from Multisensor Observations with Multiplicative Noises and Correlated Random Delays in Transmission. <i>Mathematics</i> , 2017, 5, 45.	1.1	11
46	Least-Squares Linear Smoothers from Randomly Delayed Observations with Correlation in the Delay. <i>IEICE Transactions on Fundamentals of Electronics, Communications and Computer Sciences</i> , 2006, E89-A, 486-493.	0.2	11
47	Fixed-interval smoothing problem from uncertain observations with correlated signal and noise. <i>Applied Mathematics and Computation</i> , 2004, 154, 239-255.	1.4	10
48	Fixed-interval smoothing algorithm based on covariances with correlation in the uncertainty. , 2005, 15, 207-221.		10
49	Recursive fixed-point smoothing algorithm from covariances based on uncertain observations with correlation in the uncertainty. <i>Applied Mathematics and Computation</i> , 2008, 203, 243-251.	1.4	10
50	Signal estimation with nonlinear uncertain observations using covariance information. <i>Journal of Statistical Computation and Simulation</i> , 2009, 79, 55-66.	0.7	10
51	Nonlinear estimation applying an unscented transformation in systems with correlated uncertain observations. <i>Applied Mathematics and Computation</i> , 2011, 217, 7998-8009.	1.4	10
52	A Two-Phase Distributed Filtering Algorithm for Networked Uncertain Systems with Fading Measurements under Deception Attacks. <i>Sensors</i> , 2020, 20, 6445.	2.1	10
53	Unscented Filtering from Delayed Observations with Correlated Noises. <i>Mathematical Problems in Engineering</i> , 2009, 2009, 1-9.	0.6	9
54	Recursive least-squares quadratic smoothing from measurements with packet dropouts. <i>Signal Processing</i> , 2012, 92, 931-938.	2.1	9

#	ARTICLE	IF	CITATIONS
55	Covariance-Based Estimation from Multisensor Delayed Measurements with Random Parameter Matrices and Correlated Noises. <i>Mathematical Problems in Engineering</i> , 2014, 2014, 1-13.	0.6	9
56	Chandrasekhar-type filter for a wide-sense stationary signal from uncertain observations using covariance information. <i>Applied Mathematics and Computation</i> , 2004, 151, 315-325.	1.4	8
57	A general smoothing equation for signal estimation using randomly delayed observations in the correlated signal-noise case. , 2006, 16, 369-388.		7
58	Derivation of linear estimation algorithms from measurements affected by multiplicative and additive noises. <i>Journal of Computational and Applied Mathematics</i> , 2010, 234, 794-804.	1.1	7
59	Distributed Fusion Filtering in Networked Systems with Random Measurement Matrices and Correlated Noises. <i>Discrete Dynamics in Nature and Society</i> , 2015, 2015, 1-10.	0.5	7
60	Centralized Fusion Approach to the Estimation Problem with Multi-Packet Processing under Uncertainty in Outputs and Transmissions. <i>Sensors</i> , 2018, 18, 2697.	2.1	7
61	Least-squares estimators for systems with stochastic sensor gain degradation, correlated measurement noises and delays in transmission modelled by Markov chains. <i>International Journal of Systems Science</i> , 2020, 51, 731-745.	3.7	7
62	Estimation for discrete-time systems with multiple packet dropouts using covariance information. <i>Mathematical and Computer Modelling</i> , 2011, 54, 2277-2286.	2.0	6
63	Distributed fusion estimation from measurements with correlated random parameter matrices and noise correlation. <i>International Journal of Computer Mathematics</i> , 2020, 97, 95-108.	1.0	6
64	Derivation of fixed-interval smoothing algorithm using covariance information in distributed parameter systems. <i>Applied Mathematics and Computation</i> , 2006, 176, 662-672.	1.4	5
65	Design of a fixed-interval smoother using covariance information based on the innovations approach in linear discrete-time stochastic systems. <i>Applied Mathematical Modelling</i> , 2006, 30, 406-417.	2.2	5
66	Suboptimal estimation of signals from uncertain observations using approximations of mixtures. , 2007, 17, 4-16.		5
67	Least-squares Polynomial Estimation from Observations Featuring Correlated Random Delays. <i>Methodology and Computing in Applied Probability</i> , 2010, 12, 491-509.	0.7	5
68	Least-squares linear estimation of signals from observations with Markovian delays. <i>Journal of Computational and Applied Mathematics</i> , 2011, 236, 234-242.	1.1	5
69	Distributed Fusion Estimation with Sensor Gain Degradation and Markovian Delays. <i>Mathematics</i> , 2020, 8, 1948.	1.1	5
70	An innovation approach to the smoothing problem from uncertain observations with correlated signal and noise. <i>Mathematical Methods in the Applied Sciences</i> , 2005, 28, 1569-1584.	1.2	4
71	Least-squares $\hat{1}/2$ th-order polynomial estimation of signals from observations affected by non-independent uncertainty. <i>Applied Mathematics and Computation</i> , 2006, 176, 642-653.	1.4	4
72	Filtering and prediction from uncertain observations with correlated signal and noise via mixture approximations. <i>Signal Processing</i> , 2007, 87, 970-982.	2.1	4

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73	Design of RLS Wiener fixed-lag smoother using covariance information in linear discrete stochastic systems. Applied Mathematical Modelling, 2008, 32, 1338-1349.	2.2	4
74	Design of RLS Wiener estimators from randomly delayed observations in linear discrete-time stochastic systems. Applied Mathematics and Computation, 2010, 217, 3801-3815.	1.4	4
75	Least-Squares Filtering Algorithm in Sensor Networks with Noise Correlation and Multiple Random Failures in Transmission. Mathematical Problems in Engineering, 2017, 2017, 1-9.	0.6	4
76	Design of recursive Wiener fixed-point smoothers based on innovations approach in linear discrete-time stochastic systems. Applied Mathematics and Computation, 2005, 165, 731-747.	1.4	3
77	Filtering of images corrupted by multiplicative and white plus coloured additive noises using covariance information. Mathematical and Computer Modelling, 2008, 47, 298-311.	2.0	3
78	Design of quadratic estimators using covariance information in linear discrete-time stochastic systems. Journal of Time Series Analysis, 2008, 29, 501-512.	0.7	3
79	Filtering in Generalized Signal-Dependent Noise Model Using Covariance Information. IEICE Transactions on Fundamentals of Electronics, Communications and Computer Sciences, 2008, E91-A, 809-817.	0.2	3
80	Derivation of centralized and distributed filters using covariance information. Computational Statistics and Data Analysis, 2011, 55, 312-323.	0.7	3
81	Covariance-Based Estimation for Clustered Sensor Networks Subject to Random Deception Attacks. Sensors, 2019, 19, 3112.	2.1	3
82	Distributed fusion filtering for multi-sensor systems with correlated random transition and measurement matrices. International Journal of Computer Mathematics, 2020, 97, 263-274.	1.0	3
83	Fixed-Lag Smoothing Algorithm under Non-independent Uncertainty. IEICE Transactions on Fundamentals of Electronics, Communications and Computer Sciences, 2005, E88-A, 988-995.	0.2	3
84	Centralized fusion quadratic estimators in multi-sensor systems with correlated missing measurements. Applied Mathematical Sciences, 0, 7, 2795-2813.	0.0	3
85	Quadratic estimation from uncertain observations with white plus coloured noises using covariance information. Applied Mathematics and Computation, 2004, 155, 65-79.	1.4	2
86	Signal polynomial smoothing from correlated interrupted observations based on covariances. Mathematical Methods in the Applied Sciences, 2007, 30, 1645-1665.	1.2	2
87	Design of fixed-lag smoother using covariance information based on innovations approach in linear discrete-time stochastic systems. Applied Mathematics and Computation, 2007, 193, 162-174.	1.4	2
88	Polynomial fixed-point smoothing of uncertainly observed signals based on covariances. International Journal of Systems Science, 2008, 39, 207-216.	3.7	2
89	RLS Wiener estimators from observations with multiple and random delays in linear discrete-time stochastic systems. Applied Mathematics and Computation, 2013, 225, 184-194.	1.4	2
90	Distributed estimation based on covariances under network-induced phenomena described by random measurement matrices. International Journal of General Systems, 2016, 45, 486-501.	1.2	2

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91	Covariance-based least-squares filtering algorithm under Markovian measurement delays. <i>International Journal of Computer Mathematics</i> , 2020, 97, 40-50.	1.0	2
92	Distributed Fusion Estimation in Network Systems Subject to Random Delays and Deception Attacks. <i>Mathematics</i> , 2022, 10, 662.	1.1	2
93	Least mean-squared error polynomial estimation in systems with uncertain observations. , 0, , .		1
94	Estimation from uncertain observations in distributed parameter systems using covariance information. , 0, , .		1
95	Chandrasekhar-type recursive Wiener filter using covariance information in linear discrete-time wide-sense stationary stochastic systems. <i>IFAC Postprint Volumes IPPV / International Federation of Automatic Control</i> , 2004, 37, 753-758.	0.4	1
96	Linear estimation using covariance information in distributed parameter systems with non-independent uncertainty. <i>Signal Processing</i> , 2006, 86, 3012-3020.	2.1	1
97	Design of RLS fixed-lag smoother using covariance information in linear discrete stochastic systems. <i>Applied Mathematical Modelling</i> , 2010, 34, 1093-1106.	2.2	1
98	Recursive smoothing algorithms for the estimation of signals from uncertain observations via mixture approximations. <i>International Journal of Systems Science</i> , 2010, 41, 647-656.	3.7	1
99	Quadratic extended filtering in nonlinear systems with uncertain observations. <i>Applied Mathematical Sciences</i> , 0, 8, 157-172.	0.0	1
100	Least-squares quadratic estimators from non-independent uncertain observations with coloured noise. , 0, , .		0
101	Recursive fixed-interval smoother with correlated signal and noise in presence of uncertain observations. , 0, , .		0
102	On the estimation of signals transmitted in multichannel from Chandrasekhar recursions. , 0, , .		0
103	Signal filtering algorithms in continuous-time systems with uncertain observations. , 0, , .		0
104	Fixed-interval smoother from randomly delayed observations. , 0, , .		0
105	Signal Estimation from Observations Affected by Random Delays and White plus Coloured Noises. <i>Applied Numerical Analysis and Computational Mathematics</i> , 2004, 1, 495-506.	0.6	0
106	General expression of the least-squares linear smoother using covariance information under uncertain observations. , 0, , .		0
107	Recursive filtering algorithm to estimate images observed by signal-dependent colored noise. , 2007, , .		0
108	New filtering algorithm using observations with one or two-step random delay. , 2007, , .		0

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109	Signal estimation from uncertain observations coming from multiple sensors. , 2007, , .		0
110	Linear least-squares estimation based on covariances from multiple correlated uncertain observations. IFAC Postprint Volumes IPPV / International Federation of Automatic Control, 2008, 41, 3677-3682.	0.4	0
111	Design of Quadratic Estimators using Covariance Information in Linear Discrete-Time Stochastic Systems. IFAC Postprint Volumes IPPV / International Federation of Automatic Control, 2008, 41, 14496-14501.	0.4	0
112	Estimation in Linear Systems Featuring Correlated Uncertain Observations Coming from Multiple Sensors. , 2009, , .		0
113	Unscented Filtering Algorithm for Discrete-Time Systems with Uncertain Observations and State-Dependent Noise. , 0, , .		0
114	Quadratic Filtering Algorithm Based on Covariances Using Correlated Uncertain Observations Coming from Different Sensors. ISRN Applied Mathematics, 2011, 2011, 1-18.	0.5	0
115	Recursive Estimation Algorithm Based on Covariances for Uncertainly Observed Signals Correlated with Noise. IEICE Transactions on Fundamentals of Electronics, Communications and Computer Sciences, 2008, E91-A, 1706-1712.	0.2	0
116	RLS Wiener Predictor with Uncertain Observations in Linear Discrete-Time Stochastic Systems. Journal of Signal and Information Processing, 2011, 02, 152-158.	0.8	0