

Hongjun Yu

List of Publications by Year in descending order

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Version: 2024-02-01

15
papers

91
citations

1683354

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h-index

1372195

10
g-index

15
all docs

15
docs citations

15
times ranked

83
citing authors

#	ARTICLE	IF	CITATIONS
1	Formation control for multi-robot systems with collision avoidance. International Journal of Control, 2019, 92, 2223-2234.	1.2	20
2	Robot formation control in stealth mode with scalable team size. International Journal of Control, 2016, 89, 2155-2168.	1.2	17
3	Scalable formation control in stealth with limited sensing range. International Journal of Robust and Nonlinear Control, 2017, 27, 410-433.	2.1	17
4	A New Approach of Formation Control for Multi-Agent Systems With Environmental Changes. IEEE Transactions on Circuits and Systems I: Regular Papers, 2021, 68, 3449-3459.	3.5	8
5	Event-Triggered Probability-Driven Adaptive Formation Control for Multiple Elliptical Agents. IEEE Transactions on Systems, Man, and Cybernetics: Systems, 2022, 52, 645-654.	5.9	7
6	Probability-triggered formation control with adaptive roles. International Journal of Control, 2020, 93, 1989-2000.	1.2	6
7	Steady formation analysis on multi-robot systems. Journal of Control and Decision, 2017, 4, 12-31.	0.7	5
8	Flocking and topology manipulation based on space partitioning. Robotics and Autonomous Systems, 2020, 124, 103328.	3.0	5
9	Formation control of arbitrary shape with no communication. , 2016, , .		2
10	Coordinated collision avoidance for multi-vehicle systems based on collision time. IET Control Theory and Applications, 2021, 15, 1439-1450.	1.2	2
11	A Direct Approach of Path Planning Using Environmental Contours. Journal of Intelligent and Robotic Systems: Theory and Applications, 2021, 101, 1.	2.0	1
12	Steering Control and Path Planning of Two-Wheel Vehicle with Hazard Avoidance. , 2021, , .		1
13	Collision-free path control in contest environment using circular geometric attributes. , 2017, , .		0
14	Enabling Energy Efficient Data Ferrying. , 2018, , .		0
15	Stochastic control and time scheduling for irregular robots. Journal of the Franklin Institute, 2021, 358, 3678-3700.	1.9	0