

# Zhi-Jun Fu

## List of Publications by Year in descending order

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Version: 2024-02-01

11  
papers

134  
citations

1307594

7  
h-index

1588992

8  
g-index

11  
all docs

11  
docs citations

11  
times ranked

110  
citing authors

#	ARTICLE	IF	CITATIONS
1	Robust on-line nonlinear systems identification using multilayer dynamic neural networks with two-time scales. <i>Neurocomputing</i> , 2013, 113, 16-26.	5.9	34
2	Nonlinear Systems Identification and Control Via Dynamic Multitime Scales Neural Networks. <i>IEEE Transactions on Neural Networks and Learning Systems</i> , 2013, 24, 1814-1823.	11.3	31
3	Robust adaptive nonlinear observer design via multi-time scales neural network. <i>Neurocomputing</i> , 2016, 190, 217-225.	5.9	15
4	Online Adaptive Optimal Control of Vehicle Active Suspension Systems Using Single-Network Approximate Dynamic Programming. <i>Mathematical Problems in Engineering</i> , 2017, 2017, 1-9.	1.1	15
5	<i>H<sup>∞</sup></i> optimal control of vehicle active suspension systems in two time scales. <i>Automatika</i> , 2021, 62, 284-292.	2.0	13
6	Indirect adaptive control of nonlinear system via dynamic multilayer neural networks with multi-time scales. <i>International Journal of Adaptive Control and Signal Processing</i> , 2015, 29, 505-523.	4.1	11
7	Adaptive optimal control of unknown nonlinear systems with different time scales. <i>Neurocomputing</i> , 2017, 238, 179-190.	5.9	11
8	Adaptive Nonlinear Tire-Road Friction Force Estimation for Vehicular Systems Based on a Novel Differentiable Friction Model. <i>Mathematical Problems in Engineering</i> , 2015, 2015, 1-7.	1.1	2
9	Model free adaptive optimal tracking controller design for AFS/DYC based integrated chassis control system. , 2017, , .		2
10	Adaptive nonlinear systems identification via dynamic multilayer neural networks with two-time scales. , 2013, , .		0
11	Corrigendum to "Adaptive Nonlinear Tire-Road Friction Force Estimation for Vehicular Systems Based on a Novel Differentiable Friction Model". <i>Mathematical Problems in Engineering</i> , 2015, 2015, 1-1.	1.1	0