

Siddharth Mayya

List of Publications by Year in descending order

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#	ARTICLE	IF	CITATIONS
1	A Resilient and Energy-Aware Task Allocation Framework for Heterogeneous Multirobot Systems. IEEE Transactions on Robotics, 2022, 38, 159-179.	10.3	25
2	Adaptive and Risk-Aware Target Tracking for Robot Teams With Heterogeneous Sensors. IEEE Robotics and Automation Letters, 2022, 7, 5615-5622.	5.1	5
3	The Robotarium: Automation of a Remotely Accessible, Multi-Robot Testbed. IEEE Robotics and Automation Letters, 2021, 6, 2922-2929.	5.1	8
4	Resilient Task Allocation in Heterogeneous Multi-Robot Systems. IEEE Robotics and Automation Letters, 2021, 6, 1327-1334.	5.1	24
5	A Set-Theoretic Approach to Multi-Task Execution and Prioritization. , 2020, , .		8
6	Adaptive Task Allocation for Heterogeneous Multi-Robot Teams with Evolving and Unknown Robot Capabilities. , 2020, , .		20
7	The Robotarium: Globally Impactful Opportunities, Challenges, and Lessons Learned in Remote-Access, Distributed Control of Multirobot Systems. IEEE Control Systems, 2020, 40, 26-44.	0.8	101
8	Voluntary Retreat for Decentralized Interference Reduction in Robot Swarms. , 2019, , .		11
9	Closed-loop task allocation in robot swarms using inter-robot encounters. Swarm Intelligence, 2019, 13, 115-143.	2.2	17
10	Decentralized Minimum-Energy Coverage Control for Time-Varying Density Functions. , 2019, , .		21
11	An Optimal Task Allocation Strategy for Heterogeneous Multi-Robot Systems. , 2019, , .		31
12	Non-Uniform Robot Densities in Vibration Driven Swarms Using Phase Separation Theory. , 2019, , .		10
13	A Study of a Class of Vibration-Driven Robots: Modeling, Analysis, Control and Design of the Brushbot. , 2019, , .		9
14	Localization in Densely Packed Swarms Using Interrobot Collisions as a Sensing Modality. IEEE Transactions on Robotics, 2019, 35, 21-34.	10.3	28
15	Safe open-loop strategies for handling intermittent communications in multi-robot systems. , 2017, , .		3
16	Collisions as Information Sources in Densely Packed Multi-Robot Systems Under Mean-Field Approximations. , 0, , .		10