Masahiro Sekimoto

List of Publications by Year
in descending order

31 papers	**275** citations	1307594 **7** h-index	1281871 **11** g-index
31 all docs	**31** docs citations	**31** times ranked	**137** citing authors

#	Article	IF	Citations
1	Natural resolution of ill-posedness of inverse kinematics for redundant robots: a challenge to Bernstein's degrees-of-freedom problem. Advanced Robotics, 2005, 19, 401-434.	1.8	117
2	Experimental Study on Reaching Movements of Robot Arms with Redundant DOFs Based upon Virtual Spring-Damper Hypothesis. , 2006, , .		25
3	Iterative Learning of Specified Motions in Task-Space for Redundant Multi-Joint Hand-Arm Robots. Proceedings - IEEE International Conference on Robotics and Automation, 2007, , .	0.0	22
4	A Riemannian-Geometry Approach for Control of Robotic Systems under Constraints. SICE Journal of Control Measurement and System Integration, 2009, 2, 107-116.	0.7	22
5	Modeling and Control of 2-D Grasping of an Object with Arbitrary Shape under Rolling Contact. SICE Journal of Control Measurement and System Integration, 2009, 2, 379-386.	0.7	11
6	Task-Space Iterative Learning for Redundant Robotic Systems: Existence of a Task-Space Control and Convergence of Learning. SICE Journal of Control Measurement and System Integration, 2008, 1, 312-319.	0.7	11
7	A natural redundancy-resolution for 3-D multi-joint reaching under the gravity effect. Journal of Field Robotics, 2005, 22, 607-623.	0.7	9
8	Skilled-motion plannings of multi-body systems based upon Riemannian distance. , 2008, , .		7
9	Experimental Study on Control Method for Robot Arms with Redundant Joints Based upon Virtual Spring-Damper Hypothesis. Journal of the Robotics Society of Japan, 2007, 25, 785-791.	0.1	7
10	Effect of Virtual Spring-Damper in Grasping and Object Manipulation of a Robotic Hand-Arm System. , 2006, , .		5
11	A Riemannian-Geometry Approach for Modeling and Control of Dynamics of Object Manipulation under Constraints. Journal of Robotics, 2009, 2009, 1-16.	0.9	5
12	A riemannian-geometry approach for dynamics and control of object manipulation under constraints. , 2009, , .		5
13	Basis-motion torque composition approach: Generation of motions with different velocity profiles among joints. , 2010, , .		5
14	Analysis of walking skill with trans-femoral prosthesis based on inertia-induced measure. , 2011, , .		5
15	Basis-motion torque composition approach: generation of feedforward inputs for control of multi-joint robots. , 2009, , .		3
16	Evaluation of gait with trans-femoral prosthesis based on Riemannian distance. , 2009, , .		3
17	Analysis of inertial motion in swing phase of human gait and its application to motion generation of transfemoral prosthesis. , 2014, , .		3
18	Diagonalization of Arm Kinematics by the Use of Bi-Articular Muscles. SICE Journal of Control Measurement and System Integration, 2011, 4, 114-119.	0.7	3

#	Article	IF	Citations
19	On iterative learning control for simultaneous force/position trajectory tracking by using a 5 D.O.F. robotic thumb under non-holonomic rolling constraints. , 2008, , .		2
20	Iterative Learning Control in Task-space for Robots with Redundant Joints. Journal of the Robotics Society of Japan, 2007, 25, 921-929.	0.1	2
21	Iterative Learning without Reinforcement or Reward for Multijoint Movements: A Revisit of Bernstein's DOF Problem on Dexterity. Journal of Robotics, 2010, 2010, 1-15.	0.9	1
22	Generation of feedforward torque by reuse of ILC torque for three-joint robot arm in gravity. , 2017, , .		1
23	Motion analysis of a multi-joint system with holonomic constraints using Riemannian distance. Advanced Robotics, 0, , 1-17.	1.8	1
24	A Riemannian-Geometric Approach for Intelligent Control and Fingertip Design of Multi-fingered Hands. Advanced Robotics, 2010, 24, 1345-1364.	1.8	0
25	Realization of turning a screw crank with less control inputs by using redundant degrees of freedom of a manipulator. , 2017, , .		0
26	Vibration analysis of elevator rope with vibration suppressors (Identification of flexural rigidity,) Tj ETQq0 0 0 rgBT /Overlock 10 Tf 50 46 21-00121-21-00121.	0.2	0
27	Endpoint Tracking Accuracy of a Redundant Manipulator Controlled in Task-Space Feedback during Reactions to External Forces. The Abstracts of the International Conference on Advanced Mechatronics Toward Evolutionary Fusion of IT and Mechatronics ICAM, 2015, 2015.6, 199-200.	0.0	0
28	Influence of Robot's Postures on Control-Valuable Errors and Endpoint Contact Forces during a Screw Crank Motion with Adaptation of Redundant Degrees of Freedom. The Proceedings of Conference of Hokuriku-Shinetsu Branch, 2019, 2019.56, A016.	0.0	0
29	Investigation into Adaptation of Redundant Degrees of Freedom Against Different Gripping Forces During a Screw Crank Motion. The Proceedings of Conference of Hokuriku-Shinetsu Branch, 2019, 2019.56, A015.	0.0	0
30	Examination of Inertial Properties Dependent on Mass Loading during Stair Ascending. The Proceedings of Conference of Hokuriku-Shinetsu Branch, 2019, 2019.56, A014.	0.0	0
31	Investigation of Inertial Properties of Human Walking with Wearable Devices. The Proceedings of Conference of Hokuriku-Shinetsu Branch, 2019, 2019.56, A013.	0.0	0