

# Anis Sahbani

## List of Publications by Year in descending order

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Version: 2024-02-01

22  
papers

905  
citations

1478505

6  
h-index

1281871

11  
g-index

24  
all docs

24  
docs citations

24  
times ranked

947  
citing authors

#	ARTICLE	IF	CITATIONS
1	An overview of 3D object grasp synthesis algorithms. Robotics and Autonomous Systems, 2012, 60, 326-336.	5.1	332
2	Robotic Exoskeletons: A Perspective for the Rehabilitation of Arm Coordination in Stroke Patients. Frontiers in Human Neuroscience, 2014, 8, 947.	2.0	124
3	A new strategy combining empirical and analytical approaches for grasping unknown 3D objects. Robotics and Autonomous Systems, 2010, 58, 497-507.	5.1	42
4	Constraining Upper Limb Synergies of Hemiparetic Patients Using a Robotic Exoskeleton in the Perspective of Neuro-Rehabilitation. IEEE Transactions on Neural Systems and Rehabilitation Engineering, 2012, 20, 247-257.	4.9	42
5	Dexterous manipulation planning using probabilistic roadmaps in continuous grasp subspaces. , 2007, , .		35
6	Learning the natural grasping component of an unknown object. , 2007, , .		22
7	A hybrid approach for grasping 3D objects. , 2009, , .		21
8	On computing robust n-finger force-closure grasps of 3D objects. , 2009, , .		20
9	A comanipulation device for orthopedic surgery that generates geometrical constraints with real-time registration on moving bones. , 2011, , .		11
10	Needle path planning for digital breast tomosynthesis biopsy. , 2010, , .		10
11	Fast Grasp Planning Using Cord Geometry. IEEE Transactions on Robotics, 2015, 31, 1393-1403.	10.3	7
12	A General Manipulation Task Planner. Springer Tracts in Advanced Robotics, 2004, , 311-327.	0.4	7
13	Changing human upper-limb synergies with an exoskeleton using viscous fields. , 2011, , .		6
14	Generic Motion Planner for Robot Multi-fingered Manipulation. Advanced Robotics, 2011, 25, 23-46.	1.8	5
15	A Sufficient Condition For Computing N-Finger Force-Closure Grasps of 3D Objects. , 2008, , .		4
16	Needle path planning for digital breast tomosynthesis biopsy using a heterogeneous model. , 2011, , .		4
17	Grasping objects localized from uncertain point cloud data. Robotics and Autonomous Systems, 2014, 62, 1742-1754.	5.1	4
18	A Global Approach for Dexterous Manipulation Planning Using Paths in n-fingers Grasp Subspace. , 2006, , .		3

#	ARTICLE	IF	CITATIONS
19	Needle Path Planning Method for Digital Breast Tomosynthesis Biopsy Based on Probabilistic Techniques. Lecture Notes in Computer Science, 2010, , 15-22.	1.3	3
20	Imposing joint kinematic constraints with an upper limb exoskeleton without constraining the end-point motion. , 2010, , .		1
21	A sufficient condition and a new quality criterion for force-closure grasps synthesis of 3D objects. , 2008, , .		0
22	Dexterous Manipulation Planning for an Anthropomorphic Hand. CISM International Centre for Mechanical Sciences, Courses and Lectures, 2013, , 241-248.	0.6	0