

Richard R Carrillo

List of Publications by Year in descending order

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19
papers

474
citations

840585

11
h-index

794469

19
g-index

21
all docs

21
docs citations

21
times ranked

417
citing authors

#	ARTICLE	IF	CITATIONS
1	On the Use of a Multimodal Optimizer for Fitting Neuron Models. Application to the Cerebellar Granule Cell. <i>Frontiers in Neuroinformatics</i> , 2021, 15, 663797.	1.3	3
2	A cerebellar-based solution to the nondeterministic time delay problem in robotic control. <i>Science Robotics</i> , 2021, 6, eabf2756.	9.9	22
3	Reconfigurable cyber-physical system for critical infrastructure protection in smart cities via smart video-surveillance. <i>Pattern Recognition Letters</i> , 2020, 140, 303-309.	2.6	19
4	Spike burst-pause dynamics of Purkinje cells regulate sensorimotor adaptation. <i>PLoS Computational Biology</i> , 2019, 15, e1006298.	1.5	20
5	A Metric for Evaluating Neural Input Representation in Supervised Learning Networks. <i>Frontiers in Neuroscience</i> , 2018, 12, 913.	1.4	5
6	Event- and Time-Driven Techniques Using Parallel CPU-GPU Co-processing for Spiking Neural Networks. <i>Frontiers in Neuroinformatics</i> , 2017, 11, 7.	1.3	23
7	26th Annual Computational Neuroscience Meeting (CNS*2017): Part 2. <i>BMC Neuroscience</i> , 2017, 18, .	0.8	7
8	Distributed Cerebellar Motor Learning: A Spike-Timing-Dependent Plasticity Model. <i>Frontiers in Computational Neuroscience</i> , 2016, 10, 17.	1.2	37
9	A Spiking Neural Simulator Integrating Event-Driven and Time-Driven Computation Schemes Using Parallel CPU-GPU Co-Processing: A Case Study. <i>IEEE Transactions on Neural Networks and Learning Systems</i> , 2015, 26, 1567-1574.	7.2	46
10	Fast convergence of learning requires plasticity between inferior olive and deep cerebellar nuclei in a manipulation task: a closed-loop robotic simulation. <i>Frontiers in Computational Neuroscience</i> , 2014, 8, 97.	1.2	39
11	Adaptive Robotic Control Driven by a Versatile Spiking Cerebellar Network. <i>PLoS ONE</i> , 2014, 9, e112265.	1.1	70
12	Integrated neural and robotic simulations. Simulation of cerebellar neurobiological substrate for an object-oriented dynamic model abstraction process. <i>Robotics and Autonomous Systems</i> , 2014, 62, 1702-1716.	3.0	13
13	CPU-GPU hybrid platform for efficient spiking neural-network simulation. <i>BMC Neuroscience</i> , 2013, 14, .	0.8	1
14	Cerebellar Input Configuration Toward Object Model Abstraction in Manipulation Tasks. <i>IEEE Transactions on Neural Networks</i> , 2011, 22, 1321-1328.	4.8	34
15	Event and Time Driven Hybrid Simulation of Spiking Neural Networks. <i>Lecture Notes in Computer Science</i> , 2011, , 554-561.	1.0	9
16	Context Separability Mediated by the Granular Layer in a Spiking Cerebellum Model for Robot Control. <i>Lecture Notes in Computer Science</i> , 2011, , 537-546.	1.0	0
17	Event-driven simulation of cerebellar granule cells. <i>BioSystems</i> , 2008, 94, 10-17.	0.9	9
18	A real-time spiking cerebellum model for learning robot control. <i>BioSystems</i> , 2008, 94, 18-27.	0.9	96

#	ARTICLE	IF	CITATIONS
19	Event-driven simulation of neural population synchronization facilitated by electrical coupling. BioSystems, 2007, 87, 275-280.	0.9	13