

Junho Choi

List of Publications by Year in descending order

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docs citations

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124
citing authors

#	ARTICLE	IF	CITATIONS
1	Development of a Planar Haptic Robot With Minimized Impedance. IEEE Transactions on Biomedical Engineering, 2021, 68, 1441-1449.	4.2	3
2	The speed of adaptation is dependent on the load type during target reaching by intact human subjects. Experimental Brain Research, 2021, 239, 3091-3104.	1.5	3
3	Design and Control of a Powered Lower Limb Orthosis Using a Cable-Differential Mechanism, COWALK-Mobile 2. IEEE Access, 2021, 9, 43775-43784.	4.2	4
4	The effect of pelvic movements of a gait training system for stroke patients: a single blind, randomized, parallel study. Journal of NeuroEngineering and Rehabilitation, 2021, 18, 185.	4.6	6
5	Effect of Pelvic Movement on Healthy Subjects During Gait Training Using a Gait Rehabilitation System. , 2018, 2018, 2475-2478.		3
6	A robotic orthosis with a cable-differential mechanism. , 2017, , .		3
7	A novel method for estimating external force: Simulation study with a 4-DOF robot manipulator. International Journal of Precision Engineering and Manufacturing, 2015, 16, 755-766.	2.2	14
8	Real-time gait phase detection and estimation of gait speed and ground slope for a robotic knee orthosis. , 2015, , .		8
9	Design and control of an exoskeleton system for gait rehabilitation capable of natural pelvic movement. , 2014, , .		12
10	A safe robot arm with safe joints and gravity compensator. International Journal of Control, Automation and Systems, 2013, 11, 362-368.	2.7	7
11	External force estimation using joint torque sensors and its application to impedance control of a robot manipulator. , 2013, , .		17
12	Development of Micro Hydraulic Actuator for force assistive wearable robot. , 2013, , .		3
13	External force estimation using joint torque sensors for a robot manipulator. , 2012, , .		13
14	A methodology to quantitatively evaluate the safety of a glazing robot. Applied Ergonomics, 2011, 42, 445-454.	3.1	12
15	A safe joint with a joint torque sensor. , 2011, , .		4