

CITATION REPORT

List of articles citing

Quasi-Static Assembly of Compliantly Supported Rigid Parts

DOI: 10.1115/1.3149634

Journal of Dynamic Systems, Measurement and Control, Transactions of the ASME, 1982, 104, 65-77.

Source: <https://exaly.com/paper-pdf/15617163/citation-report.pdf>

Version: 2024-04-27

This report has been generated based on the citations recorded by exaly.com for the above article. For the latest version of this publication list, visit the link given above.

The third column is the impact factor (IF) of the journal, and the fourth column is the number of citations of the article.

#	Paper	IF	Citations
665	.		4
664	Parallel coupled actuators for high performance force control: a micro-macro concept.		10
663	A 3-DOF flexure-based fixture for passive assembly of optical switches.		12
662	Robot programming. 1983 , 71, 821-841		164
661	Automatic Synthesis of Fine-Motion Strategies for Robots. 1984 , 3, 3-24		518
660	A preview approach to force control of robot manipulators. <i>Mechanism and Machine Theory</i> , 1985 , 20, 449-464	4	10
659	Compliance in robot manipulation. 1985 , 25, 5-12		1
658	Compliant control of robotic manipulators with resolved acceleration. 1985 ,		18
657	The mechanics of manipulation.		33
656	Sensory feedback structures for robots with supervised learning.		43
655	A framework for the economic evaluation of production system and product design alternatives for robot assembly. 1985 , 23, 197-207		25
654	Kinematics of workpart fixturing.		10
653	Kinematic analysis of workpart fixturing for flexible assembly with automatically reconfigurable fixtures. 1985 , 1, 86-94		250
652	Automatic grasp planning in the presence of uncertainty.		26
651	Modeling manufacturing grips and correlations with the design of robotic hands.		55
650	Robust compliant motion for manipulators, part I: The fundamental concepts of compliant motion. 1986 , 2, 83-92		234
649	Robot Systems Completely Based on Sensory Feedback. 1986 , IE-33, 105-109		13

648 References. **1986**, 33, 357-375

647 Synthesis of robot control for assembly processes. *Mechanism and Machine Theory*, **1986**, 21, 43-62 4 9

646 Contribution to synthesis of manipulator control. **1986**, 3, 71-103

645 Using Backprojections for Fine Motion Planning with Uncertainty. **1986**, 5, 19-45 161

644 Mechanics and Planning of Manipulator Pushing Operations. **1986**, 5, 53-71 300

643 Two robot arms in assembly. 4

642 The fundamental concepts of robust compliant motion for robot manipulators. 32

641 The synthesis of stable grasps in the plane. 25

640 Development of a position and force sensor for robotic applications. 1

639 Virtual internal model following control of robot arms. 25

638 Position-based impedance control - Achieving stability in practice. **1987**, 21

637 Mechanical Impedance Control of a Robot Arm by Virtual Internal Model Following Controller. **1987**, 20, 239-244 1

636 Closed-Loop Control of a Manipulator Arm Using a Wrist Force Sensor. **1987**, IE-34, 371-378 9

635 Eigenvalue assignment and performance index based force-position control with self-tuning for robotic manipulators. 6

634 Dynamics of a rigid body in frictional contact with rigid walls: Motion in two dimensions. 21

633 Force control of direct-drive manipulators for surface following. 12

632 Normal forms of stiffness and compliance matrices. **1987**, 3, 567-572 127

631 . 21

630	Problems and research issues associated with the hybrid control of force and displacement.	45
629	Constructing stable grasps in 3D.	34
628	Task oriented optimal grasping by multifingered robot hands.	2
627	An Investigation of the Insertability of Connectors in Printed Circuit Boards. 1987 , 36, 9-12	2
626	Two robot arms in assembly by using impulsive information. 1987 , 4, 585-603	2
625	Development of a novel intelligent robotic manipulator. 1987 , 7, 9-15	39
624	. 1988 , 4, 524-531	99
623	. 1988 , 4, 32-44	267
622	. 1988 , 4, 699-705	127
621	Design and implementation of a five axis robotic micromanipulator for inserting parts into precision collets. 1988 , 28, 131-139	1
620	A review of flexible fixturing systems for computer integrated manufacturing. 1988 , 1, 124-135	15
619	Technology for robotic mechanical assembly: Force-directed insertions. 1988 , 67, 23-34	11
618	.	19
617	.	17
616	.	5
615	.	2
614	.	9
613	A Three-Dimensional Assembly Task Quantification with Application to Machine Dexterity. 1988 , 7, 34-78	34

612	Automatic Grasp Planning in the Presence of Uncertainty. 1988 , 7, 3-17	387
611	The Karlsruhe Hand. 1988 , 21, 383-388	6
610	Planning Compliant Motion Strategies. 1989 , 8, 28-44	21
609	.	33
608	The Role of Sensor Directed, Model Based Control in Robotics.	
607	.	
606	.	10
605	A 2-DOF active compliant gripper for robotic applications. 1989 , 20, 315-328	3
604	. 1989 , 5, 47-52	12
603	. 1989 , 5, 30-46	255
602	Grasping and Coordinated Manipulation by a Multifingered Robot Hand. 1989 , 8, 33-50	196
601	Programmed compliance for error-correction in robotic assembly.	0
600	.	4
599	.	6
598	.	8
597	.	
596	.	0
595	Compliant gripper for precision robotic assembly.	1

594 Assembly Performance of a Robotic Vibratory Wrist. **1990**, 23, 605-608

593 ASSEMBLY PERFORMANCE OF A ROBOTIC VIBRATORY WRIST. **1990**, 605-608

592 Planning for Dexterous Manipulation with Sliding Contacts. **1990**, 9, 24-48

76

591 Development of a magnetically supported intelligent hand for automated precision assembly. **1990**, 5, 133-146

590 A Quantification of Machine Dexterity Applied to an Assembly Task. **1990**, 9, 49-62

23

589 . **1990**, 6, 473-482

81

588 . **1990**, 37, 1426-1431

587 . **1990**,

3

586 .

13

585 . **1990**, 6, 342-347

11

584 . **1990**,

83

583 Planning Multi-Step Error Detection and Recovery Strategies. **1990**, 9, 3-60

53

582 . **1990**,

8

581 .

580 .

21

579 .

2

578 .

7

577 .

3

576	.			6
575	.			46
574	An IJC Based Force-Position Control of a Robot ARM. 1991 , 24, 189-194			
573	Accommodation Based on the Compliant Robot Wrist With Six D.O.F. Displacement/Force Sensing Capability. 1991 , 24, 469-473			
572	Application of fuzzy reasoning to precision inserting operation. 1991 , 39, 205-214			4
571	Transient lateral motion of robots in part mating. <i>Robotics and Computer-Integrated Manufacturing</i> , 1991 , 8, 103-111		9.2	
570	Dynamic analysis of peg-in-hole insertion for manufacturing automation. 1991 , 10, 99-108			9
569	Spring equilibrator theory for static balancing of planar pantograph linkages. <i>Mechanism and Machine Theory</i> , 1991 , 26, 645-657		4	23
568	An action-based process model for dextrous multifinger hands. 1991 , 4, 201-219			3
567	Uncertainty and Compliance of Robot Manipulators with Applications to Task Feasibility. 1991 , 10, 200-213			25
566	.			10
565	.			12
564	.			36
563	.			6
562	.			2
561	.			6
560	.			3
559	.			

558	. 1991,			1
557	Magnetic Levitation Servo for Flexible Assembly Automation. 1992, 11, 329-345			18
556	.			21
555	Planar Quasi-static Motion Of A Lamina With Uncertain Contact Friction.			7
554	.			38
553	Randomization in Robot Tasks. 1992, 11, 399-436			25
552	Insertion Force Recognition by Modelling and Simulation of Assembly Systems with Accomodators. 1992, 25, 111-116			
551	A Model-based Generation Of Damping Control Law For Part-mat Ing.			2
550	Learning Task Strategies in Robotic Assembly Systems. <i>Robotica</i> , 1992, 10, 409-418	2.1		8
549	Virtual Wedging In Three Dimensional Peg Insertion Tasks.			4
548	.			4
547	. 1992, 8, 213-227			66
546	Virtual Wedging In Three Dimensional Peg Insertion Tasks.			1
545	.			2
544	.			
543	An Investigation Of Dextrous Manipulation Planning Using C-functions And Stability Functions.			3
542	.			6
541	A Discrete Event Controller Using Petri Nets Applied To Assembly.			11

540	.		
539	.		7
538	.		30
537	. 1992, 8, 176-185		220
536	.		33
535	An experimental investigation of object stiffness control using a multifingered hand. 1992, 10, 33-42		6
534	Robot manipulator control for hazardous waste-handling applications. 1992, 9, 215-250		36
533	Automatic grasp planning for multifingered robot hands. 1992, 3, 297-316		5
532	An aluminum salvage station for External Tanks of the Space Shuttle. 1993, 29, 379-397		
531	A fuzzy rule-based assembly algorithm for precision parts mating. 1993, 3, 433-450		14
530	Restraint analysis of assembly work carriers. <i>Robotics and Computer-Integrated Manufacturing</i> , 1993, 10, 257-265	9.2	9
529	Compliant motions and force/moment constraints in the presence of uncertainties. 1993, 17, 89-102		0
528	Guest editor's foreword special issue on computational robotics: The geometric theory of manipulation, planning, and control. 1993, 10, 91-101		2
527	Randomization for robot tasks: Using dynamic programming in the space of knowledge states. 1993, 10, 248-291		20
526	.		34
525	Intelligent manipulation of sliding operations with parallel two-fingered grippers.		5
524	. 1993, 9, 400-410		72
523	.		16

522	.	13
521	.	1
520	Task-level adaptation using a discrete event controller for robotic assembly.	5
519	.	5
518	.	
517	.	4
516	.	5
515	Robot programming by human demonstration: Subtask compliance controller identification.	9
514	An intelligent assembly algorithm for chamferless parts mating in an in-line continuous transfer system.	
513	A fuzzy intelligent organiser for control of robotic assembly operations.	
512	.	7
511	Microprocessors, Instrumentation and Control. 1993 , 11/1-11/69	
510	Simultaneous computation of robot kinematics and differential kinematics with automatic differentiation.	2
509	Development of model-based remote maintenance robot system. IV. A practical stiffness control method for redundant robot arm.	4
508	Quasi-dynamic manipulation of constrained object by robot fingers in assembly tasks.	4
507	Advanced graphics interfaces for telerobotic servicing and inspection.	4
506	Multiple-point contact with friction: Computing forces and motions in configuration space.	4
505	.	2

504	Robotic Peg-Hole Insertion Operations using a Six-Component Force Sensor. 1993 , 207, 289-306	23
503	The Motion of Planar, Compliantly Connected Rigid Bodies in Contact, With Applications to Automatic Fastening. 1993 , 12, 307-337	4
502	.	4
501	Tactile Image Sensors for Robot Assembly: Preprocessing and Control. 1993 , 26, 11-14	
500	Automatic Precision Assembly: Theory and Practice. 1993 , 26, 673-676	
499	Contact operations using an instrumented compliant wrist. 1993 , 403-419	3
498	A fuzzy expert organizer/robust control strategy for moving base robotic assembly operations.	
497	.	5
496	.	
495	.	2
494	.	4
493	On a Representation of Friction in Configuration Space. 1994 , 13, 240-271	78
492	Microprocessors, instrumentation and control. 1994 , 3/1-3/87	
491	Precise Robotic Chamferless Peg-Hole Insertion Operation Without Force Feedback and Remote Centre Compliance (RCC). 1994 , 208, 89-104	5
490	.	4
489	. 1994 , 14, 13-24	92
488	.	14
487	.	16

486	Vibration-Assisted Engagement for Parts Mating. 1994 , 43, 27-30		4
485	Application of fuzzy control to an inserting operation. 1994 , 66, 267-281		2
484	. 1994 , 41, 631-640		26
483	.		3
482	.		1
481	.		2
480	. 1994 , 10, 465-479		29
479	.		5
478	.		
477	.		8
476	.		10
475	A COMPLIANCE MEASURE FOR THE ALIGNMENT OF CYLINDRICAL PART FEATURES. 1994 , 26, 2-10		2
474	Mating of Rigid Parts by a Manipulator With Its Own Compliance. 1995 , 117, 240-247		4
473	The Discrete Event Control of Robotic Assembly Tasks. <i>Journal of Dynamic Systems, Measurement and Control, Transactions of the ASME</i> , 1995 , 117, 384-393	1.6	24
472	Fast robotic assembly with an active instrumented flexible wrist.		
471	.		1
470	A novel and practical strategy for the precise chamferless robotic peg hole insertion. <i>Robotica</i> , 1995 , 13, 29-35	2.1	5
469	Vibratory assembly of prismatic parts using neural networkbased positioning error estimation. <i>Robotica</i> , 1995 , 13, 185-193	2.1	3

468	Planning and sensitivity analysis of automated assembly processes with robots.		
467	Skillful control under uncertainty via direct reinforcement learning. 1995 , 15, 237-246		10
466	Fuzzy logic and position sensing for precision assembly. 1995 , 12, 135-146		6
465	Friction and part curvature in parallel- jaw grasping. 1995 , 12, 365-381		8
464	Fine motion planning through constraint network analysis.		6
463	A method for changing contact states for robotic assembly by using some local models in a multi-agent system.		4
462	A geometric simulator SimRep for testing the replanning approach toward assembly motions in the presence of uncertainties.		2
461	Modeling and simulation of the assembly of snap joints.		2
460	Understanding Action and Sensing by Designing Action-Based Sensors. 1995 , 14, 483-509		46
459	A neural network-based assembly algorithm for chamferless parts mating.		
458	Grasping and manipulation by arm/multifingered-hand mechanisms.		18
457	The Discrete Event Modeling and Trajectory Planning of Robotic Assembly Tasks. <i>Journal of Dynamic Systems, Measurement and Control, Transactions of the ASME</i> , 1995 , 117, 394-400	1.6	37
456	Kinematic evaluation of manipulator for peg-in-hole task.		2
455	Tele-manipulation system based on task-oriented virtual tool.		18
454	Evaluating the performance of robotic compliant tasks according to power consumption: approach and applications.		1
453	A modular approach for solving the peg-in-hole problem with a multifingered gripper.		7
452	Decentralized control of robots for dynamic coordination.		3
451	Parts orienting by push-aligning.		9

450	Peg-on-hole: a model based solution to peg and hole alignment.		38
449	Analysis of dynamic assembly using passive compliance.		3
448	Controlling the contact compliance via internal forces on objects held by dual-arm robots.		2
447	Dynamic simulation of assembly processes.		6
446	Fine Motion Strategies for Robotic Peg-Hole Insertion. 1995 , 209, 429-448		8
445	. 1995 , 11, 229-246		31
444	Detection of kinematic constraint from search motion of a robot using link weights of a neural network.		
443	Decentralized coordinated motion control of manipulators with vision and force sensors.		11
442	. 1995 , 11, 545-557		26
441	. 1995 , 11, 36-49		15
440	Dynamically reconfigurable robotic system. Assembly of new type cells as a dual-peg-in-hole problem.		0
439	Fuzzy reinforcement compliance control for robotic assembly.		2
438	Robot Grasp Synthesis Algorithms: A Survey. 1996 , 15, 230-266		421
437	Task primitives for the discrete event modeling and control of 6-DOF assembly tasks. 1996 , 12, 280-289		29
436	A model and strategy analysis of the peg-hole system in the search process associated with robotic assembly operations without chamfers. <i>Robotica</i> , 1996 , 14, 647-658	2.1	4
435	Design of an Orthogonal Compliance for Polygonal Peg Insertion. 1996 , 118, 106		9
434	Virtual Wedging in Three-Dimensional Peg Insertion Tasks. 1996 , 118, 99		12
433	Conditions for Initiating the Translation of a Rigid Cylinder in a Tube. 1996 , 118, 235-242		2

432	The unsupervised learning of assembly using discrete event control.	2
431	A Comparison of Delay and Bandwidth Limitations in Teleoperation. 1996 , 29, 5709-5714	3
430	Robotic Assembly Operation Strategy Investigation Without Force Sensors Through the Research on Contact Point Location and Range of Peg Movement. 1996 , 210, 471-485	5
429	On the mechanics of elastomer shear pads for remote center compliance (RCC).	3
428	Fuzzy rule base optimization of a compliant wrist sensor for robotic assembly. 1996 , 13, 475-487	2
427	Analysis of a planar 3 degree-of-freedom adjustable compliance mechanism. 1996 , 10, 286	1
426	A new adaptive fuzzy controller using the parallel structure of fuzzy controller and its application. 1996 , 81, 205-226	21
425	Constrained accelerated-feedback control for robot motion. <i>Robotics and Computer-Integrated Manufacturing</i> , 1996 , 12, 251-259	9.2
424	The structured design of an industrial robot controller. 1996 , 4, 239-249	20
423	Assembly processes with robotic systems. 1996 , 19, 151-166	7
422	Specification of force-controlled actions in the "task frame formalism"-a synthesis. 1996 , 12, 581-589	150
421	When quasistatic jamming is impossible.	6
420	Active compliance control of a PUMA 560 robot.	22
419	Twin-head six-axis force sensors. 1996 , 12, 146-154	16
418	Practical Force-Motion Models for Sliding Manipulation. 1996 , 15, 557-572	134
417	Skill representation and acquisition of compliant motions using a teach device.	18
416	Stability of rigid-body dynamics with sliding frictional contacts.	2
415	RCC characteristics of planar/spherical three degree of freedom parallel mechanisms with joint compliances.	2

414	Hydraulically powered dissimilar teleoperated system controller design.		1
413	Monitoring contact using clustering and discriminant functions.		8
412	A high-speed method of detecting contact-state transitions and its implementation in a task-coordinate manipulation system.		1
411	Compliant contact models for rigid body collisions.		20
410	Impedance restrictions on independent finger grippers. 1997 , 13, 617-622		
409	On the Spatial Compliance of Robotic Manipulators. <i>Journal of Dynamic Systems, Measurement and Control, Transactions of the ASME</i> , 1997 , 119, 839-844	1.6	17
408	A reconfigurable holonomic omnidirectional mobile bed with unified seating (RHOMBUS) for bedridden patients.		21
407	Drum roll: increasing bandwidth through passive impedance modulation.		9
406	Evaluation of task-performance of a manipulator for a peg-in-hole task.		5
405	Control algorithm for the scrollic gripper based on intrinsic sensory information. 1997 , 12, 15-33		
404	Identification of the mechanical impedance at the human finger tip. 1997 , 119, 109-14		131
403	Force control command synthesis for assembly using a discrete event framework.		5
402	Performance limits and stiffness control of multifingered hands. 1997 , 91-102		2
401	New properties of the remote center of compliance.		0
400	A Connection Design Methodology for Automated Assembly and the Framing of Buildings. 1997 , 119, 37-49		
399	Measurement of parts deformation and misalignment by using a visual sensing system.		1
398	A spatial impedance controller for robotic manipulation. 1997 , 13, 546-556		48
397	3D analysis of contact in peg-hole insertion.		0

396	Stability of frictional contact in constrained rigid-body dynamics. 1997 , 13, 230-236	21
395	A linear space of admittance control laws that guarantees force-assembly with friction. 1997 , 13, 656-667	10
394	On the dynamic behavior of a wrist force sensor for robots.	2
393	Manipulation task primitives for composing robot skills.	36
392	The concept of "difficulty" in mating operations.	
391	Hybrid dynamic modeling and control of constrained manipulation systems. 1997 , 4, 27-44	9
390	Passive Compliance from Robot Limbs and its Usefulness in Robotic Automation. 1997 , 20, 1-21	8
389	Adaptive discrete event control for assembly: Theory and industrial implementation. 1997 , 21, 323-339	5
388	Learning the peg-into-hole assembly operation with a connectionist reinforcement technique. 1997 , 33, 101-109	13
387	A reverse static force analysis of a special planar three-spring system. <i>Mechanism and Machine Theory</i> , 1997 , 32, 609-615	4 7
386	A Concept of an Intelligent Fuzzy Control for Assembly Robot. 1998 , 47, 9-12	1
385	Classification and methodologies for orientation and stacking of parts based on internal features. 1998 , 17, 455-475	3
384	The bounds and realization of spatial stiffnesses achieved with simple springs connected in parallel. 1998 , 14, 466-475	89
383	Robotic insertion of dual pegs based on force feedback signals.	
382	Passive compliance versus active compliance in robot-based automated assembly systems. 1998 , 25, 48-57	58
381	Strategy investigation of precise robotic assembly operations with symmetric regular polyhedral objects. 1998 , 212, 571-589	10
380	A Complete Algorithm for Fixture Loading. 1998 , 17, 1214-1224	5
379	An Exploration of Nonprehensile Two-Palm Manipulation. 1998 , 17, 485-503	46

378	Parallel-Coupled Micro-Macro Actuators. 1998 , 17, 773-791	40
377	Task Constraints Specification via Optimized Hyperellipsoids. 1998 , 17, 294-304	
376	Docking control of holonomic omnidirectional vehicles with applications to a hybrid wheelchair/bed system.	8
375	Posing Polygonal Objects in the Plane by Pushing. 1998 , 17, 70-88	49
374	Dynamical Simulation of Planar Systems With Changing Contacts Using Configuration Spaces. 1998 , 120, 181-187	12
373	Development of variable RCC and its application.	7
372	Analysis of frictional contact models for dynamic simulation.	5
371	Dynamics Modelling and Simulation of SPDM Operations Part II: SPDM Handling the IEA Battery. 1998 , 31, 165-170	1
370	Development of a Robot Assembly Task Planning System. 1998 , 31, 23-28	
369	Implementation of the Robot Workcell in the Production of the Lead/Acid Batteries. 1998 , 31, 111-115	
368	Integrating Robot Task Planning into Off-Line Programming Systems. 1998 , 31, 343-348	
367	Control of two industrial robots for parts mating.	7
366	Modeling and controlling variation in mechanical assemblies using state transition models.	4
365	Virtual lesson and its application to virtual calligraphy system.	60
364	Force-responsive robotic assembly of transmission components.	20
363	A new space used in sensor-less manipulation.	1
362	Mechanically Implementable Accommodation Matrices for Passive Force Control. 1999 , 18, 830-844	5
361	Properties of the Grasp Stiffness Matrix and Conservative Control Strategies. 1999 , 18, 159-167	31

360	Design-specific approach to design for assembly (DFA) for complex mechanical assemblies. 1999 , 15, 869-881	29
359	A vision based error-corrective algorithm for flexible parts assembly.	3
358	Automation of the lid assembly operation in the lead/acid automotive batteries manufacturing process.	0
357	Using a compliant wrist for a teleoperated robot.	1
356	A target-approachable force-guided control with adaptive accommodation for complex assembly. 1999 , 13, 886-904	
355	A hybrid systems approach to force-guided robotic assemblies.	8
354	Modeling and controlling variation propagation in mechanical assemblies using state transition models. 1999 , 15, 124-140	160
353	A perturbation/correlation method for force guided robot assembly. 1999 , 15, 764-773	14
352	Manipulators. 1999 ,	
351	An architecture for robot assembly task planning. 1999 , 32, 79-84	
350	Visual sensor-based measurement for deformable peg-in-hole tasks.	1
349	Parts Mating Aided by Constant-Amplitude Sinusoidal Motions. 1999 , 121, 802-810	1
348	A force/torque sensor-less realization of fast and dexterous tasks with a parallel robot.	0
347	Attractive regions in the environment [motion planning].	0
346	Results of Human-in-the-Loop Testing of the Force/Moment Accommodation Feature using the Special Purpose Dexterous Manipulator Ground Test Bed. 2000 ,	1
345	Lorentz Magnetic Levitation for Haptic Interaction: Device Design, Performance, and Integration with Physical Simulations. 2000 , 19, 644-667	52
344	Experimental Validation of Contact Dynamics Simulation of Constrained Robotic Tasks. 2000 , 19, 1203-1217	27
343	Development of a new variable remote center compliance for assembly robots. 2000 , 14, 241-255	10

342	. 2000 , 16, 772-781	51
341	Combination of strategy investigation and utilization of sensor signals in robotic assembly. 2000 , 214, 657-669	2
340	RCC Characteristics of Planar/Spherical Three Degree-of-Freedom Parallel Mechanisms With Joint Compliances. 2000 , 122, 10-16	21
339	Stiffness analysis for effective peg-in/out-hole tasks using multi-fingered robot hands.	2
338	A reconfigurable parts feeder with an array of pins.	5
337	Flexible robot-assembly using a multi-sensory approach.	37
336	Human Safety Mechanisms of Human-Friendly Robots: Passive Viscoelastic Trunk and Passively Movable Base. 2000 , 19, 307-335	51
335	. 2000 , 5, 122-131	23
334	Human-machine cooperative telemanipulation with motion and force scaling using task-oriented virtual tool dynamics. 2000 , 16, 505-516	45
333	A flexible parts assembly algorithm based on a visual sensing system.	
332	Development of a new variable remote center compliance using stiffness adjusters.	2
331	.	5
330	A compliance device for flexible close tolerance assembly. 2001 , 28, 54-63	5
329	Search strategies for peg-in-hole assemblies with position uncertainty.	37
328	Task-based compliance planning for multifingered hands.	
327	Robotic Surface Finishing Processes: Modeling, Control, and Experiments. <i>Journal of Dynamic Systems, Measurement and Control, Transactions of the ASME</i> , 2001 , 123, 93-102	1.6 30
326	Experimental Evaluation of a New Variable Remote Center Compliance (VRCC).. 2001 , 44, 875-882	3
325	Inverse Static Analysis of a Planar System With Flexural Pivots. 2001 , 123, 43-50	13

324	Measurement of force sensory information for the automation of ultra-precision assembly tasks.		1
323	Contact localisation: a novel approach to intelligent robotic assembly.		1
322	Attractive regions formed by constraints in configuration space-attractive regions in motion region of a polygonal or a polyhedral part with a flat environment.		1
321	Automation of the car battery lid assembly operation. <i>Robotics and Computer-Integrated Manufacturing</i> , 2001 , 17, 435-446	9.2	1
320	A neural/fuzzy optimal process model for robotic part assembly. 2001 , 41, 1783-1794		12
319	Minimal realizations of spatial stiffnesses with parallel or serial mechanisms having concurrent axes. 2001 , 18, 135-146		22
318	Achieving a cooperative behavior in a dual-arm robot system via a modular control structure. 2001 , 18, 691-699		9
317	Multidirectional compliance and constraint for improved robotic deburring. Part 1: improved positioning. <i>Robotics and Computer-Integrated Manufacturing</i> , 2001 , 17, 277-286	9.2	7
316	Fundamentals and analysis of compliance characteristics for multifingered hands.		
315	Manipulation of a large object by multiple DR Helpers in cooperation with a human.		10
314	Planar parts-mating using structured compliance.		4
313	Task analysis of ultra-precision assembly processes for automation of human skills.		1
312	Manipulating Parts with an Array of Pins: A Method and a Machine. 2001 , 20, 808-818		15
311	Computing Wrench Cones for Planar Rigid Body Contact Tasks. 2002 , 21, 1053-1066		24
310	Sensor-based analysis of high-precision insertion tasks.		
309	Improving robotic assembly performance through autonomous exploration.		5
308	Spatial parts mating with fiction using structured compliance with compliance center.		1
307	Sufficient conditions used in admittance selection for planar force-guided assembly.		

306	Attractive regions formed by the environment in configuration space: The possibility of achieving high precision sensorless manipulation in production. 2002 , 40, 975-1002		9
305	Casting Manipulation. 2002 , 45, 267-274		6
304	A Multiple RCC Device for Polygonal Peg Insertion.. 2002 , 45, 306-315		5
303	A sensorless insertion strategy for rigid planar parts.		7
302	The Combination of Attractive Regions and Pre-images in Motion Planning. 2002 , 124, 341-350		1
301	Identification of Friction Coefficient for Constrained Robotic Tasks. <i>Journal of Dynamic Systems, Measurement and Control, Transactions of the ASME</i> , 2002 , 124, 529-538	1.6	1
300	FutureHome: An integrated construction automation approach. 2002 , 9, 55-66		22
299	Intelligent passive control in robotic assembly.		
298	Motion planning for disc-shaped robots pushing a polygonal object in the plane. 2002 , 18, 550-562		58
297	Measurement of force sensory information in ultraprecision assembly tasks. 2002 , 7, 186-189		6
296	The study of a passive accommodation device in robotic insertion processes. 2002 , 124, 261-266		10
295	Optimal control planning strategies with fuzzy entropy and sensor fusion for robotic part assembly tasks. 2002 , 42, 1335-1344		16
294	Catastrophe analysis of a planar system with flexural pivots. <i>Mechanism and Machine Theory</i> , 2002 , 37, 693-716	4	14
293	Sensor-based learning for practical planning of fine motions in robotics. 2002 , 145, 147-168		6
292	Constraint network analysis of 3-dimensional insertion tasks. 2002 , 13, 19-38		4
291	Design and Analysis of Remote Center of Compliance Structures. 2003 , 20, 415-427		25
290	Virtual prototyping of assembly components using process modeling. 2003 , 22, 16-27		18
289	Sufficient conditions for admittance to ensure planar force-assembly in multi-point frictionless contact.		

288	.	5
287	Sufficient conditions used in admittance selection for force-guided assembly of polygonal parts. 2003 , 19, 737-742	10
286	Micropeg manipulation with a compliant microgripper.	0
285	Dynamic analysis of assembly process with passive compliance for robot manipulators.	5
284	Two- and three-dimensional part orientation by sensor-less grasping and pushing actions: Use of the concept of 'attractive region in environment'. 2003 , 41, 3159-3184	11
283	Admittance selection for planar force-guided assembly for single-point contact with friction.	
282	Measurement method for compliance of vertical-multi-articulated robot application to 7-DOF robot PA-10.	3
281	Evolution of the NASA/DARPA Robonaut control system.	44
280	Spatial Compliant Motion of a Rigid Body Constrained by a Frictional Contact. 2003 , 22, 733-756	3
279	New predictive display method of motion and force information for network teleoperation without using virtual environment model.	3
278	Analysis of Flexible Insertion Assembly of Polygonal Pegs. 2003 , 46, 1130-1141	1
277	Food packing with intelligent robotic system.	
276	Admittance selection for force-guided assembly of polygonal parts despite friction. 2004 , 20, 817-829	7
275	Computation and analysis of natural compliance in fixturing and grasping arrangements. 2004 , 20, 651-667	11
274	Admittance selection for force-guided assembly of polyhedral parts in single-point contact. 2004 ,	0
273	Insertion of long peg into tandem shallow hole using search trajectory generation without force feedback. 2004 ,	10
272	An admittance design method for general spatial parts mating. 2004 ,	1
271	A guideline for specifying compliance in multi-fingered operations. 2004 , 21, 651-663	

270	Micro and Mesoscale Robotic Assembly. 2004 , 6, 52-71		85
269	Flat image recognition in the process of microdevice assembly. 2004 , 25, 107-118		53
268	Contact and jamming analysis for three dimensional dual peg-in-hole mechanism. <i>Mechanism and Machine Theory</i> , 2004 , 39, 477-499	4	13
267	Task-based compliance planning for multi-fingered robotic manipulations. 2004 , 18, 23-44		2
266	Force/Position Hybrid Control for Geometrically Constrained Tendon-Driven Flexible Joint Arm. 2004 , 37, 1467-1472		0
265	Novel visual sensing systems for overcoming occlusion in robotic assembly. 2005 , 25, 21-29		2
264	Design and Evaluation of a Robust Compliant Grasper Using Shape Deposition Manufacturing. 2005 , 1403		9
263	Design of a Piezoresistive Surface Micromachined Three-Axis Force Transducer for Microassembly. 2005 , 507		2
262	A new robotic assembly modeling and trajectory planning method using synchronized Petri nets. 2005 , 26, 420-426		8
261	Optimization of damping control parameters for cycle time reduction in clutch assembly. 2005 ,		10
260	Development of a new variable remote center compliance (VRCC) with modified elastomer shear pad (ESP) for robot assembly. 2005 , 2, 193-197		37
259	Admittance Design for Assembly of Polyhedral Parts with Modeling Errors.		0
258	Vision-Based Measurement of Part Deformation and Misalignment for Deformable Cylindrical Peg-in-Hole Tasks. 2005 , 219, 589-606		3
257	The Motion of a Compliantly Suspended Rigid Body Constrained by Multipoint Frictional Contact. <i>Journal of Dynamic Systems, Measurement and Control, Transactions of the ASME</i> , 2005 , 127, 623-632	1.6	
256	Error prevention in robotic assembly tasks by a machine vision and statistical pattern recognition method. 2005 , 43, 1397-1410		6
255	Towards grasping in unstructured environments: grasper compliance and configuration optimization. 2005 , 19, 523-543		77
254	A client/server approach to open-architecture, behavior-based robot programming.		
253	Spatial admittance selection conditions for frictionless force-guided assembly of polyhedral parts in single principal contact. 2006 , 22, 225-239		1

252	A robust compliant grasper via shape deposition manufacturing. 2006 , 11, 154-161		164
251	Adaptive Accommodation Control Method for Complex Assembly. 2006 , 49, 994-1002		1
250	Increasing Efficiency of Force-Controlled Robotic Assembly. 2006 , 55, 7-10		3
249	Dynamic analysis for peg-in-hole assembly with contact deformation. 2006 , 30, 118-128		24
248	Cooperative control of a human and a robot manipulator for positioning a cart on a frictionless plane. 2006 , 16, 461-469		10
247	An admittance design approach to dynamic assembly of polyhedral parts with uncertainty.		0
246	Possibility of jamming and wedging in the three-piece trucks of a moving freight car. 2007 , 45, 61-76		6
245	Loosely Coupled Joint Driven by SMA Coil Actuators. 2007 ,		0
244	Development of SMA-Actuated Microgripper in Micro Assembly Applications. 2007 ,		7
243	Alignment of parts in automatic assembly using vibrations. 2007 , 27, 38-43		4
242	Stiffness mapping of compliant parallel mechanisms in a serial arrangement. <i>Mechanism and Machine Theory</i> , 2008 , 43, 271-284	4	17
241	Force Control. 2008 , 161-185		117
240	Motion for Manipulation Tasks. 2008 , 615-645		22
239	Fiber Assembly of MEMS Optical Switches With U-Groove Channels. 2008 , 5, 207-215		26
238	Admittance Selection Conditions for Frictionless Force-Guided Assembly of Polyhedral Parts in Two Single-Point Principal Contacts. 2008 , 24, 461-468		6
237	Microassembly Fabrication of Tissue Engineering Scaffolds With Customized Design. 2008 , 5, 446-456		21
236	Human demonstration data for fast task teaching. 2008 ,		0
235	Modelling Contact Forces for 3D Interactive Peg-in-Hole Virtual Reality Operations. 2008 ,		5

234	Analysis and evaluation for assembly behaviour of reheat stop valve based on virtual prototyping. 2008 , 25, 637-656	1
233	Connection Mechanism for Autonomous Self-Assembly in Mobile Robots. 2009 , 25, 1413-1419	12
232	Force-based needle insertion for medical applications. 2009 ,	2
231	Design of a 2-finger hand exoskeleton for finger stiffness measurements. 2009 , 6, 217-228	7
230	Geometrical conditions for wedging in mechanical systems with Coulomb friction. 2009 , 223, 1171-1179	2
229	Measurement and control scheme for a container transfer robot in living space. 2009 ,	2
228	Shear Control of Elastomer Shear Pads for Variable Remote Center Compliance. 2009 , 23, 227-237	3
227	Non-jamming conditions in multi-contact rigid-body dynamics. 2009 , 22, 269-295	11
226	A tripod mechanism for parallelism alignment: Kinematics analysis and application. 2009 ,	
225	Analysis of assembly skills for dry battery insertion based on force control parameters. 2009 ,	1
224	Hybrid core-shell nanowire forests as self-selective chemical connectors. 2009 , 9, 2054-8	56
223	Development of Robotic Task Skills with High Reusability(Mechanical Systems). 2009 , 75, 3299-3306	0
222	A tree-shaped motion strategy for robustly executing robotic assembly tasks. 2010 , 11, 986-991	1
221	Formal definition of wedging and conditions for its possibility in systems with coulomb friction. 2010 , 52, 541-547	1
220	Motion Planning by Integration of Multiple Policies for Complex Assembly Tasks. 2010 ,	1
219	Control of Flexible Manipulators. Theory and Practice. 2010 ,	
218	On the Topology of Discrete Strategies. 2010 , 29, 855-896	9
217	Performance analysis of a manipulation task in time-delayed teleoperation. 2010 ,	4

216	Stiffness Control of a Continuum Manipulator in Contact with a Soft Environment. 2010 , 2010, 863-870	24
215	Two-phased controller for a pair of 2-DOF soft fingertips based on the qualitative relationship between joint angles and object location. 2010 ,	4
214	Parallel microassembly with a robotic manipulation system. 2010 , 20, 125027	9
213	Demonstrating the benefits of variable impedance to telerobotic task execution. 2011 ,	11
212	Performance Analysis of a Haptic Telemanipulation Task under Time Delay. 2011 , 25, 651-673	22
211	Two-Flexible-Fingers Gripper Force Feedback Control System for Its Application as End Effector on a 6-DOF Manipulator. 2011 , 27, 599-615	36
210	Dynamic analysis of vibratory insertion process. 2011 , 31, 275-283	11
209	Uniform Hardness Perception in 6-DOF Haptic Rendering. <i>IEEE Transactions on Instrumentation and Measurement</i> , 2011 , 60, 214-225	5.2 6
208	High-Yield Automated MEMS Assembly. 2011 , 253-278	
207	Visual-Based Automation of Peg-in-Hole Microassembly Process. 2011 , 133,	27
206	Joint coupling design of underactuated hands for unstructured environments. 2011 , 30, 1157-1169	49
205	Assembly algorithm for plastic ring with characteristic finger shape. 2012 ,	
204	The X-Face: An improved planar passive mechanical connector for modular self-reconfigurable robots. 2012 ,	7
203	Position and Force Analysis of a Planar Tensegrity-Based Compliant Mechanism. 2012 , 4,	4
202	Sensor-less insertion strategy for an eccentric peg in a hole of the crankshaft and bearing assembly. 2012 , 32, 86-99	29
201	. 2012 ,	5
200	A stiffness-matching based evaluation approach for compliance of mechanical systems in shield tunneling machines. 2012 , 55, 2926-2935	9
199	A dry wafer-reconstitution process with zero insertion force by embedded alignment guide tabs. 2012 , 22, 065007	

198	A new insertion strategy for a peg in an unfixed hole of the piston rod assembly. 2012 , 59, 1211-1225	22
197	Grounded discovery of symbols as concept-language pairs. 2012 , 44, 901-915	1
196	Contact states recognition in robotic part mating based on support vector machines. 2012 , 59, 377-395	17
195	Spring-joint method for topology optimization of planar passive compliant mechanisms. <i>Chinese Journal of Mechanical Engineering (English Edition)</i> , 2013 , 26, 1063-1072	2.5 6
194	Robotic surface assembly via contact state transitions. 2013 ,	7
193	Improving task skill transfer method by acquiring impedance parameters from human demonstration. 2013 ,	0
192	Fast peg-and-hole alignment using visual compliance. 2013 ,	7
191	Fluidic assembly at the microscale: progress and prospects. 2013 , 14, 383-419	52
190	Three-dimensional impact: energy-based modeling of tangential compliance. 2013 , 32, 56-83	16
189	Reaching in clutter with whole-arm tactile sensing. 2013 , 32, 458-482	68
188	A flexure-based 3-DOF parallel mechanism for optical fiber assembly. 2013 ,	2
187	Realizing peg-and-hole alignment with one eye-in-hand high-speed camera. 2013 ,	5
186	Dynamic compensation by fusing a high-speed actuator and high-speed visual feedback with its application to fast peg-and-hole alignment. 2014 , 28, 613-624	20
185	Design of a novel passive flexure-based mechanism for microelectromechanical system optical switch assembly. 2014 , 85, 125113	2
184	Reducing uncertainty in robotic surface assembly tasks based on contact information. 2014 ,	3
183	Analysis, Classification, and Design of Tendon-Driven Mechanisms. 2014 , 30, 396-410	59
182	Intelligent jamming region division with machine learning and fuzzy optimization for control of robot part micro-manipulative task. 2014 , 256, 211-224	7
181	Fuzzy inference mechanism for recognition of contact states in intelligent robotic assembly. 2014 , 25, 571-587	23


180	Autonomous Robust Skill Generation Using Reinforcement Learning with Plant Variation. 2014 , 6, 276264	3
179	A modified perturbation/correlation method for force-guided assembly. 2015 , 29, 5437-5446	6
178	Diagnosis of irregularities in the robotized part mating process based on contextual recognition of contact states transitions. 2015 , 35, 190-199	6
177	A new closed-form solution to inverse static force analysis of a spatial three-spring system. 2015 , 229, 2599-2610	0
176	Precise Robotic Assembly Using Passive Alignment Principle. <i>Journal of the Robotics Society of Japan</i> , 2015 , 33, 362-369	0.1
175	The Principal Axes Decomposition of Spatial Stiffness Matrices. 2015 , 31, 191-207	35
174	Dynamic in-hand sliding manipulation. 2015 ,	12
173	Passive Alignment Principle for Robotic Assembly Between a Ring and a Shaft With Extremely Narrow Clearance. 2015 , 1-1	7
172	Modeling, identification and joint impedance control of the atlas arms. 2015 ,	3
171	Mobile manufacturing of large structures. 2015 ,	5
170	Sensorless and constraint based peg-in-hole task execution with a dual-arm robot. 2016 ,	22
169	Nested compliant admittance control for robotic mechanical assembly of misaligned and tightly toleranced parts. 2016 ,	8
168	Motion for Manipulation Tasks. 2016 , 897-930	4
167	Force Control. 2016 , 195-220	25
166	Precise assembly of ring part with optimized hollowed finger. 2016 , 3,	3
165	The best-approximate realization of a spatial stiffness matrix with simple springs connected in parallel. <i>Mechanism and Machine Theory</i> , 2016 , 103, 236-249	4 2
164	A convex polynomial force-motion model for planar sliding: Identification and application. 2016 ,	12
163	A piezo-driven 2-DOF compliant micropositioning stage with remote center of motion. 2016 , 239, 114-126	26

162	Compliance Analysis and Synthesis of a Serial Manipulator with Redundant DOFs Used in Tokamak. 2016 , 757-767		
161	Antagonistic Impedance Control for Pneumatically Actuated Robot Joints. <i>IEEE Robotics and Automation Letters</i> , 2016 , 1, 161-168	4.2	16
160	Contact-state modelling in force-controlled robotic peg-in-hole assembly processes of flexible objects using optimised Gaussian mixtures. 2017 , 231, 1448-1463		14
159	A new method for automatic shaft-hole assembly of aircraft components. 2017 , 37, 64-70		6
158	Variable-Grasping-Mode Underactuated Soft Gripper With Environmental Contact-Based Operation. <i>IEEE Robotics and Automation Letters</i> , 2017 , 2, 1164-1171	4.2	34
157	Switch-Based Sliding Mode Control for Position-Based Visual Servoing of Robotic Riveting System. 2017 , 139,		9
156	. 2017 , 33, 778-795		47
155	Virtual Prototyping of a Flexure-based RCC Device for Automated Assembly. 2017 , 11, 380-388		4
154	The vibratory alignment of the parts in robotic assembly. 2017 , 44, 720-729		7
153	Study on dual peg-in-hole insertion using of constraints formed in the environment. 2017 , 44, 730-740		8
152	Multilayered Center-of-Pressure Sensors for Robot Fingertips and Adaptive Feedback Control. <i>IEEE Robotics and Automation Letters</i> , 2017 , 2, 2180-2187	4.2	7
151	Insertion force analysis of compliantly supported peg-in-hole assembly. 2017 , 37, 285-295		15
150	Assembly line balancing problem with task learning and dynamic task reassignment. 2017 , 88, 3089-3097		14
149	A novel peg-in-hole approach based on geometrical analysis for inclined uncertainty. 2017 ,		8
148	. 2017 ,		7
147	Forward Dynamics Compliance Control (FDCC): A new approach to cartesian compliance for robotic manipulators. 2017 ,		14
146	Design of Materials and Mechanisms for Responsive Robots. 2018 , 1, 359-384		13
145	Multi-Robot Assembly Strategies and Metrics. 2018 , 51,		30

144	A convex polynomial model for planar sliding mechanics: theory, application, and experimental validation. 2018 , 37, 249-265		19
143	Toward Robotic Manipulation. 2018 , 1, 1-28		33
142	Realtime State Estimation with Tactile and Visual Sensing for Inserting a Suction-held Object. 2018 ,		15
141	Robot Learning from Human Demonstration of Peg-In-Hole Task. 2018 ,		0
140	Learning-Based Variable Compliance Control for Robotic Assembly. 2018 , 10,		19
139	Hand Design Hybrid Soft and Hard Structures Based on Human Fingertips for Dexterity. 2018 , 115-147		1
138	A Survey of Dual-Arm Robotic Issues on Assembly Tasks. 2019 , 474-480		9
137	. 2019 , 16, 298-310		19
136	Design and Experimental Analysis of a Planar Compliant Parallel Manipulator. <i>Lecture Notes in Computer Science</i> , 2019 , 637-647	0.9	4
135	High-Speed Ring Insertion by Dynamic Observable Contact Hand. 2019 ,		4
134	Comparison of assembly-jam learning algorithms with fuzzy entropy measure for intelligent robot part micro-assembly. 2019 , 104, 3473-3488		0
133	. 2019 , 7, 148313-148325		8
132	Peg-hole disassembly using active compliance. 2019 , 6, 190476		11
131	Improving dual-arm assembly by master-slave compliance. 2019 ,		3
130	Making Sense of Vision and Touch: Self-Supervised Learning of Multimodal Representations for Contact-Rich Tasks. 2019 ,		63
129	Series elastic actuation for improved transparency in time delayed haptic teleoperation. 2019 , 63, 102278		7
128	Geometry based synthesis of planar compliances with redundant mechanisms having five compliant components. <i>Mechanism and Machine Theory</i> , 2019 , 134, 645-666	4	8
127	Learning Force-Relevant Skills From Human Demonstration. 2019 , 2019, 1-11		14

126	Image-based visual servoing using a set for multiple pin-in-hole assembly. 2019 , 40, 819-831		0
125	Complementary projector for null-space stiffness control of redundant assembly robot arm. 2019 , 39, 696-714		0
124	Contact Skill Imitation Learning for Robot-Independent Assembly Programming. 2019 ,		10
123	A Comparison of Action Spaces for Learning Manipulation Tasks. 2019 ,		9
122	Transferable Trial-Minimizing Progressive Peg-in-hole Model. 2019 ,		
121	A Novel 5-DOF Flexure-based Passive Alignment Stage for Microassembly System. 2019 ,		
120	Tactile-Based Insertion for Dense Box-Packing. 2019 ,		15
119	A Peg-in-hole Assembly Strategy Using Uncalibrated Visual Servoing. 2019 ,		0
118	Quickly Inserting Pegs into Uncertain Holes using Multi-view Images and Deep Network Trained on Synthetic Data. 2019 ,		18
117	Singularity Avoidance with Preservation of Manipulation Performance in Impedance Control for Human-Robot Collaboration. 2019 ,		
116	Assembly process monitoring algorithm using force data and deformation data. <i>Robotics and Computer-Integrated Manufacturing</i> , 2019 , 56, 149-156	9.2	26
115	Design of Spatial Admittance for Force-Guided Assembly of Polyhedral Parts in Single Point Frictional Contact. 2020 ,		
114	In-Hand Sliding Regrasp With Spring-Sliding Compliance and External Constraints. 2020 , 8, 88729-88744		2
113	Contact States Estimation Algorithm Using Fuzzy Logic in Peg-in-hole Assembly*. 2020 ,		2
112	Variable Compliance Control for Robotic Peg-in-Hole Assembly: A Deep-Reinforcement-Learning Approach. <i>Applied Sciences (Switzerland)</i> , 2020 , 10, 6923	2.6	14
111	Precision Assembly of Heavy Objects Suspended With Multiple Cables From a Crane. <i>IEEE Robotics and Automation Letters</i> , 2020 , 5, 6876-6883	4.2	3
110	Model accelerated reinforcement learning for high precision robotic assembly. 2020 , 4, 202-216		5
109	A Tendon-Driven Origami Hopper Triggered by Proprioceptive Contact Detection. 2020 ,		2

108	Integrating combined task and motion planning with compliant control. 2020 , 4, 149-163		12
107	Robotic Assembly of Rounded Parts With and Without Threads. <i>IEEE Robotics and Automation Letters</i> , 2020 , 5, 2467-2474	4.2	5
106	Making Sense of Vision and Touch: Learning Multimodal Representations for Contact-Rich Tasks. 2020 , 36, 582-596		22
105	Development of assembly system with quick and low-cost installation. 2020 , 1-15		1
104	Peg-on-hole: mathematical investigation of motion of a peg and of forces of its interaction with a vertically fixed hole during their alignment with a three-point contact. 2020 , 107, 689-704		0
103	Design of a parallel compliance device with variable stiffness. 2021 , 235, 94-107		2
102	Efficient Insertion Strategy for Precision Assembly With Uncertainties Using a Passive Mechanism. 2021 , 17, 1263-1273		2
101	Learning Control with Soft Robots: Application for Industrial Assembly. <i>Journal of the Robotics Society of Japan</i> , 2021 , 39, 609-612	0.1	
100	Development of a Real-Time Human-Robot Collaborative System Based on 1 kHz Visual Feedback Control and Its Application to a Peg-in-Hole Task. 2021 , 21,		2
99	Modeling and Development of Passively Adaptive Assistive Tools for the Assembly of Press-Fit Components. 2021 , 143,		
98	Research on the tracing accurate of force based on fuzzy-pi control for a high-speed landing system. 2021 , 43, 1		0
97	Contact Pose Identification for Peg-in-Hole Assembly under Uncertainties. 2021 ,		2
96	A robot assembly framework with perception-action mapping cognitive learning. 2021 ,		
95	Robotic Disassembly for Remanufacturing. 2022 , 7-25		
94	Search trajectory with twisting motion for dual peg-in-hole assembly. 2021 , 14, 597		1
93	Control Strategy for Jam and Wedge-Free 3D Precision Insertion of Heavy Objects Suspended With a Multi-Cable Crane. <i>IEEE Robotics and Automation Letters</i> , 2021 , 6, 7453-7460	4.2	
92	Improving Automated Insertion Task in Robotics by Reducing Registration Error. <i>IFIP Advances in Information and Communication Technology</i> , 2021 , 108-121	0.5	
91	Feature-Based Compliance Control for Precise Peg-in-Hole Assembly. 2021 , 1-1		2

90	Cooperative Human and Machine Perception in Teleoperated Assembly. 2001 , 51-60		10
89	Interaction Control. 2000 , 271-294		5
88	Quaternion-Based Impedance Control for Dual-Robot Cooperation. 2000 , 59-66		1
87	Automatic Grasp Planning. An Operation Space Approach. 1987 , 380-387		3
86	Recognition of Contact States in Robotized Assembly Using Qualitative Wavelet Based Features and Support Vector Machines. 2010 , 305-308		3
85	Generic Algorithm for Peg-In-Hole Assembly Tasks for Pin Alignments with Impedance Controlled Robots. 2016 , 105-117		7
84	State of the Art. <i>Springer Tracts in Advanced Robotics</i> , 2014 , 7-23	0.5	2
83	Sensor Programming  New Way for Teaching a Robot Paths and Sensory Patterns Simultaneously. 1984 , 395-410		5
82	Active Force Feedback Control for Assembly Processes Using a Flexible and Sensible Robot Wrist. 1985 , 571-577		1
81	Contact Formations and Design Constraints: A New Basis for the Automatic Generation of Robot Programs. 1988 , 361-395		5
80	Force-feedback control of parallel kinematics manipulators. 1990 , 143-158		1
79	THE KARLSRUHE HAND. 1989 , 383-388		2
78	Analysis and Validation of a Flexible Planar Two Degrees-of-Freedom Parallel Manipulator With Structural Passive Compliance. 2020 , 12,		10
77	Support Vector Regression for Optimal Robotic Force Control Assembly. 2020 , 142,		2
76	Home-Use Object Transfer/Storage Robot System with Compliant Strategy and Mechanism (Commodities Management and its Extended Application of Daily Life Support for the Elderly). <i>Journal of Robotics and Mechatronics</i> , 2011 , 23, 532-543	0.7	9
75	Development of Mechanical-Impedance-Varying Mechanism in Admittance Control. <i>Journal of Robotics and Mechatronics</i> , 2018 , 30, 863-872	0.7	3
74	Tactile-RL for Insertion: Generalization to Objects of Unknown Geometry. 2021 ,		6
73	Stable, Sensor-less and Compliance-less Module Connection for Automated Construction System of a Modularized Rail Structure. 2021 ,		1

72	A Peg-in-hole Task Strategy for Holes in Concrete. 2021 ,		1
71	Manipulating Parts with an Array of Pins: A Method and a Machine. 2000 , 123-130		
70	Design and Implementation of a Robot Control System Using a Unified Hardware-Software Rapid-Prototyping Framework. 2002 , 669-672		
69	. 2002 , 13, 283-288		1
68	SPDM Constrained Motion - Modelling, Analysis and Controller Design. 2004 ,		
67	Insertion of Long Peg into Tandem Shallow Hole Using Search Trajectory Generation. <i>Journal of Robotics and Mechatronics</i> , 2004 , 16, 613-621	0.7	1
66	Development of a Variable Remote Center Compliance (VRCC) with Stiffness Adjusting Rods.. <i>Journal of Control Automation and Systems Engineering</i> , 2005 , 11, 704-708		
65	Analysis of Clutch Assembly with Dynamic Simulator. <i>Journal of the Japan Society for Precision Engineering</i> , 2007 , 73, 475-480	0.1	
64	An experimental study on adjusting mechanism of Remote Center Compliance for assembly robots with shear stress control of Elastomer Shear Pads(ESP). <i>Journal of Control Automation and Systems Engineering</i> , 2007 , 13, 910-914		
63	Hardware and Numerical Experiments of Autonomous Robust Skill Generation Using Reinforcement Learning. <i>Journal of Robotics and Mechatronics</i> , 2008 , 20, 350-357	0.7	1
62	Development of a Manipulation Component for a Container Transferring Robot in Living Space. <i>Springer Tracts in Advanced Robotics</i> , 2009 , 567-576	0.5	2
61	Soft Interface Connecting Physical and Information Worlds. <i>Journal of the Robotics Society of Japan</i> , 2010 , 28, 503-511	0.1	1
60	Buffering Indices for Robot Manipulators Based on the Energy Distribution. <i>Lecture Notes in Computer Science</i> , 2010 , 252-263	0.9	
59	Proposition and Demonstration of a System Configuration Method Utilizing Mechanical Compliance for a Home-use Container Transfer Robot. <i>Journal of the Robotics Society of Japan</i> , 2010 , 28, 841-852	0.1	1
58	Robot Hand Whose Fingertip Covered with Net-Shape Proximity Sensor - Moving Object Tracking Using Proximity Sensing -. <i>Journal of Robotics and Mechatronics</i> , 2011 , 23, 328-337	0.7	4
57	Educational Activities with a Focus on Robot Strategies Through the Development of LEGO Manipulation Robots Journal of Robotics and Mechatronics, 2011 , 23, 759-767	0.7	2
56	Flexure-Based Parallel-Kinematics Stages for Passive Assembly of MEMS Optical Switches. <i>Microsystems</i> , 2013 , 117-140		
55	Optimal Design of Remote Center Compliance Devices of Rotational Symmetry. <i>IFIP Advances in Information and Communication Technology</i> , 2014 , 161-169	0.5	2

54	Regelungsalgorithmen für Industrieroboter Eine Übersicht. <i>Fachberichte Messen, Steuern, Regeln</i> , 1984 , 32-58		2
53	Robot-Task Adaptability by Semi-Local Correction without Contact. 1987 , 334-341		
52	Literaturverzeichnis. <i>Fachberichte Messen, Steuern, Regeln</i> , 1988 , 134-145		
51	Assembly. 1988 , 114-130		
50	Grundstruktur von lernenden Systemen. <i>Fachberichte Messen, Steuern, Regeln</i> , 1988 , 18-25		
49	Control Concepts for Industrial Robots Equipped with Multiple and Redundant Sensors. 1990 , 277-291		2
48	Literatur. <i>Informatik-Fachberichte</i> , 1991 , 153-160		
47	Literaturverzeichnis. 1992 , 128-135		1
46	Advanced Telerobotic Systems Single-Master Multi-Slave Manipulator System and Cellular Robotic System. <i>Euro Courses Computer and Information Science</i> , 1992 , 195-208		
45	ACCOMMODATION BASED ON THE COMPLIANT ROBOT WRIST WITH SIX D.O.F. DISPLACEMENT/FORCE SENSING CAPABILITY. 1992 , 469-473		
44	AN IJC BASED FORCE-POSITION CONTROL OF A ROBOT ARM. 1992 , 189-194		
43	INSERTION FORCE RECOGNITION BY MODELLING AND SIMULATION OF ASSEMBLY SYSTEMS WITH ACCOMODATORS. 1993 , 111-116		
42	Microprocessors, instrumentation and control. 1994 , 3-1-3-87		1
41	Motion and force control. <i>Communications and Control Engineering</i> , 1996 , 141-175	0.6	1
40	Evaluation of an Inverse-Kinematics Depth-Sensing Controller for Operation of a Simulated Robotic Arm. <i>Lecture Notes in Computer Science</i> , 2016 , 373-381	0.9	1
39	Reinforcement Learning of Robotic Manipulators. 2016 , 49-69		1
38	Development of an Intersection Module for a Modularized Rail Structure Implementation of Compliant Mechanisms for a Replacing Task of Movable Parts <i>Journal of Robotics and Mechatronics</i> , 2018 , 30, 467-476	0.7	1
37	Neue Teach-In-Verfahren in der Robotik. <i>Informatik-Fachberichte</i> , 1983 , 177-193		

36	Modelling of Robotic Single Peg-In-Hole Assembly Using ADAMS/MATLAB Co-simulation. <i>IOP Conference Series: Materials Science and Engineering</i> , 995, 012008	0.4	0
35	The relationship between mechanism geometry and the centers of stiffness and compliance. <i>Mechanism and Machine Theory</i> , 2022 , 167, 104565	4	2
34	Research on the Structural Rigidity Characteristics of a Reconfigurable TBM Thrust Mechanism. <i>Chinese Journal of Mechanical Engineering (English Edition)</i> , 2019 , 32,	2.5	2
33	Prototype Design and Performance Experiment of Passive Compliant Mechanism for the Automatic Charging Robot End Effector. <i>Lecture Notes in Electrical Engineering</i> , 2020 , 281-287	0.2	
32	Interaction Control. 2001 , 121-154		
31	Position/Force Visual-Sensing Based Robotic Sheet-Like Peg-in-Hole Assembly. <i>IEEE Transactions on Instrumentation and Measurement</i> , 2021 , 1-1	5.2	0
30	A Compact, Cable-driven, Activatable Soft Wrist with Six Degrees of Freedom for Assembly Tasks. 2020 ,		1
29	Meta-Reinforcement Learning for Robotic Industrial Insertion Tasks. 2020 ,		2
28	Learning-based Contact Status Recognition for Peg-in-Hole Assembly.		0
27	Study on Data-Driven Approaches for the Automated Assembly of Board-to-Board Connectors. <i>Applied Sciences (Switzerland)</i> , 2022 , 12, 1216	2.6	1
26	Contact State Estimation for Peg-in-Hole Assembly Using Gaussian Mixture Model. <i>IEEE Robotics and Automation Letters</i> , 2022 , 7, 3349-3356	4.2	0
25	Residual Learning from Demonstration: Adapting DMPs for Contact-rich Manipulation. <i>IEEE Robotics and Automation Letters</i> , 2022 , 1-1	4.2	1
24	Curriculum-based Offline Network Training for Improvement of Peg-in-hole Task Performance for Holes in Concrete. 2022 ,		1
23	Synthesis and Prototyping of a 6-dof Parallel Robot for the Automatic Performance of Assembly Tasks. <i>Journal of Advanced Computational Intelligence and Intelligent Informatics</i> , 2022 , 26, 125-137	0.4	
22	Robot assembly theory and simulation of circular-rectangular compound peg-in-hole. <i>Robotica</i> , 1-34	2.1	
21	Experiential and Stochastic Learning Algorithms Based on the Probability of a Fuzzy Event and Modified Fuzzy Metric Distance in Intelligent Robotic Part Micro-Assembly. <i>International Journal of Uncertainty, Fuzziness and Knowledge-Based Systems</i> , 2022 , 30, 311-333	0.8	1
20	Influence of viscoelastic property of compliance material in achieving successful robotic Peg-In-Hole. <i>Materials Today: Proceedings</i> , 2022 ,	1.4	
19	A review of robotic assembly strategies for the full operation procedure: planning, execution and evaluation. <i>Robotics and Computer-Integrated Manufacturing</i> , 2022 , 78, 102366	9.2	1

18	Horizontal Insertion of a Ring Onto a Shaft Using a Gantry Crane With Minimal Sensors. <i>IEEE Robotics and Automation Letters</i> , 2022 , 7, 7271-7278	4.2	
17	Offline Meta-Reinforcement Learning for Industrial Insertion. 2022 ,		1
16	Model-driven reinforcement learning and action dimension extension method for efficient asymmetric assembly. 2022 ,		
15	Active Extrinsic Contact Sensing: Application to General Peg-in-Hole Insertion. 2022 ,		1
14	Analysis and validation of a planar parallel continuum manipulator with variable Cartesian stiffness. <i>Mechanism and Machine Theory</i> , 2022 , 177, 105030	4	0
13	A survey of robot manipulation in contact. 2022 , 156, 104224		3
12	Grasp compliance achieved with a planar hand composed of multiple 3-joint fingers. 1-22		0
11	Robotic Assistance for Peg-and-Hole Alignment by Mimicking Annular Solar Eclipse Process. 2022 , 34, 946-955		0
10	Calibration methodology for multirobot assembly cell. 2022 ,		0
9	Design of a compliant device for peg-hole separation in robotic disassembly.		0
8	Deep Imitation Learning with Pseudo-haptics Module for Peg-in-hole with Hole Position Uncertainty. 2023 , 89, 83-89		0
7	Adaptive Sequential Composition for Robot Behaviours. 2022 ,		0
6	Sim-to-Real Transfer of Robotic Assembly with Visual Inputs Using CycleGAN and Force Control. 2022 ,		1
5	Visual Spatial Attention and Proprioceptive Data-Driven Reinforcement Learning for Robust Peg-in-Hole Task Under Variable Conditions. 2023 , 1-8		0
4	A Passive Compliant Gough-Whitehall-Stewart Mechanism for Peg-Hole Disassembly. 2023 , 704-710		0
3	QUANTIFYING ROBOTIC ASSEMBLY CAPABILITY A REVIEW AND A PROSPECTUS. 2023 ,		0
2	Using semantic Geometric Dimensioning and Tolerancing (GD & T) information from STEP AP242 neutral exchange files for robotic applications.		0
1	A Light-Weight Quasi-Direct Drive Collaborative Robot Arm. 2023 ,		0

