

ATRIAS: Design and validation of a tether-free 3D-capable

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Citation Report

#	ARTICLE	IF	CITATIONS
1	Mechanics-based design of underactuated robotic walking gaits: Initial experimental realization. , 2016, , .		5
2	Experimental Evaluation of Deadbeat Running on the ATRIAS Biped. IEEE Robotics and Automation Letters, 2017, 2, 1085-1092.	5.1	22
3	Robot Simulations Based on Bipedal Spring-Mass Model With Variable Slack Length and Stiffness. IEEE Access, 2017, 5, 1156-1163.	4.2	3
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5	Template model inspired leg force feedback based control can assist human walking. , 2017, 2017, 473-478.		22
6	A force direction control method for robotic bipedal walking based on a reduced order model. , 2017, , .		4
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8	Development of torque controllable leg for running robot, AiDIN-IV. , 2017, , .		7
10	Control of Motion and Compliance. , 2017, , 135-346.		3
11	Spine morphology and energetics: how principles from nature apply to robotics. Bioinspiration and Biomimetics, 2018, 13, 036002.	2.9	29
12	Morphological and control criteria for self-stable underwater hopping. Bioinspiration and Biomimetics, 2018, 13, 016001.	2.9	18
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22	A Switchable Parallel Elastic Actuator and its Application to Leg Design for Running Robots. IEEE/ASME Transactions on Mechatronics, 2018, 23, 2681-2692.	5.8	37
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