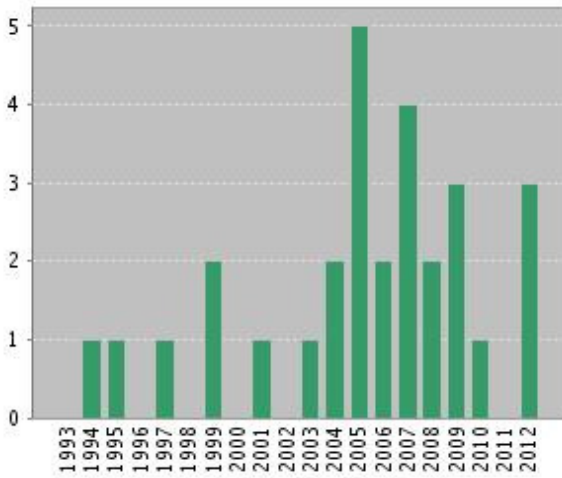


Back to Results

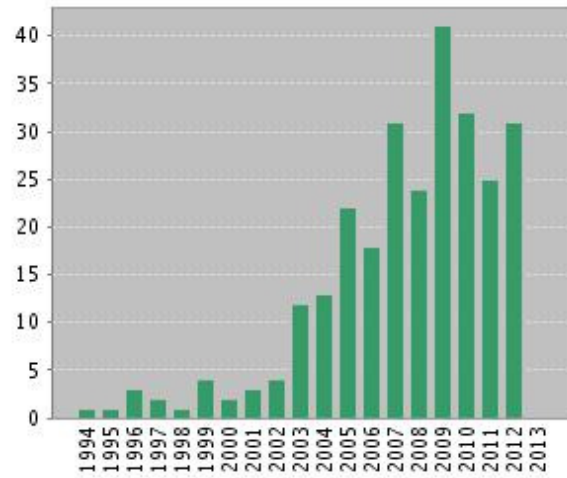
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[ 1 | 2 | 3 | 4 ]

Published Items in Each Year



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	2009	2010	2011	2012	2013	Total	Average Citations per Year
	41	32	25	31	0	270	13.50
1. <b>Title:</b> DYNAMICS OF NONHOLONOMIC MECHANICAL SYSTEMS USING A NATURAL ORTHOGONAL COMPLEMENT <b>Author(s):</b> SAHA, SK; ANGELES, J <b>Source:</b> JOURNAL OF APPLIED MECHANICS-TRANSACTIONS OF THE ASME <b>Volume:</b> 58 <b>Issue:</b> 1 <b>Pages:</b> 238-243 <b>DOI:</b> 10.1115/1.2897157 <b>Published:</b> MAR 1991	6	4	2	0	0	42	1.83
2. <b>Title:</b> Recursive kinematics and dynamics for parallel structured closed-loop multibody systems <b>Author(s):</b> Saha, SK; Schiehlen, WO <b>Source:</b> MECHANICS OF STRUCTURES AND MACHINES <b>Volume:</b> 29 <b>Issue:</b> 2 <b>Pages:</b> 143-175 <b>DOI:</b> 10.1081/SME-100104478 <b>Published:</b> 2001	5	2	2	1	0	36	2.77
3. <b>Title:</b> Dynamics of serial multibody systems using the decoupled natural orthogonal complement matrices <b>Author(s):</b> Saha, SK <b>Source:</b> JOURNAL OF APPLIED MECHANICS-TRANSACTIONS OF THE ASME <b>Volume:</b> 66 <b>Issue:</b> 4 <b>Pages:</b> 986-996 <b>DOI:</b> 10.1115/1.2791809 <b>Published:</b> DEC 1999	3	1	0	6	0	28	1.87
4. <b>Title:</b> A decomposition of the manipulator inertia matrix <b>Author(s):</b> Saha, SK <b>Source:</b> IEEE TRANSACTIONS ON ROBOTICS AND AUTOMATION <b>Volume:</b> 13 <b>Issue:</b> 2 <b>Pages:</b> 301-304 <b>DOI:</b>	3	2	5	2	0	28	1.65

	2009	2010	2011	2012	2013	Total	Average Citations per Year
	41	32	25	31	0	270	13.50
10.1109/70.563652 <b>Published:</b> APR 1997							
5. <b>Title:</b> Attribute based specification, comparison and selection of a robot <b>Author(s):</b> Bhangale, PP; Agrawal, VP; Saha, SK <b>Conference:</b> 11th National Conference on Machines and Mechanisms <b>Location:</b> Indian Inst Technol, New Delhi, INDIA <b>Date:</b> DEC 18-19, 2003 <b>Source:</b> MECHANISM AND MACHINE THEORY <b>Volume:</b> 39 <b>Issue:</b> 12 <b>Pages:</b> 1345-1366 <b>DOI:</b> 10.1016/j.mechmachtheory.2004.05.020 <b>Published:</b> DEC 2004	2	4	6	3	0	23	2.30
6. <b>Title:</b> THE DESIGN OF KINEMATICALLY ISOTROPIC ROLLING ROBOTS WITH OMNIDIRECTIONAL WHEELS <b>Author(s):</b> SAHA, SK; ANGELES, J; DARCOVICH, J <b>Source:</b> MECHANISM AND MACHINE THEORY <b>Volume:</b> 30 <b>Issue:</b> 8 <b>Pages:</b> 1127-1137 <b>DOI:</b> 10.1016/0094-114X(95)00042-W <b>Published:</b> NOV 1995	4	0	0	0	0	19	1.00
7. <b>Title:</b> Recursive kinematics and inverse dynamics for a planar 3R Parallel Manipulator <b>Author(s):</b> Khan, WA; Krovi, VN; Saha, SK; et al. <b>Source:</b> JOURNAL OF DYNAMIC SYSTEMS MEASUREMENT AND CONTROL-TRANSACTIONS OF THE ASME <b>Volume:</b> 127 <b>Issue:</b> 4 <b>Pages:</b> 529-536 <b>DOI:</b> 10.1115/1.2098890 <b>Published:</b> DEC 2005	4	4	3	3	0	18	2.00
8. <b>Title:</b> Kinematics analyses of Dodekapod <b>Author(s):</b> Bande, P; Seibt, M; Uhlmann, E; et al. <b>Source:</b> MECHANISM AND MACHINE THEORY <b>Volume:</b> 40 <b>Issue:</b> 6 <b>Pages:</b> 740-756 <b>DOI:</b> 10.1016/j.mechmachtheory.2004.11.006 <b>Published:</b> JUN 2005	1	2	1	3	0	8	0.89
9. <b>Title:</b> Balancing of four-bar linkages using maximum recursive dynamic algorithm <b>Author(s):</b> Chaudhary, Himanshu; Saha, Subir Kumar <b>Source:</b> MECHANISM AND MACHINE THEORY <b>Volume:</b> 42 <b>Issue:</b> 2 <b>Pages:</b> 216-232 <b>DOI:</b> 10.1016/j.mechmachtheory.2006.02.008 <b>Published:</b> FEB 2007	1	2	0	1	0	7	1.00
10. <b>Title:</b> Dimensional design of hexaslides for optimal workspace and dexterity <b>Author(s):</b> Rao, ABK; Rao, PVM; Saha, SK <b>Source:</b> IEEE TRANSACTIONS ON ROBOTICS <b>Volume:</b> 21 <b>Issue:</b> 3 <b>Pages:</b> 444-449 <b>DOI:</b> 10.1109/TRO.2004.842353 <b>Published:</b> JUN 2005	3	1	2	1	0	7	0.78

[Back to Results](#)

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Page 1 (Records 1 -- 10)

[Print This Page](#)

◀ [ 1 | 2 | 3 | 4 ] ▶