

List of publications

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Publikationer

Teaching hardware implementation of neural networks using high-level synthesis in less than four hours for engineering education of intelligent embedded computing

Huang, N. S., Braun, J. M., Larsen, J. C. & Manoonpong, P., 18. jul. 2019, *Proceedings of the 2019 20th International Carpathian Control Conference, ICCO 2019*. Nawrocka, A. & Kot, A. (red.). IEEE, 7 s.

A scalable Echo State Networks hardware generator for embedded systems using high-level synthesis

Huang, N. S., Braun, J. M., Larsen, J. C. & Manoonpong, P., 15. jul. 2019, *2019 8th Mediterranean Conference on Embedded Computing, MECO 2019 - Proceedings*. IEEE, 6 s. 8760065. (Mediterranean Conference on Embedded Computing, MECO , Bind 2019).

Bio-inspired design and movement generation of dung beetle-like legs

Ignasov, J., Kapilavai, A., Filonenko, K., Larsen, J. C., Baird, E., Hallam, J., Büsse, S., Kovalev, A., Gorb, S. N., Duggen, L. & Manoonpong, P., 1. dec. 2018, I : *Artificial Life and Robotics*. 23, s. 555-563 9 s.

Preface

Manoonpong, P., Larsen, J. C., Xiong, X., Hallam, J. & Triesch, J., 2018, *From Animals to Animats 15: 15th International Conference on Simulation of Adaptive Behavior, SAB 2018, Proceedings*. Manoonpong, P., Larsen, J. C., Xiong, X., Hallam, J. & Triesch, J. (red.). Springer, s. VI 1 s. (Lecture Notes in Computer Science, Bind 10994).

Locokit III: A versatile robotic platform to study embodied locomotion

Larsen, J. C. & Manoonpong, P., 29. jun. 2017. 2 s.

Bio-Inspired Design and Kinematic Analysis of Dung Beetle-Like Legs

Aditya, S. K. V., Ignasov, J., Filonenko, K., Larsen, J. C., Baird, E., Hallam, J., Büsse, S., Kovalev, A., Gorb, S., Duggen, L. & Manoonpong, P., 2017.

A Combination of Central Pattern Generator-based and Reflex-based Neural Networks for Dynamic, Adaptive, Robust Bipedal Locomotion

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A Dung Beetle-like Leg and its Adaptive Neural Control

Di Canio, G., Stoyanov, S., Larsen, J. C., Hallam, J., Kovalev, A., Kleinteich, T., Gorb, S. & Manoonpong, P., 2016, *Proceedings of the First International Symposium on Swarm Behavior and Bio-Inspired Robotics*. SWARM, 4 s.

A Robot Leg with Compliant Tarsus and its Neural Control for Efficient and Adaptive Locomotion on Complex Terrains

Di Canio, G., Stoyanov, S., Larsen, J. C., Hallam, J., Kovalev, A., Kleinteich, T., Gorb, S. & Manoonpong, P., 2016, I : *Artificial Life and Robotics*. 21, 3, s. 274-281

Adaptive Combinatorial Neural Control for Robust Locomotion of a Biped Robot

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Der skal gang i robotterne - fra Lego til LocoKit

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Fault-tolerant gait learning and morphology optimization of a polymorphic walking robot

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Locomotion Through Morphosis

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Increased performance in a bottom-up designed robot by experimentally guided redesign

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On sub-modularization and morphological heterogeneity in modular robotics: Advances in Intelligent Systems and Computing

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On Sub-Modularization and Morphological Heterogeneity in Modular Robotics

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Adaptive Strategy for Online Gait Learning Evaluated on the Polymorphic Robotic LocoKit

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LocoKit: A Robot Construction Kit for Studying and Developing Functional Morphologies

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Energy Efficiency of Robot Locomotion Increases Proportional to Weight

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Locomotion through Morphosis

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Increased Versatility of Modular Robots through Layered Heterogeneity

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Flexible, fpga-based electronics for modular robots

Brandt, D., Larsen, J. C., Christensen, D. J., Garcia, R. F. M., Shaikh, D., Schultz, U. P. & Støy, K., 2008, *Proceedings of the IROS Workshop on Self-Reconfigurable Robots, Systems and Applications*. 5 s.