

## Prof. ULUÇ SARANLI

### Personal Information

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### International Researcher IDs

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ScopusID: 6602240964

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### Education Information

Doctorate, The University of Michigan, Electrical Engineering And Computer Science, United States Of America 1998 - 2002

Postgraduate, University of Michigan, Mühendislik Fakültesi, Bilgisayar Bilimleri, United States Of America 1996 - 1998

Undergraduate, Middle East Technical University, Faculty of Engineering, Elektrik-Elektronik Mühendisliği Bölümü, Turkey 1992 - 1996

### Foreign Languages

English, C1 Advanced

### Dissertations

Doctorate, Dynamic locomotion with a Hexapod Robot, The University Of Michigan, Electrical Engineering And Computer Science, 2002

### Research Areas

Mechanical Engineering, Machine Theory and Dynamics, Robotics, Engineering and Technology

### Academic Titles / Tasks

Professor, Middle East Technical University, Faculty of Engineering, Department of Computer Engineering, 2018 - Continues

Associate Professor, Middle East Technical University, Faculty of Engineering, Department of Computer Engineering, 2012 - 2018

Assistant Professor, Middle East Technical University, Faculty of Engineering, Department of Computer Engineering, 2012 - 2012

Assistant Professor, Ihsan Dogramaci Bilkent University, Faculty Of Engineering, Department Of Computer Engineering,

2005 - 2012

Lecturer PhD, Carnegie Mellon University, Faculty Of Engineering, Robotics Institute, 2002 - 2005

Research Assistant, The University of Michigan, Faculty Of Engineering, Electrical Engineering And Computer Science, 1996 - 2002

## Advising Theses

SARANLI U., Control of quadruped walking behavior through an embedding of spring loaded inverted pendulum template, Postgraduate, M.KAAN(Student), 2022

SARANLI U., Foothold selection for quadruped robots based on feasible ground reaction force sets, Postgraduate, F.DAVULCU(Student), 2022

SARANLI U., Control of spring-mass running through virtual tuning of leg damping, Doctorate, G.Seçer(Student), 2020

SARANLI U., Synchronization of multiple serially actuated robotic legs using virtual damping control, Postgraduate, M.ÖZEN(Student), 2018

SARANLI U., Identification of legged locomotion via model-based and data-driven approaches, Doctorate, İ.UYANIK(Student), 2017

SARANLI U., Stability and control of a compass gait model walking with series-elastic ankle actuation, Doctorate, D.KERİMOĞLU(Student), 2017

SARANLI U., Estimation of ground reaction forces using forearm crutches instrumented with pressure sensors and accelerometers, Postgraduate, Ç.SEYLAN(Student), 2016

SARANLI U., SARANLI A., A novel real-time inertial motion blur metric with applications to motion blur compensation, Postgraduate, M.MUTLU(Student), 2014

SARANLI A., SARANLI U., A Novel real-time inertial motion blur metric with applications to motion blur compensation /, Postgraduate, M.Mutlu(Student), 2014

SARANLI U., Identification and stability analysis of periodic motions for a planar legged runner with a rigid body and a compliant leg, Postgraduate, G.BAYIR(Student), 2013

SARANLI U., 3D dynamic modeling of a spherical wheeled self-balancing mobile robot, Postgraduate, A.NAİL(Student), 2012

SARANLI U., Using shape information from natural tree landmarks for improving slam performance, Postgraduate, B.TURAN(Student), 2012

SARANLI U., Modeling of flexible needle insertion in moving tissue, Postgraduate, A.DENİZ(Student), 2012

SARANLI U., An actuated flexible spinal mechanism for a bounding quadrupedal robot, Postgraduate, U.ÇULHA(Student), 2012

SARANLI U., Adaptive control of a one-legged hopping robot through dynamically embedded spring loaded inverted pendulum template, Postgraduate, İ.UYANIK(Student), 2011

SARANLI U., Improving visual SLAM by filtering outliers with the aid of optical flow, Postgraduate, T.ÖZASLAN(Student), 2011

SARANLI U., Detection of tree trunks as visual landmarks in outdoor environments, Postgraduate, T.YILDIZ(Student), 2010

SARANLI A., SARANLI U., Control of hexapedal pronking through a dynamically embedded spring loaded inverted pendulum template, Postgraduate, M.MERT(Student), 2010

SARANLI U., A backwards theorem prover with focusing, resource management and constraints for robotic planning within intuitionistic linear logic, Postgraduate, S.KORTİK(Student), 2010

SARANLI U., A USB-based real-time communication infrastructure for robotic platforms, Postgraduate, C.ÖZTÜRK(Student), 2009

SARANLI U., Model based methods for the control and planning of running robots, Postgraduate, Ö.ARSLAN(Student), 2009

SARANLI U., Experiments in integrating constraints with logical reasoning for robotic planning within the twelf logical framework and the prolog language, Postgraduate, M.DUATEPE(Student), 2008

SARANLI U., Line segment based range scan matching without pose information for indoor environments, Postgraduate,

İ.YAKIN(Student), 2008

SARANLI U., The universal robot bus: A local communication infrastructure for small robots, Postgraduate,

A.AVCI(Student), 2008

## Published journal articles indexed by SCI, SSCI, and AHCI

- I. **Efficient bipedal locomotion on rough terrain via compliant ankle actuation with energy regulation**  
Kerimoglu D., Karkoub M., Ismail U., MORGÜL Ö., SARANLI U.  
BIOINSPIRATION & BIOMIMETICS, vol.16, no.5, 2021 (SCI-Expanded)
- II. **The Effects of Clinical and Home-based Physiotherapy Programs in Secondary Head and Neck Lymphedema**  
Ozdemir K., KESER İ., DÜZLÜ M., ERPOLAT Ö. P., SARANLI U., TUTAR H.  
LARYNGOSCOPE, vol.131, no.5, 2021 (SCI-Expanded)
- III. **Robotic Task Planning Using a Backchaining Theorem Prover for Multiplicative Exponential First-Order Linear Logic**  
Kortik S., SARANLI U.  
JOURNAL OF INTELLIGENT & ROBOTIC SYSTEMS, vol.96, no.2, pp.179-191, 2019 (SCI-Expanded)
- IV. **Frequency-Domain Subspace Identification of Linear Time-Periodic (LTP) Systems**  
Uyanik İ., Saranlı U., Ankaralı M. M., Cowan N., Morgül Ö.  
IEEE TRANSACTIONS ON AUTOMATIC CONTROL, vol.64, pp.2529-2536, 2019 (SCI-Expanded)
- V. **Control of Planar Spring-Mass Running Through Virtual Tuning of Radial Leg Damping**  
Secer G., SARANLI U.  
IEEE TRANSACTIONS ON ROBOTICS, vol.34, no.5, pp.1370-1383, 2018 (SCI-Expanded)
- VI. **Estimation of Ground Reaction Forces Using Low-Cost Instrumented Forearm Crutches**  
Seylan C., SARANLI U.  
IEEE TRANSACTIONS ON INSTRUMENTATION AND MEASUREMENT, vol.67, no.6, pp.1308-1316, 2018 (SCI-Expanded)
- VII. **LinGraph: a graph-based automated planner for concurrent task planning based on linear logic**  
Kortik S., SARANLI U.  
APPLIED INTELLIGENCE, vol.47, no.3, pp.914-934, 2017 (SCI-Expanded)
- VIII. **Stability and control of planar compass gait walking with series-elastic ankle actuation**  
KERIMOGLU D., MORGUL O., SARANLI U.  
TRANSACTIONS OF THE INSTITUTE OF MEASUREMENT AND CONTROL, vol.39, no.3, pp.312-323, 2017 (SCI-Expanded)
- IX. **Approximate analytical solutions to the double-stance dynamics of the lossy spring-loaded inverted pendulum**  
SHAHBAZI M., SARANLI U., BABUSKA R., LOPES G. A. D.  
BIOINSPIRATION & BIOMIMETICS, vol.12, no.1, 2017 (SCI-Expanded)
- X. **Identification of a vertical hopping robot model via harmonic transfer functions**  
Uyanik I., Ankaralı M. M., Cowan N. J., SARANLI U., Morgul O.  
TRANSACTIONS OF THE INSTITUTE OF MEASUREMENT AND CONTROL, vol.38, no.5, pp.501-511, 2016 (SCI-Expanded)
- XI. **Experimental Validation of a Feed-Forward Predictor for the Spring-Loaded Inverted Pendulum Template**  
Uyanik I., Morgul O., SARANLI U.  
IEEE TRANSACTIONS ON ROBOTICS, vol.31, no.1, pp.208-216, 2015 (SCI-Expanded)
- XII. **Optimal control of a half-circular compliant legged monopod**  
AYDIN Y. O., SARANLI A., YAZICIOĞLU Y., SARANLI U., LEBLEBICIOGLU K.  
CONTROL ENGINEERING PRACTICE, vol.33, pp.10-21, 2014 (SCI-Expanded)
- XIII. **Reactive Planning and Control of Planar Spring-Mass Running on Rough Terrain**

- Arslan O., Saranli U.  
IEEE TRANSACTIONS ON ROBOTICS, vol.28, no.3, pp.567-579, 2012 (SCI-Expanded)
- XIV. **Model-Based Proprioceptive State Estimation for Spring-Mass Running**  
Gur O., Saranli U.  
ROBOTICS: SCIENCE AND SYSTEMS VII, pp.105-112, 2012 (SCI-Expanded)
- XV. **A Modular Real-Time Fieldbus Architecture for Mobile Robotic Platforms**  
Saranli U., Avci A., Oeztuerk M. C.  
IEEE TRANSACTIONS ON INSTRUMENTATION AND MEASUREMENT, vol.60, no.3, pp.916-927, 2011 (SCI-Expanded)
- XVI. **Control of underactuated planar pronking through an embedded spring-mass Hopper template**  
Ankarali M. M., Saranli U.  
AUTONOMOUS ROBOTS, vol.30, pp.217-231, 2011 (SCI-Expanded)
- XVII. **Analysis and Control of a Dissipative Spring-Mass Hopper with Torque Actuation**  
ANKARALI M. M., Saranli U.  
ROBOTICS: SCIENCE AND SYSTEMS VI, pp.41-48, 2011 (SCI-Expanded)
- XVIII. **Approximate analytic solutions to non-symmetric stance trajectories of the passive Spring-Loaded Inverted Pendulum with damping**  
Saranli U., Arslan O., Ankarali M. M., Morgul O.  
NONLINEAR DYNAMICS, vol.62, pp.729-742, 2010 (SCI-Expanded)
- XIX. **Stride-to-stride energy regulation for robust self-stability of a torque-actuated dissipative spring-mass hopper**  
Ankarali M. M., Saranli U.  
CHAOS, vol.20, 2010 (SCI-Expanded)
- XX. **Solving models of controlled dynamic planar rigid-body systems with frictional contact**  
GREENFIELD A., Saranli U., RIZZI A.  
INTERNATIONAL JOURNAL OF ROBOTICS RESEARCH, vol.24, no.11, pp.911-931, 2005 (SCI-Expanded)
- XXI. **Multi-point contact models for dynamic self-righting of a Hexapod**  
Saranli U., Rizzi A. A., Koditschek D. E.  
Springer Tracts in Advanced Robotics, vol.17, pp.409-424, 2005 (SCI-Expanded)
- XXII. **Model-based dynamic self-righting maneuvers for a hexapedal robot**  
Saranli U., RIZZI A., KODITSCHKEK D.  
INTERNATIONAL JOURNAL OF ROBOTICS RESEARCH, vol.23, no.9, pp.903-918, 2004 (SCI-Expanded)
- XXIII. **RHex: A biologically inspired hexapod runner**  
ALTENDORFER R., MOORE N., Komsuolu H., BUEHLER M., BROWN H., MCMORDIE D., Saranli U., FULL R., KODITSCHKEK D.  
AUTONOMOUS ROBOTS, vol.11, no.3, pp.207-213, 2001 (SCI-Expanded)
- XXIV. **RHex: A simple and highly mobile hexapod robot**  
Saranli U., Buehler M., Koditschek D.  
INTERNATIONAL JOURNAL OF ROBOTICS RESEARCH, vol.20, pp.616-631, 2001 (SCI-Expanded)
- XXV. **Evidence for spring loaded inverted pendulum running in a hexapod robot**  
ALTENDORFER R., Saranli U., KOMSUOGLU H., KODITSCHKEK D., BROWN H., BUEHLER M., MOORE N., MCMORDIE D., FULL R.  
EXPERIMENTAL ROBOTICS VII, vol.271, pp.291-302, 2001 (SCI-Expanded)

## Articles Published in Other Journals

- I. **Design, modeling and preliminary control of a compliant hexapod robot**  
Saranli U., Buehler M., Koditschek D. E.  
Proceedings-IEEE International Conference on Robotics and Automation, vol.3, pp.2589-2596, 2000 (Scopus)

## Books & Book Chapters

- I. **Analysis and control of a dissipative spring-mass hopper with torque actuation**  
Ankaralı M. M., Saranlı U.  
in: Robotics: Science and Systems VI, Yoky Matsuoka, Hugh Durrant-Whyte, José Neira, Editor, The MIT Press, Cambridge (MA), USA, Massachusetts, pp.41-48, 2011

## Refereed Congress / Symposium Publications in Proceedings

- I. **Characterization of Fixed Points of Spring-Mass Model with a Body Govde Eklenmis Yay-Kutle Modelinin Sabit Noktalarinin Karakterizasyonu**  
Karagoz O. K., Sever I., Dilsad Er G., SARANLI U., ANKARALI M. M.  
28th Signal Processing and Communications Applications Conference, SIU 2020, Gaziantep, Turkey, 5 - 07 October 2020
- II. **Analysis and Control of a Body-Attached Spring-Mass Runner Based on Central Pivot Point Approach**  
Karagoz O. K., Sever I., Saranlı U., Ankaralı M. M.  
IEEE/ASME International Conference on Advanced Intelligent Mechatronics (AIM), ELECTR NETWORK, 6 - 09 July 2020, pp.495-500
- III. **Modelling, control and design of a clutched parallel elastically actuated articulated robotic leg through virtual tunable damping**  
TANFENER E., CANDAN S. Ş., TURGUT A. E., SARANLI U.  
ASME 2020 International Mechanical Engineering Congress and Exposition, IMECE 2020, Virtual, Online, 16 - 19 November 2020, vol.7A-2020
- IV. **Characterization of Fixed Points of Spring-Mass Model With a Body**  
Karagoz O. K., Sever I., Er G. D., SARANLI U., ANKARALI M. M.  
28th Signal Processing and Communications Applications Conference (SIU), ELECTR NETWORK, 5 - 07 October 2020
- V. **Deadbeat Control of Running with the ATRIAS Biped Based on Spring-Mass Model with Trunk and Tunable Leg Damping**  
SEÇER G., SARANLI U.  
Dynamic Walking, Pensacola, Fl, United States Of America, 21 - 24 May 2018, pp.1-5
- VI. **Energy efficient control of a 1D hopper through tunable damping**  
SEÇER G., SARANLI U.  
Dynamic Walking, Michigan, United States Of America, 1 - 05 June 2017, pp.1-5
- VII. **Energy efficient control of planar monopodal running through tunable damping**  
Seçer G., SARANLI U.  
Dynamic Walking Conference, 4 - 07 July 2016
- VIII. **Parametric Identification of Hybrid Linear-Time-Periodic Systems**  
Uyanık I., SARANLI U., Morgul O., Aukarah M. M.  
6th IFAC Symposium on System Structure and Control (SSSC), İstanbul, Turkey, 22 - 24 June 2016, vol.49, pp.7-12
- IX. **Koltuk Değneklerinden Basınç ve İvme Ölçümleri ile Yeryüzü Tepki Kuvveti Tahmini**  
SEYLAN Ç., SARANLI U.  
Türkiye Robotbilim Konferansı, Turkey, 26 - 27 October 2015
- X. **Stability of a Compass Gait Walking Model with Series Elastic Ankle Actuation**  
Kerimoğlu D., Morgul O., SARANLI U.  
International Conference on Advanced Robotics (ICAR), İstanbul, Turkey, 27 - 31 July 2015, pp.351-356
- XI. **Toward Data-Driven Models of Legged Locomotion using Harmonic Transfer Functions**  
Uyanık I., Ankaralı M. M., Cowan N. J., Morgul O., SARANLI U.  
International Conference on Advanced Robotics (ICAR), İstanbul, Turkey, 27 - 31 July 2015, pp.357-362
- XII. **Extending The Lossy Spring-Loaded Inverted Pendulum Model with a Slider-Crank Mechanism**

- Orhon H. E., Odabas C., Uyanik I., Morgul O., SARANLI U.  
International Conference on Advanced Robotics (ICAR), İstanbul, Turkey, 27 - 31 July 2015, pp.99-104
- XIII. **Path Following with An Underactuated Self-Balancing Spherical-Wheel Mobile Robot**  
Inal A. N., Morgul O., SARANLI U.  
International Conference on Advanced Robotics (ICAR), İstanbul, Turkey, 27 - 31 July 2015, pp.194-199
- XIV. **Identifying Stability Properties of a Hybrid Spring–Mass–Damper via Piecewise LTI Approximation and Harmonic Transfer Functions**  
Uyanik İ., Ankaralı M. M., Cowan N., Morgül Ö., Saranlı U.  
Dynamic Walking 2015, Zürich, Switzerland, 21 - 24 July 2015
- XV. **Stability of Planar Compass Gait Walking with Series Elastic Ankle Actuation**  
Kerimoğlu D., MORGÜL Ö., SARANLI U.  
Dynamic Walking Conference, 20 - 24 July 2015
- XVI. **Independent estimation of input and measurement delays for a hybrid vertical spring-mass-damper via harmonic transfer functions**  
Uyamk I., Ankaralı M. M., Cowan N. J., Saranlı U., Morgül Ö., Özbay H.  
12th IFAC Workshop on Time Delay Systems, TDS 2015, Michigan, United States Of America, 28 - 30 June 2015, vol.28, pp.298-303
- XVII. **System Identification of Legged Locomotion via Harmonic Transfer Functions and Piecewise LTI Approximation**  
Uyanik İ., Ankaralı M. M., Cowan N., Morgül Ö., Saranlı U.  
Dynamic Walking 2014, Zürich, Switzerland, 10 - 13 June 2014
- XVIII. **Control of Hopping Through Active Virtual Tuning of Leg Damping for Serially Actuated Legged Robots**  
SEÇER G., SARANLI U.  
IEEE International Conference on Robotics and Automation (ICRA), Hong Kong, PEOPLES R CHINA, 31 May - 07 June 2014, pp.4556-4561
- XIX. **A Real-Time Inertial Motion Blur Metric: Application to Frame Triggering Based Motion Blur Minimization**  
Mutlu M., SARANLI A., SARANLI U.  
IEEE International Conference on Robotics and Automation (ICRA), Hong Kong, PEOPLES R CHINA, 31 May - 07 June 2014, pp.671-676
- XX. **Linear Planning Logic: An Efficient Language and Theorem Prover for Robotic Task Planning**  
Kortik S., SARANLI U.  
IEEE International Conference on Robotics and Automation (ICRA), Hong Kong, PEOPLES R CHINA, 31 May - 07 June 2014, pp.3764-3770
- XXI. **A Real-Time Inertial Motion Blur Metric**  
Mutlu M., SARANLI A., SARANLI U.  
22nd IEEE Signal Processing and Communications Applications Conference (SIU), Trabzon, Turkey, 23 - 25 April 2014, pp.2225-2228
- XXII. **Control of Monopedal Running Through Tunable Damping**  
SEÇER G., SARANLI U.  
21st Signal Processing and Communications Applications Conference (SIU), CYPRUS, 24 - 26 April 2013
- XXIII. **A 3D Dynamic Model of a Spherical Wheeled Self-Balancing Robot**  
Inal A. N., Morgul O., SARANLI U.  
25th IEEE\RSJ International Conference on Intelligent Robots and Systems (IROS), Algarve, Portugal, 7 - 12 October 2012, pp.5381-5386
- XXIV. **A DYNAMIC MODEL OF RUNNING WITH A HALF-CIRCULAR COMPLIANT LEG**  
Ankaralı M. M., SAYGINER E., YAZICIOĞLU Y., SARANLI A., SARANLI U.  
15th International Conference on Climbing and Walking Robots and the Support Technologies for Mobile Machines, Maryland, United States Of America, 23 - 26 July 2012, pp.425-432
- XXV. **TD-SLIP: A better predictive model for human running**

- Ankaralı M. M., Cowan N., Saranlı U.  
Dynamic Walking 2012, Florida, United States Of America, 21 - 24 May 2012
- XXVI. **Model-based proprioceptive state estimation for spring-mass running**  
Gür Ö., Saranlı U.  
International Conference on Robotics Science and Systems, RSS 2011, California, United States Of America, 27 June - 01 July 2011, vol.7, pp.105-112
- XXVII. **Adaptive Control of a Spring-Mass Hopper**  
Uyanık I., Saranlı U., Morgul O.  
IEEE International Conference on Robotics and Automation (ICRA), Shanghai, China, 9 - 13 May 2011, pp.2138-2143
- XXVIII. **Quadrupedal Bounding with an Actuated Spinal Joint**  
Culha U., Saranlı U.  
IEEE International Conference on Robotics and Automation (ICRA), Shanghai, China, 9 - 13 May 2011, pp.1392-1397
- XXIX. **Analysis And Control Of A Dissipative Spring-mass Hopper With Torque Actuation**  
ANKARALI M. M., SARANLI U.  
Robotics: Science And Systems, Zaragoza, Spain, 27 - 30 June 2010, pp.41-48
- XXX. **Control of Underactuated Planar Hexapedal Pronking Through a Dynamically Embedded SLIP Monopod**  
Ankaralı M. M., Saranlı U., SARANLI A.  
IEEE International Conference on Robotics and Automation (ICRA), Alaska, United States Of America, 3 - 08 May 2010, pp.4721-4727
- XXXI. **Reactive Footstep Planning for a Planar Spring Mass Hopper**  
Arslan O., Saranlı U., Morgul O.  
IEEE RSJ International Conference on Intelligent Robots and Systems, Missouri, United States Of America, 10 - 15 October 2009, pp.160-166
- XXXII. **An Analytical Solution to the Stance Dynamics of Passive Spring-Loaded Inverted Pendulum with Damping**  
ANKARALI M. M., Arslan O., Saranlı U.  
12th International Conference on Climbing and Walking Robots the Support Technologies for Mobile Machines (CLAWAR), İstanbul, Turkey, 9 - 11 September 2009, pp.693-700
- XXXIII. **An Approximate Stance Map of The Spring Mass Hopper with Gravity Correction For Nonsymmetric Locomotions**  
Arslan O., Saranlı U., Morgul O.  
IEEE International Conference on Robotics and Automation, Kobe, Japan, 12 - 17 May 2009, pp.1829-1830
- XXXIV. **Using constrained intuitionistic linear logic for hybrid robotic planning problems**  
Saranlı U., Pfenning F.  
IEEE International Conference on Robotics and Automation, Rome, Italy, 10 - 14 April 2007, pp.3705-3706
- XXXV. **Robotics in scansorial environments**  
AUTUMN K., BUEHLER M., CUTKOSKY M., FEARING R., FULL R., GOLDMAN D., GROFF R., PROVANCHER W., RIZZI A., Saranlı U., et al.  
Conference on Unmanned Ground Vehicle Technology VII, Florida, United States Of America, 29 - 31 March 2005, vol.5804, pp.291-302
- XXXVI. **Multi-point contact models for dynamic self-righting of a hexapod**  
Saranlı U., RIZZI A., KODITSCHKEK D.  
6th International Workshop on Algorithmic-Foundations-of-Robotics, Zeist, Netherlands, 11 - 13 July 2004, vol.17, pp.409-424
- XXXVII. **Template based control of hexapedal running**  
Saranlı U., KODITSCHKEK D.  
20th IEEE International Conference on Robotics and Automation (ICRA), Taipei, Taiwan, 14 - 19 September 2003, pp.1374-1379

**XXXVIII. Back flips with a hexapedal robot**

Saranli U., KODITSCHEK D.

19th IEEE International Conference on Robotics and Automation (ICRA), Washington, Kiribati, 11 - 15 May 2002, pp.2209-2215

**XXXIX. Evidence for Spring Loaded Inverted Pendulum Running in a Hexapod Robot**

Altendorfer R., SARANLI U., Komsuoğlu H., Koditschek D. E., Brown H. B., Buehler M., Moore N., McMordie D., Full R. International Symposium on Experimental Robotics, 11 - 13 December 2000

**XL. Proprioception based behavioral advances in a hexapod robot**

Komsuoğlu H., McMordie D., Saranli S., Moore N., Buehler M., Koditschek D.

IEEE International Conference on Robotics and Automation, Seoul, South Korea, 21 - 26 May 2001, pp.3650-3655

**XLI. Toward the control of a multi-jointed, monoped runner**

Saranli U., SCHWIND W., KODITSCHEK D.

IEEE International Conference on Robotics and Automation, Leuven, Belgium, 16 - 20 May 1998, pp.2676-2682

## Supported Projects

SARANLI U., Project Supported by Higher Education Institutions, Küresel tekerlekli mobil robotlarda denge, yöreüne kontrolü ve yol planlaması, 2013 - 2019

## Patent

SARANLI U., Single actuator per leg robotic hexapod, Patent, CHAPTER F Mechanical engineering; Lighting; Heating; Weaponry; Destroyed Materials, Standard Registration, 2002

## Scientific Refereeing

International Journal on Robotics Research, National Scientific Refreed Journal, April 2018

## Metrics

Publication: 70

Citation (WoS): 1936

Citation (Scopus): 1929

H-Index (WoS): 15

H-Index (Scopus): 16

## Congress and Symposium Activities

IEEE International Conference on Robotics and Intelligent Systems, Invited Speaker, Madrid, Spain, 2018