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Kişisel Bilgiler

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Eğitim Bilgileri

Doktora, The University of Michigan, Electrical Engineering And Computer Science, Amerika Birleşik Devletleri 1998 - 2002
Yüksek Lisans, University of Michigan, Mühendislik Fakültesi, Bilgisayar Bilimleri, Amerika Birleşik Devletleri 1996 - 1998
Lisans, Orta Doğu Teknik Üniversitesi, Mühendislik Fakültesi, Elektrik-Elektronik Mühendisliği Bölümü, Türkiye 1992 - 1996

Yabancı Diller

İngilizce, C1 İleri

Yaptığı Tezler

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

Araştırma Alanları

Makina Mühendisliği, Makina Teorisi ve Dinamiği, Robotik , Mühendislik ve Teknoloji

Akademik Unvanlar / Görevler

Prof. Dr., Orta Doğu Teknik Üniversitesi, Mühendislik Fakültesi, Bilgisayar Mühendisliği Bölümü, 2018 - Devam Ediyor
Doç. Dr., Orta Doğu Teknik Üniversitesi, Mühendislik Fakültesi, Bilgisayar Mühendisliği Bölümü, 2012 - 2018
Yrd. Doç. Dr., Orta Doğu Teknik Üniversitesi, Mühendislik Fakültesi, Bilgisayar Mühendisliği Bölümü, 2012 - 2012
Yrd. Doç. Dr., İhsan Doğramacı Bilkent Üniversitesi, Mühendislik Fakültesi, Bilgisayar Mühendisliği Bölümü, 2005 - 2012
Öğretim Görevlisi Dr., Carnegie Mellon University, Faculty Of Engineering, Robotics Institute, 2002 - 2005
Araştırma Görevlisi, The University of Michigan, Faculty Of Engineering, Electrical Engineering And Computer Science, 1996 - 2002

Yönetilen Tezler

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

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

SARANLI U., Yay kütleli koşunun sanal bacak sönümlenme katsayısı aracılığı ile kontrolü, Doktora, G.Seçer(Öğrenci), 2020

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

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

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

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

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

SARANLI A., SARANLI U., Özgün gerçek zamanli ataletsel hareket bulanikliği ölçeği ve hareket bulanikliği giderme üzerine uygulamalari., Yüksek Lisans, M.Mutlu(Öğrenci), 2014

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

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

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

SARANLI U., Modeling of flexible needle ınsertion ın moving tissue, Yüksek Lisans, A.DENİZ(Öğrenci), 2012

SARANLI U., An actuated flexible spinal mechanism for a bounding quadrupedal robot, Yüksek Lisans, U.ÇULHA(Öğrenci), 2012

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

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

SARANLI U., Detection of tree trunks as visual landmarks in outdoor environments, Yüksek Lisans, T.YILDIZ(Öğrenci), 2010

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

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

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

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

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

SARANLI U., Line segment based range scan matching without pose information for indoor environments, Yüksek Lisans, İ.YAKIN(Öğrenci), 2008

SARANLI U., The universal robot bus: A local communication infrastructure for small robots, Yüksek Lisans, A.AVCI(Öğrenci), 2008

SCI, SSCI ve AHCI İndekslerine Giren Dergilerde Yayınlanan Makaleler

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, cilt.16, sa.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, cilt.131, sa.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, cilt.96, sa.2, ss.179-191, 2019 (SCI-Expanded)

IV. **Frequency-Domain Subspace Identification of Linear Time-Periodic (LTP) Systems**
Uyanık İ., Saranlı U., Ankaralı M. M., Cowan N., Morgül Ö.
IEEE TRANSACTIONS ON AUTOMATIC CONTROL, cilt.64, ss.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, cilt.34, sa.5, ss.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, cilt.67, sa.6, ss.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, cilt.47, sa.3, ss.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, cilt.39, sa.3, ss.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, cilt.12, sa.1, 2017 (SCI-Expanded)

X. **Identification of a vertical hopping robot model via harmonic transfer functions**
Uyanik I., Ankarali M. M., Cowan N. J., SARANLI U., Morgul O.
TRANSACTIONS OF THE INSTITUTE OF MEASUREMENT AND CONTROL, cilt.38, sa.5, ss.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, cilt.31, sa.1, ss.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, cilt.33, ss.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, cilt.28, sa.3, ss.567-579, 2012 (SCI-Expanded)

XIV. **Model-Based Proprioceptive State Estimation for Spring-Mass Running**
Gur O., Saranli U.
ROBOTICS: SCIENCE AND SYSTEMS VII, ss.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, cilt.60, sa.3, ss.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, cilt.30, ss.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, ss.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, cilt.62, ss.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, cilt.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, cilt.24, sa.11, ss.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, cilt.17, ss.409-424, 2005 (SCI-Expanded)

XXII. **Model-based dynamic self-righting maneuvers for a hexapedal robot**
Saranli U., RIZZI A., KODITSCHEK D.
INTERNATIONAL JOURNAL OF ROBOTICS RESEARCH, cilt.23, sa.9, ss.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., KODITSCHEK D.
AUTONOMOUS ROBOTS, cilt.11, sa.3, ss.207-213, 2001 (SCI-Expanded)

XXIV. **RHex: A simple and highly mobile hexapod robot**
Saranli U., Buehler M., Kodıtschek D.
INTERNATIONAL JOURNAL OF ROBOTICS RESEARCH, cilt.20, ss.616-631, 2001 (SCI-Expanded)

XXV. **Evidence for spring loaded inverted pendulum running in a hexapod robot**
ALTENDORFER R., Saranli U., KOMSUOGLU H., KODITSCHEK D., BROWN H., BUEHLER M., MOORE N., MCMORDIE D., FULL R.
EXPERIMENTAL ROBOTICS VII, cilt.271, ss.291-302, 2001 (SCI-Expanded)

Diğer Dergilerde Yayınlanan Makaleler

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, cilt.3, ss.2589-2596, 2000 (Scopus)

Kitap & Kitap Bölümleri

I. **Analysis and control of a dissipative spring-mass hopper with torque actuation**
Ankaralı M. M., Saranlı U.
Robotics: Science and Systems VI, Yoky Matsuoka,Hugh Durrant-Whyte,José Neira, Editör, The MIT Press,

Cambridge (MA), USA , Massachusetts, ss.41-48, 2011

Hakemli Kongre / Sempozyum Bildiri Kitaplarında Yer Alan Yayınlar

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, Türkiye, 5 - 07 Ekim 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 Temmuz 2020, ss.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 Kasım 2020, cilt.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 Ekim 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, Amerika Birleşik Devletleri, 21 - 24 Mayıs 2018, ss.1-5

VI. **Energy efficient control of a 1D hopper through tunable damping**
SEÇER G., SARANLI U.
Dynamic Walking, Michigan, Amerika Birleşik Devletleri, 1 - 05 Haziran 2017, ss.1-5

VII. **Energy efficient control of planar monopedal running through tunable damping**
Seçer G., SARANLI U.
Dynamic Walking Conference, 4 - 07 Temmuz 2016

VIII. **Parametric Identification of Hybrid Linear-Time-Periodic Systems**
Uyanik I., SARANLI U., Morgul O., Aukarah M. M.
6th IFAC Symposium on System Structure and Control (SSSC), İstanbul, Türkiye, 22 - 24 Haziran 2016, cilt.49, ss.7-12

IX. **Koltuk Değneklerinden Basınç ve İvme Ölçümleri ile Yeryüzü Tepki Kuvveti Tahmini**
SEYLAN Ç., SARANLI U.
Türkiye Robotbilim Konferansı, Türkiye, 26 - 27 Ekim 2015

X. **Stability of a Compass Gait Walking Model with Series Elastic Ankle Actuation**
Kerimoglu D., Morgul O., SARANLI U.
International Conference on Advanced Robotics (ICAR), İstanbul, Türkiye, 27 - 31 Temmuz 2015, ss.351-356

XI. **Toward Data-Driven Models of Legged Locomotion using Harmonic Transfer Functions**
Uyanik I., Ankarali M. M., Cowan N. J., Morgul O., SARANLI U.
International Conference on Advanced Robotics (ICAR), İstanbul, Türkiye, 27 - 31 Temmuz 2015, ss.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, Türkiye, 27 - 31 Temmuz 2015, ss.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, Türkiye, 27 - 31 Temmuz 2015, ss.194-199

XIV. **Identifying Stability Properties of a Hybrid Spring–Mass–Damper via Piecewise LTI Approximation and Harmonic Transfer Functions**
Uyanık İ., Ankaralı M. M., Cowan N., Morgül Ö., Saranlı U.
Dynamic Walking 2015, Zürich, İsviçre, 21 - 24 Temmuz 2015

XV. **Stability of Planar Compass Gait Walking with Series Elastic Ankle Actuation**
Kerimoğlu D., MORGÜL Ö., SARANLI U.
Dynamic Walking Conference, 20 - 24 Temmuz 2015

XVI. **Independent estimation of input and measurement delays for a hybrid vertical spring-mass-damper via harmonic transfer functions**
Uyamk I., Ankarali M. M., Cowan N. J., Saranli U., Morgül Ö., Özbay H.
12th IFAC Workshop on Time Delay Systems, TDS 2015, Michigan, Amerika Birleşik Devletleri, 28 - 30 Haziran 2015, cilt.28, ss.298-303

XVII. **System Identification of Legged Locomotion via Harmonic Transfer Functions and Piecewise LTI Approximation**
Uyanık İ., Ankaralı M. M., Cowan N., Morgül Ö., Saranlı U.
Dynamic Walking 2014, Zürich, İsviçre, 10 - 13 Haziran 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 Mayıs - 07 Haziran 2014, ss.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 Mayıs - 07 Haziran 2014, ss.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 Mayıs - 07 Haziran 2014, ss.3764-3770

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Mutlu M., SARANLI A., SARANLI U.
22nd IEEE Signal Processing and Communications Applications Conference (SIU), Trabzon, Türkiye, 23 - 25 Nisan 2014, ss.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 Nisan 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, Portekiz, 7 - 12 Ekim 2012, ss.5381-5386

XXIV. **A DYNAMIC MODEL OF RUNNING WITH A HALF-CIRCULAR COMPLIANT LEG**
Ankarali 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, Amerika Birleşik Devletleri, 23 - 26 Temmuz 2012, ss.425-432

XXV. **TD-SLIP: A better predictive model for human running**
Ankaralı M. M., Cowan N., Saranlı U.
Dynamic Walking 2012, Florida, Amerika Birleşik Devletleri, 21 - 24 Mayıs 2012

XXVI. **Model-based proprioceptive state estimation for spring-mass running**
Gür Ö., Saranli U.
International Conference on Robotics Science and Systems, RSS 2011, California, Amerika Birleşik Devletleri, 27

Haziran - 01 Temmuz 2011, cilt.7, ss.105-112

XXVII. **Adaptive Control of a Spring-Mass Hopper**
Uyanik I., Saranli U., Morgul O.
IEEE International Conference on Robotics and Automation (ICRA), Shanghai, Çin, 9 - 13 Mayıs 2011, ss.2138-2143

XXVIII. **Quadrupedal Bounding with an Actuated Spinal Joint**
Culha U., Saranli U.
IEEE International Conference on Robotics and Automation (ICRA), Shanghai, Çin, 9 - 13 Mayıs 2011, ss.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, İspanya, 27 - 30 Haziran 2010, ss.41-48

XXX. **Control of Underactuated Planar Hexapedal Pronking Through a Dynamically Embedded SLIP Monopod**
Ankaralı M. M., Saranli U., SARANLI A.
IEEE International Conference on Robotics and Automation (ICRA), Alaska, Amerika Birleşik Devletleri, 3 - 08 Mayıs 2010, ss.4721-4727

XXXI. **Reactive Footstep Planning for a Planar Spring Mass Hopper**
Arslan O., Saranli U., Morgul O.
IEEE RSJ International Conference on Intelligent Robots and Systems, Missouri, Amerika Birleşik Devletleri, 10 - 15 Ekim 2009, ss.160-166

XXXII. **An Analytical Solution to the Stance Dynamics of Passive Spring-Loaded Inverted Pendulum with Damping**
ANKARALI M. M., Arslan O., Saranli U.
12th International Conference on Climbing and Walking Robots the Support Technologies for Mobile Machines (CLAWAR), İstanbul, Türkiye, 9 - 11 Eylül 2009, ss.693-700

XXXIII. **An Approximate Stance Map of The Spring Mass Hopper with Gravity Correction For Nonsymmetric Locomotions**
Arslan O., Saranli U., Morgul O.
IEEE International Conference on Robotics and Automation, Kobe, Japonya, 12 - 17 Mayıs 2009, ss.1829-1830

XXXIV. **Using constrained intuitionistic linear logic for hybrid robotic planning problems**
Saranli U., Pfenning F.
IEEE International Conference on Robotics and Automation, Rome, İtalya, 10 - 14 Nisan 2007, ss.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., Saranli U., et al.
Conference on Unmanned Ground Vehicle Technology VII, Florida, Amerika Birleşik Devletleri, 29 - 31 Mart 2005, cilt.5804, ss.291-302

XXXVI. **Multi-point contact models for dynamic self-righting of a hexapod**
Saranli U., RIZZI A., KODITSCHEK D.
6th International Workshop on Algorithmic-Foundations-of-Robotics, Zeist, Hollanda, 11 - 13 Temmuz 2004, cilt.17, ss.409-424

XXXVII. **Template based control of hexapedal running**
Saranli U., KODITSCHEK D.
20th IEEE International Conference on Robotics and Automation (ICRA), Taipei, Tayvan, 14 - 19 Eylül 2003, ss.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 Mayıs 2002, ss.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 Aralık 2000

XL. **Proprioception based behavioral advances in a hexapod robot**
Komsuoglu H., McMordie D., Saranli S., Moore N., Buehler M., Koditschek D.
IEEE International Conference on Robotics and Automation, Seoul, Güney Kore, 21 - 26 Mayıs 2001, ss.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, Belçika, 16 - 20 Mayıs 1998, ss.2676-2682

Desteklenen Projeler

SARANLI U., Yükseköğretim Kurumları Destekli Proje, Küresel tekerlekli mobil robotlarda denge, yörünge kontrolü ve yol planlaması, 2013 - 2019

Patent

SARANLI U., Single actuator per leg robotic hexapod, Patent, BÖLÜM F Makine Mühendisliği; Aydınlatma; Isıtma; Silahlar; Tahrip Malzemeleri, Standart Tescil, 2002

Bilimsel Hakemlikler

International Journal on Robotics Research, Hakemli Bilimsel Dergi, Nisan 2018

Metrikler

Yayın: 70
Atıf (WoS): 1936
Atıf (Scopus): 1929
H-İndeks (WoS): 15
H-İndeks (Scopus): 16

Kongre ve Sempozyum Katılımı Faaliyetleri

IEEE International Conference on Robotics and Intelligent Systems, Davetli Konuşmacı, Madrid, İspanya, 2018