

**Lista de lucrări**

Categorii / subcategorii	Cod	Autori, Titlul lucrării, Editura, revista sau conferința, pagini, anul apariției	Nr. autori / Nr. ani	FI (actual, pt. 2018)	Punctaj
A.1.1.1. Cărți de autor sau capitole [1] de specialitate în edituri cu ISBN din străinătate [1] Capitolul de carte să NU fie într-un volum de conferință. Punctaj capitol = 1/4 din punctaj pt. categoria respectivă	Ci1	M. Kloetzer, Symbolic Motion Planning and Control, Ed. ProQuest, USA, 145 pg., 2008, ISBN: 9780549547297.	1		50.00
	Ci2	C. Mahulea, M. Kloetzer, and R. Gonzalez. Path Planning of Cooperative Mobile Robots Using Discrete Event Models, Editura Wiley-IEEE Press, IEEE Press Series on Systems Science and Engineering, editor serie Mengchu Zhou, 212 pg., 2020, ISBN: 9781119486329.	1		50.00
	<b>Total A1.1.1</b>				<b>100.00</b>
A.1.1.2. Cărți de autor sau capitole [1] de specialitate în edituri cu ISBN din țară [1] Capitolul de carte să NU fie într-un volum de conferință. Punctaj capitol = 1/4 din punctaj pt. categoria respectivă	Cn1	M. Kloetzer, L. Mirea, O. Păstrăvanu: Sisteme liniare continue, Ed. Politehnicum, Iași, 340 pg., 2014, ISBN: 978-973-621-422-6.	3		16.67
	Cn2	A. Burlacu, M. Kloetzer: Controlul Sistemelor Mobile cu Roți, Ed. Performantica, Iași, 120 pg., 2014, ISBN: 978-606-685-157-2.	2		25.00
	<b>Total A1.1.2</b>				<b>41.67</b>
A1.2.1. Material didactic / Lucrări didactice publicate în edituri cu ISBN	M1	M. Kloetzer, O. Păstrăvanu, Instrumente MATLAB în studierea dinamicilor modelabile liniar, Ed. Politehnicum, Iași, 158 pg., 2014, ISBN: 978-973-621-425-7.	2		20.00
	M2	M. Kloetzer, Strategii de planificare automată a roboților mobili, Ed. Matrix Rom, București, 89 pg., 2012, ISBN: 978-973-755-791-9.	1		40.00
	<b>Total A1.2</b>				<b>60.00</b>
	ISI1	M. Kloetzer and C. Belta, Temporal Logic Planning and Control of Robotic Swarms by Hierarchical Abstractions, IEEE Transactions on Robotics, vol. 23 (2), pp. 320-331, 2007. (Q1 pt. 2018)	2	6.483	109.75
	ISI2	M. Kloetzer and C. Belta, A Fully Automated Framework for Control of Linear Systems From Temporal Logic Specifications, IEEE Transactions on Automatic Control, vol. 53 (1), pp. 287-297, 2008. (Q1 pt. 2018)	2	5.093	88.90
	ISI3	M. Kloetzer and C. Belta, Reachability analysis of multi-affine systems, Transactions of the Institute of Measurement and Control, vol. 32 (5), pp. 445-467, 2010.	2	1.956	41.84
	ISI4	M. Kloetzer and C. Belta, Automatic Deployment of Distributed Teams of Robots From Temporal Logic Motion Specifications, IEEE Transactions on Robotics, vol. 26 (1), pp. 48-61, 2010. (Q1 pt. 2018)	2	6.483	109.75
	ISI5	M. Kloetzer, C. Mahulea, C. Belta, and M. Silva, An Automated Framework for Formal Verification of Timed Continuous Petri Nets, IEEE Transactions on Industrial Informatics, vol. 6 (3), pp. 460-471, 2010. (Q1 pt. 2018)	4	7.377	61.58
	ISI6	X.C. Ding, M. Kloetzer, Y. Chen, and C. Belta, Automatic Deployment of Robotic Teams, IEEE Robotics & Automation Magazine, vol. 18 (3), pp. 75-86, 2011. (Q1 pt. 2018)	4	4.25	38.13
	ISI7	D. Panescu, M. Kloetzer, A. Burlacu and C. Pascal, Artificial Intelligence based Solutions for Cooperative Mobile Robots, Journal of Control Engineering and Applied Informatics, vol. 14 (1), pp. 74-82, 2012.	4	0.583	10.62
	ISI8	N. Ghița and M. Kloetzer, Trajectory Planning for a Car-Like Robot by Environment Abstraction, Robotics and Autonomous Systems, vol. 60 (4), pp. 609-619, 2012. (Q2 pt. 2018)	2	2.928	56.42
	ISI9	M. Kloetzer and C. Mahulea, A Petri net based approach for multi-robot path planning, Discrete Event Dynamic Systems: Theory and Applications, vol. 24 (4), pp. 417-445, 2014. (Q2 pt. 2018)	2	1.128	29.42
	ISI10	M. Kloetzer and C. Mahulea, LTL-based Planning in Environments with Probabilistic Observations, IEEE Transactions on Automation Science and Engineering, vol. 12 (4), pp. 1407-1420, 2015. (Q1 pt. 2018)	2	5.224	90.86
	ISI11	C. Mahulea and M. Kloetzer, Robot Planning Based on Boolean Specifications Using Petri Net Models, IEEE Transactions on Automatic Control, vol. 63 (7), pp. 2218-2225, 2018. (Q1 pt. 2018)	2	5.093	88.90
	ISI12	A. Burlacu, M. Kloetzer and C. Mahulea, Numerical Evaluation of Sample Gathering Solutions for Mobile Robots, Applied Sciences-Basel, vol. 9 (4), art. 791, 2019. (Q2 pt. 2018)	3	2.217	30.50
	ISI13	M. Kloetzer and C. Mahulea, Path planning for robotic teams based on LTL specifications and Petri net models, Discrete Event Dynamic Systems, vol. 30 (1), pp. 55-79, 2020. (Q2 pt. 2018)	2	1.128	29.42
	ISI14	M. Kloetzer and C. Belta, Hierarchical abstractions for robotic swarms, IEEE International Conference on Robotics and Automation (ICRA), Orlando, FL, USA, pp. 952-957, 2006.	2	0.25	16.25
	ISI15	M. Kloetzer and C. Belta, A framework for automatic deployment of robots in 2D and 3D environments, IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS), Beijing, China, pp. 953-958, 2006.	2	0.25	16.25
	ISI16	M. Kloetzer and C. Belta, LTL planning for groups of robots, IEEE International Conference on Networking, Sensing, and Control (ICNSC), Ft. Lauderdale, FL, USA, pp. 578-583, 2006.	2	0.25	16.25
	ISI17	M. Kloetzer and C. Belta, A fully automated framework for control of linear systems from LTL specifications, International Workshop on Hybrid Systems: Computation and Control (HSCC), Santa Barbara, CA, USA, pp. 333-347, LNCS 3927, 2006.	2	0.25	16.25
	ISI18	M. Kloetzer and C. Belta, Reachability analysis of multi-affine systems, International Workshop on Hybrid Systems: Computation and Control (HSCC), Santa Barbara, CA, USA, pp. 348-362, LNCS 3927, 2006.	2	0.25	16.25
	ISI19	L.C.G.J.M. Habets, M. Kloetzer, and C. Belta, Control of rectangular multi-affine hybrid systems, 45th IEEE Conference on Decision and Control (CDC), San Diego, CA, USA, pp. 2619-2624, 2006.	3	0.25	10.83
	ISI20	M. Kloetzer and C. Belta, Managing non-determinism in symbolic robot motion planning and control, IEEE International Conference on Robotics and Automation (ICRA), pp. 3110-3115, Rome, Italy, 2007.	2	0.25	16.25

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A2.1. Articole în reviste cotate ISI și lucrări în volumele unor manifestări științifice indexate ISI	ISI21	M. Kloetzer and C. Belta, Distributed implementations of global temporal logic motion specifications, IEEE Int. Conf. on Robotics and Automation (ICRA), Pasadena, CA, USA, pp. 393-398, 2008.	2	0.25	16.25
	ISI22	M. Kloetzer, C. Mahulea, C. Belta, L. Recalde and M. Silva, Formal analysis of timed continuous Petri nets, IEEE Conference on Decision and Control (CDC), Cancun, Mexico, pp. 245-250, 2008.	5	0.25	6.50
	ISI23	M. Kloetzer and C. Belta, Dealing with nondeterminism in symbolic control, International Workshop on Hybrid Systems: Computation and Control (HSCC), St. Louis, MO, USA, pp. 287-300, LNCS 4981, 2008.	2	0.25	16.25
	ISI24	M. Lahijanian, M. Kloetzer, S. Itani, C. Belta and S. Andersson, Automatic deployment of autonomous cars in a robotic urban-like environment (RULE), IEEE International Conference on Robotics and Automation (ICRA), Kobe, Japan, pp. 2055-2060, 2009.	5	0.25	6.50
	ISI25	M. Kloetzer, S. Itani, S. Birch, and C. Belta, On the Need for Communication in Distributed Implementations of LTL Motion Specifications, IEEE International Conference on Robotics and Automation (ICRA), Anchorage, Alaska, USA, pp. 4451-4456, 2010.	4	0.25	8.13
	ISI26	A. Burlacu, M. Kloetzer, and D. Panescu, Some AI Based Approaches on Mobile Robots Motion Planning, International Conference on Robotics and Automation Systems, Cluj Napoca, Romania, 2010.	3	0.25	10.83
	ISI27	M. Kloetzer, C. Mahulea, O. Pastravanu, A Probabilistic Abstraction Approach for Planning and Controlling Mobile Robots, IEEE Conference on Emerging Technologies & Factory Automation (ETFA), Toulouse, France, 2011.	3	0.25	10.83
	ISI28	M. Kloetzer, X.C. Ding, C. Belta, Multi-robot Deployment From LTL Specifications with Reduced Communication, IEEE Conference on Decision and Control (CDC), Orlando, FL, USA, 2011.	3	0.25	10.83
	ISI29	C. Mahulea, M. Kloetzer, Online Petri Net Based Algorithm for Planning and Controlling Mobile Robots, IEEE Conference on Emerging Technologies & Factory Automation (ETFA), Krakow, Poland, 2012.	2	0.25	16.25
	ISI30	V. Tiganas, M. Kloetzer, A. Burlacu, Multi-robot based implementation for a sample gathering problem, 17th International Conference on System Theory, Control, and Computing (ICSTCC), Sinaia, Romania, pp. 545-550, 2013.	3	0.25	10.83
	ISI31	A. Burlacu, M. Kloetzer, F. Ostafi, Optimal multi-agent planning solution for a sample gathering problem, IEEE International Conference on Automation, Quality and Testing, Robotics (AQTR), Cluj-Napoca, Romania, pp. 1-5, 2014.	3	0.25	10.83
	ISI32	M. Kloetzer, C. Mahulea, An Assembly Problem with Mobile Robots, IEEE Conference on Emerging Technologies & Factory Automation (ETFA), Barcelona, Spain, pp. 1-7, 2014.	2	0.25	16.25
	ISI33	C. Mahulea, M. Kloetzer, Planning Mobile Robots with Boolean-based Specifications, IEEE Conference on Decision and Control (CDC), Los Angeles, CA, USA, pp. 5137-5142, 2014.	2	0.25	16.25
	ISI34	M. Kloetzer, C. Mahulea, Accomplish Multi-Robot Tasks Via Petri Net Models, IEEE International Conference on Automation Science and Engineering (CASE), Gothenberg, Sweden, pp. 304-309, 2015.	2	0.25	16.25
	ISI35	R. Gonzalez, C. Mahulea, M. Kloetzer, A Matlab-Based Interactive Simulator for Mobile Robotics, IEEE International Conference on Automation Science and Engineering (CASE), Gothenberg, Sweden, pp. 310-315, 2015.	3	0.25	10.83
	ISI36	A.E. Cozma, V.G. Seliman, A. Burlacu, M. Kloetzer, Numerical simulations and comparative study for auction-based sample gathering solutions, International Conference on System Theory, Control and Computing (ICSTCC), Cheile Gradistei, Romania, pp.93-98, 2015.	4	0.25	8.13
	ISI37	M. Kloetzer, C. Mahulea, R. Gonzalez, Optimizing Cell Decomposition Path Planning for Mobile Robots Using Different Metrics, International Conference on System Theory, Control and Computing (ICSTCC), Cheile Gradistei, Romania, pp.565-570, 2015.	3	0.25	10.83
	ISI38	X. Wang, M. Kloetzer, C. Mahulea, M. Silva, Collision avoidance of mobile robots by using initial time delays, 54th IEEE Conference on Decision and Control (CDC), Osaka, Japan, 2015.	4	0.25	8.13
	ISI39	M. Kloetzer, C. Mahulea, A. Burlacu, Sample gathering problem for different robots with limited capacity, International Conference on System Theory, Control and Computing (ICSTCC), Sinaia, Romania, pp. 490-495, 2016.	3	0.25	10.83
	ISI40	A. Zapodeanu, A. Burlacu, M. Kloetzer, On some implementation issues in robot-to-area allocation problems, International Conference on System Theory, Control and Computing (ICSTCC), Sinaia, Romania, pp. 496-501, 2016.	3	0.25	10.83
	ISI41	J. Lamarca, M. Kloetzer, C. Mahulea, Inexpensive robot for experimental validation of planning and control algorithms, International Conference on System Theory, Control and Computing (ICSTCC), Sinaia, Romania, pp. 502-507, 2016.	3	0.25	10.83
	ISI42	M. Kloetzer, C. Mahulea, Multi-robot path planning for syntactically co-safe LTL specifications, 13th International Workshop on Discrete Event Systems (WODES), Xi'an, China, pp. 452-458, 2016.	2	0.25	16.25
	ISI43	R. Gonzalez, M. Kloetzer, C. Mahulea, Comparative study of trajectories resulted from cell decomposition path planning approaches, International Conference on System Theory, Control and Computing (ICSTCC), Sinaia, Romania, pp. 49-54, 2017.	3	0.25	10.83
	ISI44	E. Vitolo, C. Mahulea, M. Kloetzer, A computationally efficient solution for path planning of mobile robots with boolean specifications, International Conference on System Theory, Control and Computing (ICSTCC), Sinaia, Romania, pp. 63-69, 2017.	3	0.25	10.83
	ISI45	L. Parrilla, C. Mahulea, M. Kloetzer, RMTTool: recent enhancements, 20th World Congress of the International-Federation-of-Automatic-Control (IFAC), Toulouse, France, IFAC-PapersOnLine vol. 50 (1), pp. 5824-5830, 2017.	3	0.25	10.83
	ISI46	E. Vitolo, C. Mahulea, M. Kloetzer, Path-planning in Discretized Environments with Optimized Waypoints Computation, 23rd International Conference on Emerging Technologies and Factory Automation (ETFA), Torino, Italy, pp. 729-735, 2018.	3	0.25	10.83
ISI47	S. Hustiu, M. Lupascu, S. Popescu, A. Burlacu, M. Kloetzer, Stable hovering architecture for nanoquadcopter applications in indoor environments, 22nd International Conference on System Theory, Control and Computing (ICSTCC), Sinaia, Romania, pp. 659-663, 2018.	5	0.25	6.50	

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<b>Total A2.1</b>				<b>58.443</b>	<b>1203.69</b>
<b>A2.2 Articole în reviste și în volumele unor manifestări științifice indexate în alte baze de date internaționale recunoscute (BDI) [4]</b> [4] Baze de date recunoscute: ISI, Scopus, IEEE (Institute of Electrical and Electronics Engineers) Xplore, Science Direct, Elsevier, Springerlink, ACM (Association for Computing Machinery), DBLP, EURASIP, Wiley, Inspec	BDI1	C. Lazăr, S. Cărați, D. Vrabie and M. Kloetzer, Neuro-predictive control based self-tuning of PID controllers, ESANN'2004: European Symposium on Artificial Neural Networks, Bruges, Belgium, pp. 391-395, 2004.	4		5.00
	BDI2	M. Kloetzer and C. Belta, Control of multi-robot teams based on LTL specifications, 4th IFAC Conference on Management and Control of Production and Logistics (MCPL), pp. 103-108, Sibiu, Romania, 2007.	2		10.00
	BDI3	N. Ghita and M. Kloetzer, Cell Decomposition-Based Strategy for Planning and Controlling a Car-like Robot, Proceedings of the 14th International Conference on System Theory and Control (ICSTCC), Sinaia, pp. 225-230, 2010.	2		10.00
	BDI4	M. Kloetzer and N. Ghita, Software Tool for Constructing Cell Decompositions, 7th IEEE Conference on Automation Science and Engineering (CASE), Trieste, Italy, pp. 507-512, 2011.	2		10.00
	BDI5	N. Ghita, M. Kloetzer, and O. Pastravanu, Probabilistic Car-Like Robot Path Planning from Temporal Logic Specifications, 15th International Conference on System Theory, Control, and Computing (ICSTCC), Sinaia, Romania, pp. 267-271, 2011.	3		6.67
	BDI6	M. Kloetzer, A. Burlacu, and D. Panescu, On a Class of Multi-Robot Task Allocation Problems, 14th IFAC Symposium Information Control Problems in Manufacturing (INCOM), Bucharest, Romania, pp. 841-846, 2012.	3		6.67
	BDI7	M. Kloetzer and C. Mahulea, LTL planning in dynamic environments, 11th IFAC Int. Workshop on Discrete Event Systems (WODES), Guadalajara, Mexico, pp. 294-300, 2012.	2		10.00
	BDI8	M. Kloetzer, S. Magdici, A. Burlacu, Experimental platform and Matlab toolbox for planning mobile robots, 16th International Conference on System Theory, Control, and Computing (ICSTCC), Sinaia, Romania, pp. 1-6, 2012.	3		6.67
	BDI9	M. Kloetzer, C. Mahulea and J.M. Colom, Petri net approach for deadlock prevention in robot planning, 18th IEEE International Conference on Emerging Technologies and Factory Automation (ETFA), Calgary, Italy, pp. 1-4, 2013.	3		6.67
	BDI10	M. Kloetzer, F. Ostafi, A. Burlacu, Trading optimality for computational feasibility in a sample gathering problem, International Conference on System Theory, Control, and Computing (ICSTCC), Sinaia, Romania, pp. 151-156, 2014.	3		6.67
	BDI11	C. Budaciu, N. Botezatu, M. Kloetzer, A. Burlacu, On the evaluation of the Crazyflie modular quadcopter system, 24th IEEE International Conference on Emerging Technologies and Factory Automation (ETFA), Zaragoza, Spain, pp. 1189-1195, 2019.	4		5.00
	BDI12	M. Kloetzer, A. Burlacu, G. Enescu, S. Caraiman, C. Mahulea, Optimal indoor goods delivery using drones, 24th IEEE International Conference on Emerging Technologies and Factory Automation (ETFA), Zaragoza, Spain, pp. 1579-1582, 2019.	5		4.00
	BDI13	M. Lupascu, S. Hustiu, A. Burlacu, M. Kloetzer, Path planning for autonomous drones using 3D rectangular cuboid decomposition, 23rd International Conference on System Theory, Control, and Computing (ICSTCC), Sinaia, Romania, pp. 119-124, 2019.	4		5.00
<b>Total A2.2</b>					<b>92.33</b>

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Prof. dr. ing. Kloetzer Marius

