

DAFTAR PUSTAKA

- Auzan, M., Dharmawan, A., dan Candradewi, I. (2017). Sistem Kendali Robot *Humanoid* Ketika Berjalan Menggunakan Konsep Pendulum Terbalik. *IJEIS*, 10
- Babuska, R., dan Kober, J. (2018) “Knowledge-Based Control Systems,”.
- Baskoro, A. S., dan Priyono, M. G. (2016). Design of humanoid robot stable walking using inverse kinematics and zero moment point. *2016 International Electronics Symposium (IES)*, 335–339. <https://doi.org/10.1109/ELECSYM.2016.7861027>
- Grewal, M. S., dan Andrews, A. P. (2001). *Kalman Filtering: Theory and Practice Using MATLAB* (2nd ed.). John Wiley dan Sons.
- Ioannou, P., & Baldi, S. (2010). Robust adaptive control. In *The Control Systems Handbook: Control System Advanced Methods, Second Edition*. <https://doi.org/10.1201/b10384>
- Jazar, R. N. (2007). Theory of Applied. In Engineering.
- Joseph, L. (2018). Robot Operating System for Absolute Beginners. In *Robot Operating System for Absolute Beginners*. <https://doi.org/10.1007/978-1-4842-3405-1>
- Kajita, S., Hirukawa, H., Harada, K., & Yokoi, K. (2014). Springer Tracts in Advanced Robotics 101 Introduction to Humanoid Robotics.
- Kajita, S., Hirukawa, H., Harada, K., dan Yokoi, K. (2014a). Introduction to Humanoid Robotics. In *Springer Tracts in Advanced Robotics* (Vol. 101). <https://doi.org/10.1007/978-3-642-54536-8>
- Kajita, S., Hirukawa, H., Harada, K., dan Yokoi, K. (2014b). *Introduction to Humanoid Robotics* (Vol. 101). Springer Berlin Heidelberg. <https://doi.org/10.1007/978-3-642-54536-8>
- Kajita, S., Kanehiro, F., Kaneko, K., Yokoi, K., & Hirukawa, H. (2001). The 3D Linear inverted pendulum mode: A simple modeling for a biped walking pattern generation. *IEEE International Conference on Intelligent Robots and Systems*, 1, 239–240. <https://doi.org/10.1109/iros.2001.973365>
- Küçük, S., dan Bingöl, Z. (2004). The inverse kinematics solutions of industrial robot manipulators. *Proceedings of the IEEE International Conference on*

Mechatronics 2004, ICM'04, April 2016, 274–279.
<https://doi.org/10.1109/icmech.2004.1364451>

Lu, Y., Lu, Z., Yu, Y., Zhao, H., dan Zhang, Y. (2018). Development of Humanoid Robot and Biped Walking Based on Linear Inverted Pendulum Model. *2018 IEEE International Conference on Intelligence and Safety for Robotics (ISR)*, 244–249. <https://doi.org/10.1109/IISR.2018.8535689>

Mason, S., Rotella, N., Schaal, S., dan Righetti, L. (2016). Balancing and walking using full dynamics LQR control with contact constraints. *2016 IEEE-RAS 16th International Conference on Humanoid Robots (Humanoids)*, 63–68. <https://doi.org/10.1109/HUMANOIDS.2016.7803255>

Morisawa, M., Kajita, S., Harada, K., Fujiwara, K., Kanehiro, F., Kaneko, K., dan Hirukawa, H. (2005). Emergency stop algorithm for walking humanoid robots. *2005 IEEE/RSJ International Conference on Intelligent Robots and Systems*, 2109–2115. <https://doi.org/10.1109/IROS.2005.1544955>

Nava, G., Romano, F., Nori, F., dan Pucci, D. (2016). Stability analysis and design of momentum-based controllers for humanoid robots. *2016 IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*, 680–687. <https://doi.org/10.1109/IROS.2016.7759126>

Ogata, K. (2010). Modern control engineering. In *Modern Control Engineering* (5th ed.). Pearson Education. <https://doi.org/10.1201/9781315214573>

Rahadiyan, D. (2019). *Kendali Keseimbangan Berjalan Menurun Robot Humanoid di Bidang Miring Menggunakan LQR*. Universitas Gadjah Mada.

Sivanandam, S. N., Sumathi, S., dan Deepa, S. N. (2007a). *Introduction to Fuzzy Logic using MATLAB*. Springer Berlin Heidelberg. <https://doi.org/10.1007/978-3-540-35781-0>

Sivanandam, S. N., Sumathi, S., dan Deepa, S. N. (2007b). Introduction to fuzzy logic using MATLAB. In *Introduction to Fuzzy Logic using MATLAB*. <https://doi.org/10.1007/978-3-540-35781-0>

Starlino. (2009). *A Guide To using IMU (Accelerometer and Gyroscope Devices) in Embedded Applications* . IMU Theory and Experiments. [https://doi.org/Featured, IMU Theory and Experiments](https://doi.org/Featured,IMU%20Theory%20and%20Experiments)

Urbann, O., Schwarz, I., dan Hofmann, M. (2015). Flexible Linear Inverted Pendulum Model for cost-effective biped robots. *2015 IEEE-RAS 15th International Conference on Humanoid Robots (Humanoids)*, 128–131. <https://doi.org/10.1109/HUMANOIDS.2015.7363525>

- Wasielica, M., dan Wasik, M. (2014). Active stabilization of a humanoid robot base on inertial measurement unit data. *Proceedings of the 16th International Conference on Mechatronics - Mechatronika 2014*, 364–369. <https://doi.org/10.1109/MECHATRONIKA.2014.7018285>
- Welch, G., dan Bishop, G. (2006). An Introduction to the Kalman Filter. *UNC - Chapel Hill*, 1–16.
- Xie, K., Zhao, J., dan Mei, T. (2015). Task-based whole-body control of humanoid robots to a walking motion. *2015 IEEE International Conference on Mechatronics and Automation (ICMA)*, 1187–1192. <https://doi.org/10.1109/ICMA.2015.7237654>