



## DAFTAR PUSTAKA

- Ahmad, N. et al. (2013) 'Reviews on Various Inertial Measurement Unit (IMU) Sensor Applications', *International Journal of Signal Processing Systems*, 1(2), pp. 256–262. doi: 10.12720/ijsp.1.2.256-262.
- Akhtaruzzaman, M. and Shafie, A. A. (2011) 'Geometrical analysis on BIOLOID humanoid system standing on single leg', 2011 4th International Conference on Mechatronics: Integrated Engineering for Industrial and Societal Development, ICOM'11 - Conference Proceedings, (May), pp. 17–19. doi: 10.1109/ICOM.2011.5937193.
- Auzan, M. (2016). **SISTEM KENDALI ROBOT HUMANOID KETIKA BERJALAN MENGGUNAKAN KONSEP PENDULUM TERBALIK. UNIVERSITAS GADJAH MADA.**
- Dharmawan, A., Habiba, C. and Auzan, M. (2019) 'Walking stability control system on humanoid when turning based on LQR method', *International Journal of Scientific and Technology Research*, 8(11), pp. 2606–2611.
- Habiba, C. (2017). **SISTEM KENDALI ROBOT HUMANOID PADA SAAT BERJALAN BELOK. UNIVERSITAS GADJAH MADA.**
- Kagawa, T. and Uno, Y. (2009) 'Gait pattern generation for a power-assist device of paraplegic gait', *Proceedings - IEEE International Workshop on Robot and Human Interactive Communication*, pp. 633–638. doi: 10.1109/ROMAN.2009.5326348.
- Kajita, S. et al. (2014) *Springer Tracts in Advanced Robotics 101 Introduction to Humanoid Robotics*.
- Kajita, S., Hirukawa, H., Harada, K., & Yokoi, K. (2014). *Introduction to Humanoid Robotics*. Berlin Heidelberg: Springer.
- Kim, J. (2020) 'Multi-Axis Force-Torque Sensors for Measuring Zero-Moment Point in Humanoid Robots : A Review', 20(3), pp. 1126–1141.
- Kucuk, S. and Bingul, Z. (2006) *Industrial robotics: Theory, Modelling and Control - Robot Kinematics: Forward and Inverse Kinematics*.
- M, A., & A.A, S. (2011). "Geometrical analysis on BIOLOID humanoid system standing on single leg," 2011 4th Int. Conf. Mechatronics Integr. Eng. Ind. Soc. Dev. ICOM'11 - Conf. Proc., no. May, pp. 17-19.



- Mason, S., Righetti, L. and Schaal, S. (2015) 'Full dynamics LQR control of a humanoid robot: An experimental study on balancing and squatting', IEEE-RAS International Conference on Humanoid Robots, 2015-Febru, pp. 374–379. doi: 10.1109/HUMANOIDS.2014.7041387.
- Ogata, K. (2010). *Modern Control Engineering*. Pearson: doi:10.1109/TAC.1972.1100013.
- Patiung, F. L. (2013). Rancang Bangun Robot Beroda Dengan Pengendali Suara. *Jurnal Teknik Elektro dan Komputer*, 2(4), pp.48-52.
- Pemula, P. D. (2017) 'WALKING CONTROL SYSTEM OF HUMANOID ROBOT USING INVERTED PENDULUM', 110265, p. 110493.
- Riyanto et al. (2018) 'Center of Mass based Walking Pattern Generator with Gravity Compensation for Walking Control on Bioloid Humanoid Robot', 2018 15th International Conference on Control, Automation, Robotics and Vision, ICARCV 2018, pp. 54–59. doi: 10.1109/ICARCV.2018.8580633.
- Starlino. (2009, December). A Guide To using IMU (Accelerometer and Gyroscope Devices) in. Retrieved from Starlino Electronics: [http://www.starlino.com/imu\\_guide.html](http://www.starlino.com/imu_guide.html)
- Strom, J., Slavov, G., & Chown, E. (2009). Omnidirectional walking using zmp and preview control for the nao humanoid robot. In *Robot Soccer World Cup*. Berlin, Heidelberg: Springer.
- Strom, J., Slavov, G., & Chown, E. (2010). Omnidirectional walking using ZMP and preview control for the NAO humanoid robot. *Lecture Notes in Computer Science (Including Subseries Lecture Notes in Artificial Intelligence and Lecture Notes in Bioinformatic, J., Slavov, G. and Chown, E. (2010) 'Omnidirectional walking using ZMP and preview control for the NAO humanoid robot', Lecture Notes in Computer Science (including subseries Lecture Notes in Artificial Intelligence and Lecture Notes in Bioinformatics), 5949 LNAI, pp. 378–389. doi: 10.1007/978-3-642-11876-0\_33.*
- Tao, X., & Qijun, C. (2011). A Simple Rebalance Strategy for Omnidirectional Humanoids Walking by Learning Foot Positioning, *Control Conference (ASCC). 2011 8th Asian*, 1340-1345.
- Terrain, U. (2019) 'A Robust Balance-Control Framework for the Terrain-Blind Bipedal Walking of a Humanoid Robot'.



- Wang, H. et al. (2015) 'Research on the Relationship between Classic Denavit-Hartenberg and Modified Denavit-Hartenberg', Proceedings - 2014 7th International Symposium on Computational Intelligence and Design, ISCID 2014, 2, pp. 26–29. doi: 10.1109/ISCID.2014.56.
- Yang, T. et al. (2018) 'Turning gait planning method for humanoid robots', Applied Sciences (Switzerland), 8(8), pp. 1–16. doi: 10.3390/app8081257.
- Yanto, L. et al. (2017) 'Total kinematic on humanoid "FLoW" Teen-Size robot', Proceedings IES-ETA 2017 - International Electronics Symposium on Engineering Technology and Applications, 2017-Decem, pp. 106–111. doi: 10.1109/ELECSYM.2017.8240387.
- Yoshida, E. et al. (2006) 'Proceedings of the 2006 6th IEEE-RAS International Conference on Humanoid Robots : December 4-6, 2006, Genoa, Italy.', pp. 208–213.
- Yoshida, E., Kanoun, O., Esteves, C., & Laumond, J. (2006, Desember). Task-driven support polygon reshaping for humanoids. In 2006 6th IEEE-RAS International Conference on Humanoid Robots, pp. 208-213.
- Yoshikawa, T. (2022) 'Identification of Human Walking Balance Controller Based on COM-ZMP Model of Humanoid Robot', *Frontiers in Robotics and AI*, 9(February), pp. 1–21. doi: 10.3389/frobt.2022.757630