

DAFTAR PUSTAKA

- [1] R. Mahony, V. Kumar, and P. Corke, "Multirotor aerial vehicles: Modeling, estimation, and control of quadrotor," *IEEE Robot. Autom. Mag.*, vol. 19, no. 3, pp. 20–32, 2012.
- [2] B. M. K. dan G. (BMKG), "Data Online - Kecepatan Angin Harian," 2024.
- [3] R. Roy, M. Islam, N. Sadman, M. A. P. Mahmud, K. D. Gupta, and M. M. Ahsan, "A review on comparative remarks, performance evaluation and improvement strategies of quadrotor controllers," *Technologies*, vol. 9, no. 2, p. 37, 2021.
- [4] O. K. Soyinka, M. N. Ikpaya, and L. Luka, "Study on PID gain parameter optimization for a quadcopter under static wind turbulence using bio-inspired algorithms," *Discov. Electron.*, vol. 2, no. 1, pp. 1–19, 2025.
- [5] L. Ma, S. Pang, Y. He, Y. Wu, Y. Li, and W. Zhou, "Passivity-Based Sliding Mode Control for the Robust Trajectory Tracking of Unmanned Surface Vessels Under External Disturbances and Model Uncertainty," *J. Mar. Sci. Eng.*, vol. 13, no. 2, p. 364, 2025.
- [6] Z. Zhang, Y. Li, H. Jiang, J. Li, and Z. Wang, "A Novel Overactuated Quadrotor: Prototype Design, Modeling, and Control," in *Actuators*, 2025, vol. 14, no. 5, p. 223.
- [7] J. Kim, S. A. Gadsden, and S. A. Wilkerson, "A comprehensive survey of control strategies for autonomous quadrotors," *Can. J. Electr. Comput. Eng.*, vol. 43, no. 1, pp. 3–16, 2019.
- [8] A. Asignacion Jr and S. Satoshi, "Historical and current landscapes of autonomous quadrotor control: An early-career researchers' guide," *Drones*, vol. 8, no. 3, p. 72, 2024.
- [9] K. Ogata, "Modern control engineering," 2020.
- [10] K. Lee, S. Kim, S. Kwak, and K. You, "Quadrotor stabilization and tracking

- using nonlinear surface sliding mode control and observer,” *Appl. Sci.*, vol. 11, no. 4, p. 1417, 2021.
- [11] H. Ahn, M. Hu, Y. Chung, and K. You, “Sliding-mode control for flight stability of quadrotor drone using adaptive super-twisting reaching law,” *Drones*, vol. 7, no. 8, p. 522, 2023.
- [12] P. M. Tiwari, S. Janardhanan, and M. un Nabi, “Attitude control using higher order sliding mode,” *Aerosp. Sci. Technol.*, vol. 54, pp. 108–113, 2016.
- [13] T. Le Huu, H. Le Anh, and D. T. Tran, “Applying Sliding Mode Control to a Quadrotor,” *Eng. Technol. Appl. Sci. Res.*, vol. 14, no. 5, pp. 16389–16394, 2024.
- [14] A. Sawiński, P. Chudzik, and K. Tatar, “Cascade Sliding Mode Control for Linear Displacement Positioning of a Quadrotor,” *Sensors (Basel)*, vol. 25, no. 3, p. 883, 2025.
- [15] Y.-C. Um, S.-Y. Oh, and H.-L. Choi, “An event-triggered γ -sliding mode controller for hovering control of a quadrotor with uncertain time-varying mass and external disturbance,” *Int. J. Control. Autom. Syst.*, vol. 20, no. 10, pp. 3372–3382, 2022.
- [16] N. Xuan-Mung *et al.*, “Novel gain-tuning for sliding mode control of second-order mechanical systems: theory and experiments,” *Sci. Rep.*, vol. 13, no. 1, pp. 1–15, 2023, doi: 10.1038/s41598-023-37562-7.
- [17] S. Bouabdallah and R. Siegwart, “Full control of a quadrotor,” in *2007 IEEE/RSJ international conference on intelligent robots and systems*, 2007, pp. 153–158.
- [18] M. Kok, J. D. Hol, and T. B. Schön, “Using inertial sensors for position and orientation estimation,” *arXiv Prepr. arXiv1704.06053*, 2017.

- [19] R. Mahony, T. Hamel, and J.-M. Pflimlin, “Nonlinear complementary filters on the special orthogonal group,” *IEEE Trans. Automat. Contr.*, vol. 53, no. 5, pp. 1203–1218, 2008.