



DAFTAR PUSTAKA

- Abouzahir, M., Elouardi, A., Bouaziz, S., Latif, R., Tajer, A., 2014, FastSLAM 2.0 running on a low-cost embedded architecture, in: Control Automation Robotics & Vision (ICARCV), 2014 13th International Conference on. IEEE, pp. 1421–1426.
- Albrecht, S., 2009. An analysis of visual mono-slam. Diss. Master's Thesis. Universität Osnabrück 2009.
- Civera, J., Grasa, O.G., Davison, A.J. and Montiel, J.M.M., 2010, 1-Point RANSAC for extended Kalman filtering: Application to real-time structure from motion and visual odometry. *Journal of Field Robotics*, 27(5), pp.609-631.
- Davison, A.J., Reid, I.D., Molton, N.D., Stasse, O., 2007, MonoSLAM: Real-Time Single Camera SLAM. *IEEE Transactions on Pattern Analysis and Machine Intelligence* 29, 1052–1067. <https://doi.org/10.1109/TPAMI.2007.1049>
- Gemeiner, P., Davison, A. and Vincze, M., 2008, June. Improving Localization Robustness in Monocular SLAM Using a High-Speed Camera. In *Robotics: Science and Systems*.
- Giubilato, R., Pertile, M., Debei, S., 2016, A comparison of monocular and stereo visual FastSLAM implementations, in: *Metrology for Aerospace (MetroAeroSpace)*, 2016 IEEE. IEEE, pp. 227–232.
- Hwang, S.-Y., Song, J.-B., 2011. Monocular Vision-Based SLAM in Indoor Environment Using Corner, Lamp, and Door Features From Upward-Looking Camera. *IEEE Transactions on Industrial Electronics* 58, 4804–4812. <https://doi.org/10.1109/TIE.2011.2109333>
- Kang, W., Han, Y., 2015. SmartPDR: Smartphone-Based Pedestrian Dead Reckoning for Indoor Localization. *IEEE Sensors Journal* 15, 2906–2916. <https://doi.org/10.1109/JSEN.2014.2382568>
- Kim, T.-H., Park, T.-H., 2016, EKF-based simultaneous localization and mapping using laser corner-pattern matching, in: *Information and Automation (ICIA)*, 2016 IEEE International Conference on. IEEE, pp. 491–497.
- Kumiawan, D., Jati, A.N. and Sunarya, U., 2016, A study of 2D indoor localization and mapping using FastSLAM 2.0, in: *Control, Electronics, Renewable Energy and Communications (ICCEREC)*, 2016 International Conference. IEEE, pp. 152-156.



- Korkmaz, M., Yilmaz, N., Durdu, A., 2016, Comparison of the SLAM algorithms: Hangar experiments. MATEC Web of Conferences 42, 03009. <https://doi.org/10.1051/mateconf/20164203009>
- Liu, F., Lv, Q., Lin, H., Zhang, Y., Qi, K., 2016, An image registration algorithm based on FREAK-FAST for visual SLAM, in: Control Conference (CCC), 2016 35th Chinese. IEEE, pp. 6222–6226.
- Luknanto, B.K., Cahyadi, A.I., Wibirama, S. and Herianto, H., 2016, Real Time Monocular Visual Odometry using ORB Features for Indoor Environment. Journal of Instrumentation, Automation and Systems, 2(2), pp.52-58
- Mansur, S., Habib, M., Pratama, G.N.P., Cahyadi, A.I. and Ardiyanto, I., 2017, Real time monocular visual odometry using Optical Flow: Study on navigation of quadrotors UAV, in: Science and Technology-Computer (ICST), 2017 3rd International Conference. IEEE , pp. 122-126.
- Mur-Artal, R., Montiel, J.M.M., Tardos, J.D., 2015, ORB-SLAM: A Versatile and Accurate Monocular SLAM System. IEEE Transactions on Robotics 31, 1147–1163. <https://doi.org/10.1109/TRO.2015.2463671>
- Rublee, E., Rabaud, V., Konolige, K., Bradski, G., 2011. ORB: An efficient alternative to SIFT or SURF, in: Computer Vision (ICCV), 2011 IEEE international conference on. IEEE, pp. 2564-2571.
- Xu, X., Fan, H., 2016. Feature based simultaneous localization and semi-dense mapping with monocular camera, in: Image and Signal Processing, BioMedical Engineering and Informatics (CISP-BMEI), International Congress on. IEEE, pp. 17–22.
- Yap, M., Bonardi, A., Lersen, P., Howell, A., 2016, Monocular simultaneous localization and mapping, a guide to SLAM with only a single visual camera, <http://www.doc.ic.ac.uk/~ab9515/introductiontomonocular.html>, diakses pada tanggal 1 November 2017
- Ye, C., Zhao, Y., 2015, An EKF-SLAM method with filter consistency test for mobile robots using a 3D camera, in: Robotics and Biomimetics (ROBIO), 2015 IEEE International Conference on. IEEE, pp. 188–193.