

**PENINGKATAN AKURASI PENGUKURAN JARAK OBJEK
BERDASARKAN *GRID-EDGE-DEPTH MAP* DALAM PENENTUAN
KEPUTUSAN ARAH GERAK ROBOT BERODA**

***THE ACCURACY IMPROVEMENT OF OBJECT'S DISTANCE
MEASUREMENT BASED ON GRID-EDGE-DEPTH MAP
IN THE DETERMINATION OF WHEELED ROBOT'S
DECISION OF DIRECTION***



**BUDI RAHMANI
14/372103/SPA/492**

**PROGRAM STUDI S3 ILMU KOMPUTER
DEPARTEMEN ILMU KOMPUTER DAN ELEKTRONIKA
FAKULTAS MATEMATIKA DAN ILMU PENGETAHUAN ALAM
UNIVERSITAS GADJAH MADA
YOGYAKARTA
2019**