

## REFERENSI

- [1] “DARPA Robotics Challenge (DRC).” [Online]. Available: <https://www.darpa.mil/program/darpa-robotics-challenge>. [Accessed: 01-Mar-2020].
- [2] A. Robotics, “Robots — Agility Robotics.” [Online]. Available: <https://www.agilityrobotics.com/robots#digit>. [Accessed: 01-Mar-2020].
- [3] R. Gerndt, D. Seifert, J. H. Baltes, S. Sadeghnejad, and S. Behnke, “Humanoid Robots in Soccer: Robots Versus Humans in RoboCup 2050,” *IEEE Robot. Autom. Mag.*, vol. 22, no. 3, pp. 147–154, 2015.
- [4] S. Böttcher, “Principles of robot locomotion.”
- [5] IEEE, “Atlas (2013) - ROBOTS: Your Guide to the World of Robotics,” 2019. [Online]. Available: <https://robots.ieee.org/robots/atlas/>. [Accessed: 18-Sep-2019].
- [6] K. Townsend, “Adafruit BNO055 absolute orientation sensor,” *Adafruit Learn. Syst.*, pp. 1–39, 2019.
- [7] Bosch Sensortec, “BNO055 Intelligent 9-axis absolute orientation sensor, [https://cdn-shop.adafruit.com/datasheets/BST\\_BNO055\\_DS000\\_12.pdf](https://cdn-shop.adafruit.com/datasheets/BST_BNO055_DS000_12.pdf),” no. November, p. 105, 2014.
- [8] S. Kajita, H. Hirukawa, K. Harada, and K. Yokoi, “Introduction to Humanoid Robotics,” in *Springer Tracts in Advanced Robotics*, vol. 101, 2014, pp. 69–79.
- [9] E. M. Cimpoeșu, B. D. q Ciubotaru, and D. Ștefănoiu, “Fault detection and identification using parameter estimation techniques,” *UPB Sci. Bull. Ser. C Electr. Eng. Comput. Sci.*, vol. 76, no. 2, pp. 3–14, 2014.
- [10] Azeddine Kinsheel, “Robust least square estimation of the CRS A465 robot arm’s dynamic model parameters,” *J. Mech. Eng. Res.*, vol. 4, no. 3, 2012.
- [11] A. Sakai, “GitHub - AtsushiSakai/rosbag\_to\_csv: Converter from ros bag to csv.” [Online]. Available: [https://github.com/AtsushiSakai/rosbag\\_to\\_csv](https://github.com/AtsushiSakai/rosbag_to_csv). [Accessed: 25-Mar-2020].
- [12] M. Verhaegen and V. Verdult, *Filtering and system identification: A least squares approach*, vol. 9780521875. 2007.
- [13] R. Babuška and J. Kober, “Knowledge-Based Control Systems,” 2018.
- [14] J. Pratt, J. Carff, S. Drakunov, and A. Goswami, “Capture point: A step toward humanoid push recovery,” *Proc. 2006 6th IEEE-RAS Int. Conf. Humanoid Robot. HUMANOIDS*, pp. 200–207, 2006.
- [15] X. Xinjilefu, “State Estimation for Humanoid Robots,” Carnegie Mellon University, 2015.