

DAFTAR PUSTAKA

- [1] J. Li, "Dynamic Analysis and PID Control for a Quadrotor," pp. 573–578, 2011.
- [2] D. H. Shim, H. J. Kim, and S. Sastry, "Control System Design for Rotorcraft-based Unmanned Aerial Vehicles using Time-domain System Identification," *Proc. 2000 IEEE Int. Conf. Control Appl.*, no. 2, pp. 808–813, 2000.
- [3] S. Scherer, S. Singh, L. Chamberlain, and M. Elgersma, "Flying Fast and Low Among Obstacles: Methodology and Experiments," *Int. J. Rob. Res.*, vol. 27, no. 5, pp. 549–574, May 2008.
- [4] A. Coates, P. Abbeel, and A. Y. Ng, "Learning for control from multiple demonstrations," *Proc. 25th Int. Conf. Mach. Learn. - ICML '08*, pp. 144–151, 2008.
- [5] G. Pang and H. Liu, "Evaluation of a low-cost MEMS accelerometer for distance measurement," *J. Intell. Robot. Syst. Theory Appl.*, vol. 30, no. 3, pp. 249–265, 2001.
- [6] S. A. Quadri and O. Sidek, "Error and Noise Analysis in an IMU using Kalman Filter," *Int. J. Hybrid Inf. Technol.*, vol. 7, no. 3, pp. 39–48, 2014.
- [7] S. Colton, *The Balance Filter A Simple Solution for Integrating Accelerometer and Gyroscope Measurements for a Balancing Platform*. 2007.
- [8] D. Yue, X. Huang, and H. Tan, "INS/VNS Fusion Based on Unscented Particle Filter," *Int. Conf. Wavelet Anal. Pattern Recognit.*, pp. 151–156, 2007.
- [9] X. Ren and G. Xue, "Position Estimation for Manipulators Based on Multisensor Fusion," *31st Chinese Control Conf.*, pp. 5082–5087, 2012.
- [10] Y. Chen, S. Chang, and R. Yu, "Robust Estimation Design of MEMS-Based Integration Inertial Navigation Systems Chiung-Yau Huang," *IECON 2006 - 32nd Annu. Conf. IEEE Ind. Electron.*, pp. 3117–3122, 2006.
- [11] W. Lv and Y. Kang, "Fuzzy-Logic Based Adaptive Weighting Filter for Strap-Down Inertial Navigation Systems *," *IEEE 11th World Congr. Intell. Control Autom.*, pp. 2053–2059, 2014.

- [12] Q. Lin and H. P. E. Stem, "Analysis of a Correlation Filter for Thermal Noise Reduction in a MEMS Gyroscope," 2002.
- [13] H. Ferdinando, H. Khoswanto, and U. K. Petra, "Embedded Kalman Filter For Inertial Measurement Unit (IMU) on the Atmega8535," pp. 1–5, 2012.
- [14] N. A. Razak, N. Hashim, M. Arshad, R. Adnan, M. F. Misnan, N. M. Thamrin, S. F. Mahmud, and S. Alam, "A Study of Kalman ' s Filter in Embedded Controller for Real-Time Quadcopter Roll and Pitch Measurement," *IEEE Int. Conf. Control Syst. Comput. Eng.*, pp. 590–595, 2012.
- [15] M. Achtelik, A. Bachrach, R. He, S. Prentice, and N. Roy, "Autonomous Navigation and Exploration of a Quadrotor Helicopter in GPS-denied Indoor Environments," *Int. Aer. Robot. Compet.*, 2009.
- [16] A. Bachrach, S. Prentice, and N. Roy, "RANGE - Robust Autonomous Navigation in GPS-denied Environments," *J. F. Robot.*, 2009.
- [17] C. Christmann, A. Wu, H. Hashimoto, C. Ong, R. Kalghatgi, and E. N. Johnson, "Self-Contained Ranging Sensor Aided Autonomous Guidance , Navigation , and Control for Indoor Flight," *Am. Inst. Aeronaut. Astronaut.*, pp. 1–21.
- [18] A. Bry, A. Bachrach, and N. Roy, "State estimation for aggressive flight in GPS-denied environments using onboard sensing," *2012 IEEE Int. Conf. Robot. Autom.*, no. Icara 2012, pp. 1–8, May 2012.
- [19] D. Li, Q. Li, N. Cheng, Q. Wu, J. Song, and L. Tang, "Combined RGBD-inertial based state estimation for MAV in GPS-denied indoor environments," *2013 9th Asian Control Conf.*, pp. 1–8, Jun. 2013.
- [20] M. Achtelik, A. Bachrach, R. He, S. Prentice, and N. Roy, "Stereo vision and laser odometry for autonomous helicopters in GPS-denied indoor environments," *Int. Soc. Opt. Eng.*, pp. 733219–733219–10, May 2009.
- [21] L. R. García Carrillo, A. E. Dzul López, R. Lozano, and C. Pégard, "Combining Stereo Vision and Inertial Navigation System for a Quad-Rotor UAV," *J. Intell. Robot. Syst.*, vol. 65, no. 1–4, pp. 373–387, Aug. 2011.

- [22] R. Voigt, J. Nikolic, C. Hurzeler, S. Weiss, L. Kneip, and R. Siegwart, "Robust embedded egomotion estimation," *2011 IEEE/RSJ Int. Conf. Intell. Robot. Syst.*, pp. 2694–2699, Sep. 2011.
- [23] F. Uavs, R. Beard, D. Kingston, M. Quigley, D. Snyder, R. Christiansen, W. Johnson, T. Mclain, and M. A. Goodrich, "Autonomous Vehicle Technologies for Small Fixed-Wing UAVs," *J. Aerosp. Comput. INFORMATION, Commun.*, vol. 2, no. January, pp. 92–108, 2005.
- [24] W. E. Green and P. Y. Oh, "Autonomous Hovering of a Fixed-Wing Micro Air Vehicle," *IProceedings 2006 IEEE Int. Conf. Robot. Autom.*, no. May, pp. 2164–2169, 2006.
- [25] Z. H. Ondřej, Š. Spinka, Š. Stěpán, and K. Kroupa, "Control System for Unmanned Aerial Vehicles," *5th IEEE Int. Conf. Ind. Informatics*, 2007.
- [26] S. Salazar-cruz, "Real-Time Stabilization of a Small Three-Rotor Aircraft," *IEEE Trans. Aerosp. Electron. Syst.*, vol. 44, no. April, pp. 783–794, 2008.
- [27] D.-W. Yoo, H.-D. Oh, D.-Y. Won, and M.-J. Tahk, "Dynamic modeling and control system design for Tri-Rotor UAV," *2010 3rd Int. Symp. Syst. Control Aeronaut. Astronaut.*, pp. 762–767, Jun. 2010.
- [28] P. Corke, *Robotics, Vision and Control*, vol. 73. Berlin: Springer, 2011.
- [29] R. M. Murray, Z. Li, and S. S. Sastry, *A Mathematical Introduction to Robotic Manipulation*. Berkeley: University of California, 1994.
- [30] J. Dixon and O. Henlich, "Mobile Robot Navigation," *Surprise_97*, vol. 4, 1997.
- [31] P. Goel, S. I. Roumeliotis, and G. S. Sukhatme, "Robot Localization Using Relative and Absolute Position Estimates," *IEEE/RSJ Int. Conf. on Intelligent Robot. Syst.*, 1999.
- [32] J. J. Engel, "Autonomous Camera-Based Navigation of a Quadrotor," DER TECHNISCHE UNIVERSITÄT MÜNCHEN, 2011.
- [33] S. Thrun, "Probabilistic Algorithms in Robotics," *Science (80-.)*, vol. 4, no. April, pp. 93–109, 2000.



- [34] G. Welch and G. Bishop, “An Introduction to the Kalman Filter,” Chapel Hill: University of North Carolina, 2006, pp. 1–16.
- [35] C. Chiu, “Error Reduction Techniques for a MEMS Accelerometer-based Digital Input Device,” The Chinese University of Hong Kong, 2008.
- [36] S. W. Smith, *The Scientist and Engineer’s Guide to Digital Signal Processing*. San Diego: California Technical Publishing, 1997.