

## DAFTAR PUSTAKA

- Arun, S. V. K., Subramaniam, U., Padmanaban, S., Bhaskar, M. S., & Almakhlles, D. (2019). Investigation for performances comparison PI, adaptive PI, fuzzy speed control induction motor for centrifugal pumping application. *Proceedings - 2019 IEEE 13th International Conference on Compatibility, Power Electronics and Power Engineering, CPE-POWERENG 2019*. <https://doi.org/10.1109/CPE.2019.8862351>
- Åström, K. J., & Hägglund, T. (1995). *PID controllers: theory, design, and tuning* (Vol. 2).
- Ayas, M. S., & Sahin, E. (2014). Trajectory Tracking Control of a Stewart Platform. *16th International Power Electronics and Motion Control Conference and Exposition, PEMC 2014*, 720–724. <https://doi.org/10.1109/EPEPEMC.2014.6980582>
- Bang, H., & Lee, Y. S. (2018). Implementation of a Ball and Plate Control System Using Sliding Mode Control. *IEEE Access*, 6, 32401–32408. <https://doi.org/10.1109/ACCESS.2018.2838544>
- Cai, Y., Zheng, S., Liu, W., Qu, Z., & Han, J. (2020). Model Analysis and Modified Control Method of Ship-mounted Stewart Platforms for Wave Compensation. *IEEE Access*, 9. <https://doi.org/10.1109/ACCESS.2020.3047063>
- Cavallaro, F. (2015). A Takagi-Sugeno Fuzzy Inference System for Developing a Sustainability Index of Biomass. *Sustainability (Switzerland)*, 7(9), 12359–12371. <https://doi.org/10.3390/su70912359>
- Charters, T., & Enguiça, R. (2009). Detecting Singularities of Stewart Platforms. *Industry Case Studies Journal*, 1, 66–80. <https://cdn.instructables.com/ORIG/FFK/LAIV/I55MRG6M/FFKLAIIV55MRG6M.pdf>
- Chen, Z., & Liyan, Z. (2013). Kinematics Analysis and Workspace Investigation of a Novel 2-DOF Parallel Manipulator Applied in Vehicle Driving Simulator. *Robotics and Computer-Integrated Manufacturing*, 29(4), 113–120. <https://doi.org/10.1016/j.rcim.2012.11.005>
- Cholakian, R. C. (1979). Narrative structure in rabelais and the question of the authenticity of the cinquieme livre. *French Studies*, 33(1), 1–12. <https://doi.org/10.1093/fs/XXXIII.1.1>
- Dongsu, W., & Hongbin, G. (2007). Adaptive Sliding Control of Six-DOF Flight Simulator Motion Platform. *Chinese Journal of Aeronautics*, 20(5), 425–433. [https://doi.org/10.1016/S1000-9361\(07\)60064-8](https://doi.org/10.1016/S1000-9361(07)60064-8)
- Du, T., Wang, K., & Li, Y. (2020). A tracking system based on 2-DOF motion platform for flight simulator. *Chinese Control Conference, CCC, 2020-July*, 2723–2728. <https://doi.org/10.23919/CCC50068.2020.9189479>
- Escobar, L. A. M., Almeida, M. A. G., Camacho, O. E., Acosta, J. A. R., & Espin, D. F. P. (2018). A Comparative Analysis Among Different Controllers Applied to The Experimental Ball and Plate System. *Proceedings - 2017 International Conference on Information Systems and Computer Science, INCISCOS 2017, 2017-Novem*, 108–114. <https://doi.org/10.1109/INCISCOS.2017.27>
- Gui, P., Tang, L., & Mukhopadhyay, S. (2015). MEMS based IMU for tilting measurement: Comparison of complementary and kalman filter based data fusion. *Proceedings of the*



- 2015 10th IEEE Conference on Industrial Electronics and Applications, ICIEA 2015, 2004–2009. <https://doi.org/10.1109/ICIEA.2015.7334442>
- Ighs, L. E. D. L. (2014). D C -D C B Uck -B Oost and Sepic C Onverters To D Rive. *2018 International Conference on Advancement in Electrical and Electronic Engineering (ICAEED)*, 7(4), 1283–1293.
- Kassem, A., & Haddad. (2015). Commparation Between Different Methods of Control of Ball and Plate System with 6DOF Stewart Platform. *IFAC-PapersOnLine*, 48(11), 47–52. <https://doi.org/10.1016/j.ifacol.2015.09.158>
- Kurniawan, A. (2019). *Arduino Mega 2560 A Hands-On Guide for Beginner*. PE Press. <https://books.google.co.id/books?id=peSgDwAAQBAJ>
- Merlet, J.-P. (2006). *Parallel Robots* (Second edi). Springer Science & Business Media.
- NXP Semiconductors. (2015). PCA9685 16-channel, 12-bit PWM Fm+ I2C-bus LED controller. *NXP Semiconductors N.V, April, 52*. <https://cdn-shop.adafruit.com/datasheets/PCA9685.pdf>
- Ogata, K. (1970). *Modern Control Engineering K Ogata 5Th Edition* (Vol. 4, Issue 3). <http://ieeexplore.ieee.org/document/1100013/%0Ahttp://www.academia.edu/download/32572194/82.pdf>
- Owoc, D., & Ludwiczak, K. (2019). Mechatronics Design, Modelling and Controlling of The Stewart-Gough Platform. *2019 24th International Conference on Methods and Models in Automation and Robotics, MMAR 2019, 76–80*. <https://doi.org/10.1109/MMAR.2019.8864694>
- Rabah, M., Rohan, A., Mohamed, S. A. S., & Kim, S. H. (2019). Autonomous Moving Target-Tracking for a UAV Quadcopter Based on Fuzzy-PI. *IEEE Access*, 7, 38407–38419. <https://doi.org/10.1109/ACCESS.2019.2906345>
- Rusli, M. (2017). *Dasar Perancangan Kendali Logika Fuzzy* (1st ed.). UB Media.
- Shen, J., Xin, B., Cui, H., & Gao, W. (2017). Control of Single-Axis Rotation INS by Tracking Differentiator Based Fuzzy PID. *IEEE Transactions on Aerospace and Electronic Systems*, 53(6), 2976–2986. <https://doi.org/10.1109/TAES.2017.2722558>
- Shukla, A., & Karki, H. (2014). Modeling Simulation & Control of 6-DOF Parallel Manipulator using PID Controller and Compensator. In *IFAC Proceedings Volumes (IFAC-PapersOnline)* (Vol. 3, Issue PART 1). IFAC. <https://doi.org/10.3182/20140313-3-IN-3024.00015>
- Siahaan, J. P. C., Sumardi, & Setiyono, B. (2016). *Self-Balancing Scooter Menggunakan Metode Kendali Pid Dengan Tuning Fuzzy*.
- Stewart, D. (1965). A Platform with Six Degrees of Freedom. *Proceedings of the Institution of Mechanical Engineers*, 180(1), 371–386. [https://doi.org/10.1243/PIME\\_PROC\\_1965\\_180\\_029\\_02](https://doi.org/10.1243/PIME_PROC_1965_180_029_02)
- Sun, L., Ma, J., & Yang, B. (2020). Fuzzy PID Design of Vehicle Attitude Control Systems. *Proceedings of the 32nd Chinese Control and Decision Conference, CCDC 2020, 2*, 1826–1830. <https://doi.org/10.1109/CCDC49329.2020.9164275>
- Suratno. (2002). *Pengaruh Perbedaan Tipe Fungsi Keanggotaan Pada Pengendali Logika*



*Fuzzy Terhadap Tanggapan Waktu Sistem Orde Dua Secara Umum.* 1–10.

- Szufnarowski, F. (2013). Stewart platform with Fixed Rotary Actuators : a Low Cost Design Study. *Faculty of Technology, Bielefeld University, Germany*, 1–11.
- Tarokh, M. (2007). Real time forward kinematics solutions for general Stewart platforms. *Proceedings - IEEE International Conference on Robotics and Automation, April*, 901–906. <https://doi.org/10.1109/ROBOT.2007.363100>
- Wei, Y., & Wang, A. (2019). Ocean Wave Active Compensation Analysis of Inverse Kinematics for Hybrid Boarding System Based on Fuzzy Algorithm. *Ocean Engineering*, 182(March), 577–583. <https://doi.org/10.1016/j.oceaneng.2019.03.059>
- Wokingham U3A Math Group. (n.d.). The Mathematics of the Stewart Platform. *Wokingham U3A Math Group*.
- Yaovaja, K. (2018). Ball Balancing on a Stewart Platform using Fuzzy Supervisory PID Visual Servo Control. *ICAICTA 2018 - 5th International Conference on Advanced Informatics: Concepts Theory and Applications*, 170–175. <https://doi.org/10.1109/ICAICTA.2018.8541349>
- Yi, Q., Zhuang, H., Lu, C., Gao, H., & Wang, W. (2020). Optimal Control Algorithm of Working Speed of Deicing Robot Based on Fuzzy PID. *Proceedings of 2020 IEEE 4th Information Technology, Networking, Electronic and Automation Control Conference, ITNEC 2020, Itmec*, 2118–2122. <https://doi.org/10.1109/ITNEC48623.2020.9084816>
- Zhang, H., & Liu, D. (2007). *Fuzzy Modeling and Fuzzy Control Control Engineering* (Berilustra). Springer Science & Business Media.
- Zulkarnaen, F. (2020). *RANCANG BANGUN GIMBAL STABILIZER DENGAN MODUL SENSOR MPU-6050 MENGGUNAKAN RANCANG BANGUN GIMBAL STABILIZER DENGAN MODUL SENSOR MPU-6050 MENGGUNAKAN COMPLEMENTARY FILTER.*