

DAFTAR PUSTAKA
www.itk.ac.id

- Alaimo, A., Artale, V., Milazzo, C. L., & Ricciardello, A. (2013). PID Controller Applied to *Hexacopter*. *Journal of Intelligent & Robotic Systems*.
- Al-Dunainawi, Y., Abbod, M. F., & Jizany, A. (2017). A new MIMO ANFIS-PSO based NARMA-L2 controller for *nonlinear* dynamic systems. *Engineering Applications of Artificial Intelligence*, 265–275.
- Ang, K. H., Chong, G., & Li, Y. (2005). PID Control System Analysis, Design, and Technology. *IEEE TRANSACTIONS ON CONTROL SYSTEMS TECHNOLOGY*, 559-576.
- Artale, V., Milazzo, C., & Ricciardello, A. (2013). Mathematical Modeling of *Hexacopter*. *Applied Mathematical Sciences*, 4805 - 4811.
- Baldeon, J., Garcia, G. D., & Camacho, O. (2016). Control for *Hexacopters*: A Sliding Mode Control and PID Comparison. *Revista Técnica de la Facultad de Ingeniería Universidad del Zulia*, 137-144.
- Bresciani, T. (2008). *Modelling, Identification and Control of a Quadrotor Helicopter*. Lund, Swedia: Lund University Department of Automatic Control.
- Chai, T., & Draxler, R. R. (2014). Root mean square *error* (RMSE) or mean absolute *error* (MAE)? – Arguments *against* avoiding RMSE in the literature. *Geosci. Model Dev.*, 7, 1247–1250.
- Encina, A. d., L´opez, N., & Rubio, F. (2019). Exporting *Rain-Fall* Optimization concepts to Artificial Bee Colony. *IEEE International Conference on Systems, Man and Cybernetics (SMC)*, 2047-2052.
- Farid, G., Hamid, H. T., Karim, S., & Tahir, S. (2018). Waypoint-Based Generation of Guided and Optimal Trajectories for Autonomous Tracking Using a Quadrotor UAV. *Studies in Informatics and Control*, 225-236.
- Han, H.-G., Zhang, L., Hou, Y., & Qiao, J.-F. (2016). *Nonlinear* Model Predictive Control Based on a Self-Organizing Recurrent Neural Network. *IEEE TRANSACTIONS ON NEURAL NETWORKS AND LEARNING SYSTEMS*, 402 - 415.

- Indrawati, V., Prayitno, A., & Kusuma, A. (2015). Waypoint Navigation of AR.Drone Quadrotor Using Fuzzy Logic Controller. *TELKOMNIKA, Vol.13, No.3*, 930-939.
- Jeng, J.-C. (2015). A Model-Free Direct Synthesis Method for PIPID Controller Design Based on Disturbance Rejection. *Chemometrics and Intelligent Laboratory Systems*.
- Jung, C. S., Song, H. K., & Hyun, J. C. (1999). A direct synthesis tuning method of unstable firstorder-plus-time-delay processes. *Journal of Process Control* 9, 265-269.
- Kaboli, S. H., Selvaraj, J., & Rahim, N. (2016). Rain-fall optimization algorithm: a population based algorithm for solving constrained optimization problems. *Journal of Computational Science*.
- Koohi, I., & Groza, V. Z. (2014). Optimizing Particle Swarm Optimization Algorithm. *CCECE 2014 1569887533*, 1-5.
- Ligthart, J. A., Poksawat, P., Wang, L., & Nijmeijer, H. (2017). Experimentally Validated Model Predictive Controller for a *Hexacopter*. *International Federation of Automatic Control*, 4076–4081.
- Panagopoulos, A. A., & Chalkiadakis, G. (2015). Moment of Inertia of Potentially Tilted Cuboids. *A Draft Proof of Equation 10 at AAAI-15 paper*.
- Paz, R. (2001). The Design of the PID Controller. *Klipsch School of Electrical and Computer Engineering*.
- Pi, C.-H., Hu, K.-C., Cheng, S., & Wu, I.-C. (2019). Low-level autonomous control and tracking of quadrotor using reinforcement learning. *Control Engineering Practice* 95 (2020) 104222, 1-11.
- Robandi, I. (2019). *ARTIFICIAL INTELLIGENCE-Mengupas Rekayasa Kecerdasan Tiruan*. Yogyakarta: Penerbit ANDI.
- Rojas, R. (2019). Moment of inertia through scaling and the parallel axis theorem. *Revista Brasileira de Ensino de Física, vol. 41, no 1, e20180146*.
- Sabatino, F. (2015). *Quadrotor control: modeling, nonlinear control design, and simulation*. Stockholm: KTH Electrical Engineering.
- Suprpto, B. Y., Mustaqim, A., Wahab, W., & Kusumoputro, B. (2017). Modified Elman Recurrent Neural Network for Attitude and Altitude Control of

Heavy-lift *Hexacopter*. *Intl. Symp. Elec. and Com. Eng*, 309 - 314.

Walker, J., Halliday, D., & Resnick, R. (2014). *Fundamentals of physics*.

Hoboken: John Wiley & Sons, Inc.

Zanetti, R., & DeMars, K. J. (2018). Fully Multiplicative Unscented Kalman Filter for Attitude Estimation. *Journal of Guidance Control and Dynamics*.



www.itk.ac.id