

DAFTAR PUSTAKA

- [1] M. Elbanhawi dan M. Simic, "Sampling-based robot motion planning: A review," *IEEE Access*, vol. 2, no. February, hal. 56–77, 2014.
- [2] S. Karaman, M. R. Walter, A. Perez, E. Frazzoli, dan S. Teller, "Anytime motion planning using the RRT," *Proc. - IEEE Int. Conf. Robot. Autom.*, hal. 1478–1483, 2011.
- [3] B. Paden, M. Čáp, S. Z. Yong, D. Yershov, dan E. Frazzoli, "A survey of motion planning and control techniques for self-driving urban vehicles," *IEEE Trans. Intell. Veh.*, vol. 1, no. 1, hal. 33–55, 2016.
- [4] D. González, J. Pérez, V. Milanés, dan F. Nashashibi, "A Review of Motion Planning Techniques for Automated Vehicles," *IEEE Trans. Intell. Transp. Syst.*, vol. 17, no. 4, hal. 1135–1145, 2016.
- [5] Liu, Ying, dan Norman I. Badler. "Real-time reach planning for animated characters using hardware acceleration." In *Proceedings 11th IEEE international workshop on program comprehension*, hal. 86-93. IEEE, 2003.
- [6] S. Zhang, J. Pu, dan Y. Si, "An Adaptive Improved Ant Colony System Based on Population Information Entropy for Path Planning of Mobile Robot," *IEEE Access*, vol. 9, hal. 24933–24945, 2021.
- [7] LaValle, S.M. Rapidly-exploring random trees: A new tool for path planning. *Comput. Sci. Dept.* Oct. 1998.
- [8] LaValle, S.M. dan Kuffner, J.J., Jr. Rapidly-exploring random trees: Progress and prospects. *Algorithmic and Computational Robotics: New Directions*, hal.293-308, 2000.
- [9] J. Nasir, F. Islam, dan Y. Ayaz, "Adaptive Rapidly-Exploring-Random-Tree-Star (RRT*) -Smart: Algorithm Characteristics and Behavior Analysis in Complex Environments," *Asia-Pacific J. Inf. Technol. Multimed.*, vol. 02, no. 02, hal. 39–51, 2013.
- [10] S. Karaman, dan E. Frazzoli. "Incremental sampling-based algorithms for optimal motion planning." *Robotics Science and Systems VI* 104, no. 2 (2010).
- [11] L. G. D. O. Véras, F. L. L. Medeiros, dan L. N. F. Guimarães, "Rapidly exploring Random Tree* with a sampling method based on Sukharev grids and convex vertices of safety hulls of obstacles," *Int. J. Adv. Robot. Syst.*, vol. 16, no. 1, hal. 1–19, 2019.
- [12] J. Dong, M. Mukadam, F. Dellaert, dan B. Boots, "Motion planning as probabilistic inference using Gaussian processes and factor graphs," *Robot. Sci. Syst.*, vol. 12, 2016.
- [13] J. Wang, X. Li, dan M. Q. H. Meng, "An improved RRT algorithm incorporating obstacle Boundary information," 2016 IEEE Int. Conf. Robot. Biomimetics, ROBIO 2016, hal. 625–630, 2016.
- [14] O. Hachour, "Path planning of Autonomous Mobile robot," vol. 2, no. 4, hal. 178–190, 2008.
- [15] S. Khanmohammadi dan A. Mahdizadeh, "Density avoided sampling: An intelligent sampling technique for rapidly-exploring random trees," *Proc. - 8th Int. Conf. Hybrid Intell. Syst. HIS 2008*, hal. 672–677, 2008.
- [16] E. S. Nugraha, "Simulator Edukatif untuk Pembelajaran Algoritma Rapidly-exploring Random Tree (RRT)," *Telekontran J. Ilm. Telekomun. Kendali dan Elektron. Terap.*, vol. 7, no. 2, 2020.
- [17] F. Islam, J. Nasir, U. Malik, Y. Ayaz, dan O. Hasan, "RRT*-Smart: Rapid convergence implementation of RRT* towards optimal solution," *2012 IEEE Int. Conf. Mechatronics Autom. ICMA 2012*, hal. 1651–1656, 2012.
- [18] Kang, Gitae, Yong Bum Kim, Won Suk You, Young Hun Lee, Hyun Seok Oh, Hyungpil Moon, dan Hyouk Ryeol Choi. "Sampling-based path planning with goal

- oriented sampling." In *2016 IEEE International Conference on Advanced Intelligent Mechatronics (AIM)*, hal. 1285-1290. IEEE, 2016.
- [19] R. Geraerts dan M. Overmars, "Sampling techniques for probabilistic roadmap planners," *Proc. Int. Conf. Intell. Auton. Syst.*, hal. 600–609, 2004.
- [20] Amato, Nancy M., dan Yan Wu. "A randomized roadmap method for path and manipulation planning." In *Proceedings of IEEE international conference on robotics and automation*, vol. 1, hal. 113-120. IEEE, 1996.
- [21] Noreen, Iram, Amna Khan, dan Zulfiqar Habib. "A comparison of RRT, RRT* and RRT*-smart path planning algorithms." *International Journal of Computer Science and Network Security (IJCSNS) 16*. Hal.10-20 (2016).