

DAFTAR PUSTAKA

- [1] A. Gasparetto, P. Boscariol, A. Lanzutti, dan R. Vidoni, “*Path planning* and Trajectory Planning Algorithms: A General Overview,” dalam *Motion and Operation Planning of Robotic Systems*, vol. 29, G. Carbone dan F. Gomez-Bravo, Ed. Cham: Springer International Publishing, 2015, hlm. 3–27.
- [2] J. D. Gammell, S. S. Srinivasa, dan T. D. Barfoot, “*Informed-RRT**: Optimal *sampling*-based *path planning* focused via direct *sampling* of an admissible ellipsoidal heuristic,” dalam *2014 IEEE/RSJ International Conference on Intelligent Robots and Systems*, Chicago, IL, Sep 2014, hlm. 2997–3004.
- [3] N. D. Rumlaklak, “Studi Performansi Algoritma Perencanaan Jalur diantara PRM, RRT, RRT* dan *Informed-RRT*,” *Jurnal Ilmiah Telekomunikasi, Kendali dan Elektronika Terapan*, vol. 7, no. 2, 2020
- [4] E. W. Dijkstra, E. W. “A note on two problems in connexion with graphs,” *Numerische mathematik*, vol. 1, no. 1, pp. 269-271, 1959
- [5] P. E. Hart, N. J. Nilsson, dan B. Raphael, “A formal basis for the heuristic determination of minimum *cost paths*,” *IEEE transactions on Systems Science and Cybernetics*, vol. 4, no. 2, pp. 100-107, 1968
- [6] A. Stentz, “Optimal and efficient *path planning* for unknown and dynamic environments,” Carnegie-Mellom Univ Pittsburgh PA Robotics Inst, 1993
- [7] M. Likhachev, D. Ferguson, G. Gordon, A. Stentz, dan S. Thrun, “Anytime search in dynamic graphs,” *Artificial Intelligence*, vol. 172, no. 14, pp. 1613-1643, 2008
- [8] S. Karaman, M. R. Walter, A. Perez, E. Frazzoli, dan S. Teller, “Anytime motion planning using the RRT,” *2011 IEEE International Conference on Robotics and Automation*, pp. 1478-1483, 2011
- [9] L. E. Kavraki, P. Svestka, J. C. Latombe, and M. H. Overmars, M. H. “Probabilistic roadmaps for *path planning* in high-dimensional configuration spaces,” *IEEE transactions on Robotics and Automation*, vol. 12, no. 4, pp. 566-580, 1996
- [10] S. M. LaValle, “*Rapidly-exploring Random Trees: A new tool for path planning*,” Tech. Rep., Computer Science Dept., Iowa State University, pp. 1-4, 1998

- [11] S. Karaman, dan E. Frazzoli, “*Sampling*-based algorithms for optimal motion planning,” *The international journal of robotics research*, vol. 30, no 7, pp. 846-894, 2011
- [12] N. M. Amato dan Y. Wu, “A randomized roadmap method for *path* and manipulation planning,” dalam *Proceedings of IEEE International Conference on Robotics and Automation*, Minneapolis, MN, USA, vol. 1, hlm. 113–120, 1996
- [13] M. Elbanhawi, dan M. Simic, “*Sampling*-based robot motion planning: A review,” *IEEE Access*, vol. 2, pp. 56-77, 2014
- [14] S. Karaman, dan E. Frazzoli, “Optimal kinodynamic motion planning using incremental *sampling*-based methods,” 49th IEEE conference on decision and control (CDC), pp. 7681-7687, 2010