

DAFTAR PUSTAKA

- [1] Siegwart, Roland noubakhsh, Illah R.2004. Introduction to Autonomous Mobile Robots. London: Massachusetts.
- [2] Buehler, Martin.1998. SCOUT: a simple quadruped that walks, climbs,and runs. Belgium : Walt Disney Imagineering.
- [3] Meng, Ni Xiaodong, Wang. 2011.Kinematics Analysis and Simulation of Quadruped Robot. Beijing : School of Automation Science and Electrical Engineering, Beihang University.
- [4] *PANDILOV, Zoran DUKOVSKI, Vladimir.* Comparison Of The Characteristics Between Serial And Parallel Robots. Macedonia : *Sv. Kiriil I Metodij university.*
- [5] Endang.2013."WR note Electrical Engineering". [Online]. Available: <https://wangready.wordpress.com>. [Accessed 2016].
- [6] Morimoto, Jun Endo, Gen Nakanishi, Jun Chen, gordon.2008. Modulation of Sinusoidal Patterns by a Coupled Oscillator Model. Japan Sci. & Technol. Agency.
- [7] Gómez, Javier Muñoz-Martínez, Pablo, R-Moreno, María D Romeral Julio J. López, Sara Navarro.2009.An Autonomous system for the locomotion of a Hexapod Exploration Robot.Madrid : Departamento de Automática, Universidad de Alcalá.
- [8] Tarokh, Mahmoud and Lee, Malrey. 2009. Systematic Method for Kinematics Modeling of Legged Robots on Uneven Terrain. San Diego :Department of Computer Science, San Diego State University.
- [9] Wang, Lianqing Yu Yujin dan Tao, Weijun.2010. Gait Analysis and Implementation of a Simple Quadruped Robot.China : Wuhan University of Science and Engineering and Nanjing University of Science and Technology.
- [10] Yamazaki, Kenneth S.1999. The Design and Control of Scout I A Simple Quadruped Robot. Montreal :Department of Mechanical Engineering McGill University.
- [11] Ijspeert, jan, auke.2008. Central pattern generators for locomotion control in animals and robots:A review.Switzerland : School of Computer and Sciences.