DAFTAR PUSTAKA

[1] Tashrif, T. (2018). *Peneliti: Energi fosil akan habis 2050*. [online] Antara News. Available at: https://www.antaranews.com/berita/545481/peneliti-energi-fosil-akan-habis-2050 [Accessed 12 Oct. 2018].

[2] Handayani, R. (2018). *Gaikindo: Tantangan Mobil Listrik di Indonesia Masih Besar | Republika Online*. [online] Republika Online. Available at: https://republika.co.id/berita/otomotif/mobil/18/05/23/p96o7o284-gaikindo-tantangan-mobil-listrik-di-indonesia-masih-besar [Accessed 12 Oct. 2018].

[3] Hafil, M. (2015). *Sulitnya Self Service di SPBU | Republika Online*. [online] Republika Online. Available at: https://www.republika.co.id/berita/koran/urbana/15/05/18/nojfoq29-sulitnya-self-service-di-spbu [Accessed 12 Oct. 2019].

[4] Botsford, C and Szczepanek, A. (2009). Fast Charging vs. Slow Charging: Pros and cons for the New Age of Electric Vehicles [Accessed 12 Oct. 2019].

[5] Petrou, M. and Petrou, C. (n.d.). *Image processing*. 5th ed. UK: John Wiley & Sons.

[6] Gonzalez, R. and Woods, R. (n.d.). *Digital image processing*. 3rd ed. New Jersey: Prentice Hall.

[7] Firoozian, R. (2009). *Servo motors and industrial control theory*. New York: Springer.

[8] Wicaksono, F. (2018). *Perancangan Dan Implementasi Alat Penyortir Barang Pada Konveyor Dengan Pengolahan Citra*. Bandung: Telkom University.

[9] Febrian, W. (2018). *Sistem Pengolahan Citra Pendeteksi Jalur Pada Mobil Listrik Otonom*. Bandung: Telkom University.

[10] Efander, A. (2017). *Sistem Interaksi Robot Menggunakan Citra Deteksi Wajah Manusia Secara Realtime*. Bandung: Telkom University.

[11] Wahyu. (2014). *Perancangan Dan Implementasi Kontrol Posisi Lengan Robot Untuk Pemngambilan Objek Menggunakan Kamera Dan Metode Inverse Kinematics*. Bandung: Telkom University.

[12] Kucuk, S. and Bingul, Z. (2006). *Industrial Robotics Theory Modelling Control*. London: IntechOpen.

[13] Jazar, R. (2010). *Theory of applied robotics*. New York: Springer.

[14] Hessmer, R. (2009). Kinematics for Lynxmotion Robot Arm. *Kinematics for Lynxmotion Robot Arm*, 6.