

## Bukti Korespondensi

Penulis : **P. Paryanto\***, Rakha Rahmadani Pratama, Roni Permana Saputra  
(**Corresponding & 1<sup>st</sup> author**)  
Jurnal : *2023 International Conference on Radar, Antenna, Microwave, Electronics, and Telecommunications (ICRAMET)* – IEEE Conference  
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No	Jenis Korespondensi / Kegiatan	Tanggal	Lampiran bukti
1	Manuscript Submission to Conference	04 Oktober 2023	Lampiran 1
2	Decision on the manuscript: accepted with revisions	24 Oktober 2023	Lampiran 2
3	IEEE copyright transfer agreement	05 November 2023	Lampiran 3
4	Paper online on IEEE Explore	25 December 2023	Lampiran 4

Semarang, 06.03.2025

### Lampiran 1: Manuscript Submission to the IEEE conference – 04 Oktober 2023

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**From:** Conference Iccramet (icramet@brin.go.id)  
**Sent:** 04 October 2023 11:23  
**To:** P Paryanto; Rakha Rahmadani Pratama; Roni Permana Saputra  
**Subject:** [ICRAMET 2023] #1570960888 has been uploaded

Dear Mr. P Paryanto:

Thank you for uploading your full paper manuscript for paper 1570960888 (*Wheel Odometry-based Localization for Autonomous Personal Mobility Vehicles*) to **2023 International Conference on Radar, Antenna, Microwave, Electronics, and Telecommunications (ICRAMET)**. The paper is of type application/pdf and has a length of 3985083 bytes.

You can modify your paper at [1570960888](https://edas.info/index.php?c=30762) and see all your submissions at <https://edas.info/index.php?c=30762> using the EDAS identifier [paryanto@ft.undip.ac.id](mailto:paryanto@ft.undip.ac.id)

Regards,  
Technical Program Committee of ICRAMET 2023  
Research Center for Electronics  
National Research and Innovation Agency (BRIN)

## Lampiran 2: Decision on the manuscript: Accepted with revisions – 24 Oktober 2023

We are pleased to inform you that your paper: #1570960888 entitled 'Wheel Odometry-based Localization for Autonomous Personal Mobility Vehicles' **has been accepted** for ICRAMET 2023. Some revisions as mentioned in the review results below are required for the final manuscript to be presented in the ICRAMET 2023.

Please read the instructions below carefully in regard to final manuscript submission:

### 1. **Preparation of your final manuscript:**

- The paper should follow the standard IEEE conference templates with A4 or US letter formats that can be found at:  
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- Papers should be written in English with a maximum paper length of six (6) printed pages including figures without incurring any page charges. Two additional pages are permitted with an overlength page charge of USD100 for each excess page.
- When preparing the final manuscript, authors should address critical comments/feedback from reviewers. Please fill-up the form [that can be downloaded here](#) to explain your revisions and respond to the reviewers and TPC comments. Email a ZIP file/archive containing the editable format of the final manuscript (LaTeX (Tex) files or MS Word document) and review response form to [icramet@brin.go.id](mailto:icramet@brin.go.id).
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- Please note that presenters are required to complete the registration fee no later than **November 7<sup>th</sup>, 2023**:

IEEE Member/BRIN Researcher Speaker (already including publication cost): IDR 1,850,000 / US\$ 150;

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Participant (Non-speaker, certificate will be provided): IDR 100,000/US\$ 8;

## Lampiran 3: IEEE copyright transfer agreement – 05 November 2023

### IEEE Copyright Transfer Confirmation for Article: Wheel Odometry-based Localization for Autonomous Wheelchair



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Author(s): Dr. P Paryanto, Mr. Rakha Rahmadani Pratama and Dr. Roni Permana Saputra

Author E-mail: [paryanto@ft.undip.ac.id](mailto:paryanto@ft.undip.ac.id), [rakhardp@students.undip.ac.id](mailto:rakhardp@students.undip.ac.id), [roni.permana.saputra@brin.go.id](mailto:roni.permana.saputra@brin.go.id)

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**Lampiran 4: Paper online on IEEE Explore – 25 December 2023**

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# Wheel Odometry-Based Localization for Autonomous Wheelchair

**Publisher:** IEEE [Cite This](#) [PDF](#)

P Paryanto ; Rakha Rahmadani Pratama ; Roni Permana Saputra **All Authors**

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**Abstract**
Document Sections

- I. Introduction
- II. Method
- III. System Design and Implementations
- IV. Experiment & Results
- V. Conclusion

**Abstract:**

Localization is a fundamental requirement for an autonomous vehicle system. One of the most often used systems for autonomous vehicle localization is the global positioning system (GPS). Nevertheless, the functionality of GPS is strongly dependent on the availability of satellites, making it unreliable in some situations. As a result, autonomous vehicles must possess autonomous self-localization capabilities to ensure their independent operation. Odometry techniques are employed to achieve vehicle localization by predicting the vehicle position and orientation based on sensor measurements of the vehicle motion. One of the approaches employed in odometry is known as wheel odometry. Wheel odometry has a lower degree of reliance on the surrounding environment than visual odometry and laser odometry. This study aims to evaluate the performance of wheel odometry implementation for an autonomous wheelchair in the context of the localization process. The differential drive kinematic model is employed to determine the predicted pose of a wheelchair. This prediction is derived from the measurement of the linear and angular velocity of the wheelchair. Several experiments have been conducted to evaluate the performance of wheel odometry-based

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