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# Introduction

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# Literature Review

## **Dependent Variable**

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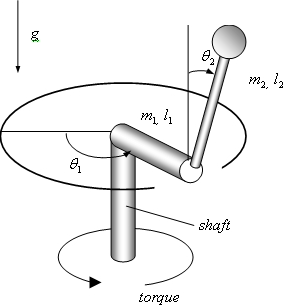
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**Fig. 1** *Simplified rotary inverted pendulum schematic [22]*

# Methodology

## Figures and Tables

Figures and tables are to be embedded in the main text body. They should not have cosmetic enhancement such as a shadow frame. One blank line separates the figure or table with the following text

The numerical values of the mechanical and electrical system parameters for the RIP system are provided in Table 1. Table 2 tabulates the numerical nomenclature of the RIP system.

**Table 1** *RIP system variables and parameters*

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| HEADING | UPPER | TIMES NEW ROMAN | 12 | BOLD | CENTER |
| SUBHEADING | UPPER | TIMES NEW ROMAN | 12 | NORMAL | CENTRE |
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A diagram of a mechanical arm

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**Fig. 1** *Simplified rotary inverted pendulum schematic [22]*

# Results and Discussion

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# Conclusion

From the observation, it can be concluded that LQR exhibits a faster stabilization speed than FSF. However, LQR shows an unappealing pendulum angle overshoot post-stability, where the pendulum angle peaked at 0.0799 radian, which is higher than the FSF (0.0264 radian).

# Acknowledgement

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# Conflict of Interest

Authors declare that there is no conflict of interests regarding the publication of the paper.

# Author Contribution

*The authors confirm contribution to the paper as follows:* ***Formulation of Dynamical model of RIP:*** *Muhammd Nizam Kamarudin;* ***Literature survey and review:*** *Rozilawati Mohd Nor;* ***Formulation of FSF with Simulation analysis:*** *Sahazati Md Rozali;* ***Formulation of LQR with Simulation analysis:*** *Muhammad Nizam Kamarudin;* ***draft manuscript preparation:*** *Muhammad Nizam Kamarudin, Mohd Saifuzam Jamri. All authors reviewed the results and approved the final version of the manuscript.*

# Ethic Statement

*The authors confirm contribution to the paper as follows:* ***Formulation of Dynamical model of RIP:*** *Muhammd Nizam Kamarudin;* ***Literature survey and review:*** *Rozilawati Mohd Nor;* ***Formulation of FSF with Simulation analysis:*** *Sahazati Md Rozali;* ***Formulation of LQR with Simulation analysis:*** *Muhammad Nizam Kamarudin;* ***draft manuscript preparation:*** *Muhammad Nizam Kamarudin, Mohd Saifuzam Jamri. All authors reviewed the results and approved the final version of the manuscript.*

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