Modélisation mathématique:

University of New Mexico - Control Theory of The Double Pendulum Inverted on a Cart/ https://drive.google.com/file/d/1VxT84KJXg89n7mJowL-xiMBDLQW6Sbc3/view?usp=sharing

Modélisation du système sur MATLAB:

Implementation of MATLAB Code for LQR/LQG for linearized and non-linearized system: https://github.com/nakul3112/Double-inverted-pendulum.git

Modélisation et simulation LabVIEW (Simulation #1):

Quanser Linear Double Inverted Pendulum: https://www.quanser.com/products/linear-double-inverted-pendulum/

Quanser - Linear Servo Control Systems Brochure: https://drive.google.com/file/d/1FyeQGBpf4AzLHVXN6yYvqwZmRYK\_1f8l/view?usp=sharing

Quanser - Linear Double Inverted Pendulum - Laboratory Guide: https://drive.google.com/file/d/1QVa5jelx7D5Yzznd775VXKbIiXpe-aos/view?usp=sharing

Apprentissage par renforcement (Simulation #4):

Inverted Double pendulum: https://github.com/Julien-Gustin/Inverted-Double-pendulum

Université de Liège - Julien Gustin, Joachim Houyon - Searching High-Qaulity Policies to Control an Unstable Physical System: https://drive.google.com/file/d/1ZZP9JLJm16gNSK-q3P0HJkgEw7KP5H6O/view?usp=sharing

Google Deepmind. "Continuous control with deep reinforcement learning". : https://arxiv.org/pdf/1509.02971.pdf (pages 2, 4, 8).