

# 1<sup>st</sup> APTECS 2009

NATIONAL SEMINAR ON APPLIED TECHNOLOGY, SCIENCE, AND ARTS



## THE PROCEEDING

Surabaya, Dec. 22, 2009



LEMBAGA PENELITIAN DAN  
PENGABDIAN KEPADA  
MASYARAKAT

FIND-11

IPTEK

The Journal for Technology and Science



PROCEEDING

**NATIONAL SEMINAR  
ON “APPLIED TECHNOLOGY, SCIENCE AND ARTS”  
1<sup>st</sup> APTECS 2009**

THEME

**KEUNGGULAN PENGELOLAAN SUMBER-  
SUMBER ENERGI DALAM MENGHADAPI  
KRISIS SOSIAL-EKONOMI GLOBAL**

**Graha Sepuluh Nopember, 22 Desember 2009**

**Organized by:**

**LEMBAGA PENGABDIAN PADA MASYARAKAT (LPPM)  
INSTITUT TEKNOLOGI SEPULUH NOPEMBER  
2009**

# **PROCEEDING OF NATIONAL SEMINAR ON APPLIED TECHNOLOGY, SCIENCE, AND ARTS 1<sup>st</sup> APTECS 2009**

**Edited by APTECS TEAM**

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# NATIONAL SEMINAR ON APPLIED TECHNOLOGY, SCIENCE, AND ARTS 2009

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# SAMBUTAN REKTOR ITS

Assalamu'alaikum Wr. Wb. Salam sejahtera bagi kita semua, semoga Allah SWT selalu melimpahkan rahmat dan karuniaNya kepada kita sekalian. Saya mengucapkan selamat datang untuk peserta *National Seminar on Applied Technology, Science and Arts (APTECS)* yang telah datang dari dalam maupun luar negeri. Seminar ini merupakan forum komunikasi ilmiah dalam rangka *sharing* ilmu pengetahuan, teknologi dan seni.

Sebagai komponen bangsa, Institut Teknologi Sepuluh Nopember (ITS) ikut menyelesaikan permasalahan bangsa yang menyangkut krisis sosial dan ekonomi melalui pengelolaan sumber-sumber energi yang tepat dan terarah yang merupakan topik APTECS kali ini. Topik APTECS yang pertama ini bersesuaian (*selaras*) dengan 3 (tiga) unggulan penelitian di ITS yaitu, Energi, Permukiman, dan Kelautan.

Energi merupakan salah satu daya dukung penguatan sektor ekonomi dan pembangunan Indonesia. Krisis di sektor riil dan investasi global berimplikasi signifikan pada daya dukung tersebut, dan berdampak pada penurunan kemampuan pemenuhan kebutuhan dasar masyarakat (sandang, papan, dan pangan). Oleh karena itu melalui APTECS yang pertama ini ITS menggagas tentang kesinergian yang berkesinambungan di bidang teknologi, sosial dan ekonomi dalam upaya menghadapi krisis tersebut secara regional maupun global, sehingga pemecahan dan tanggung jawabnya tidak terpisah hanya di satu negara saja, namun menjadi tanggungjawab semua negara. Bentuk sumbangsih ini akan dipresentasikan dalam bentuk diskusi ilmiah yang merangkai berbagai disiplin ilmu di seminar ini.

Dalam kesempatan ini ITS berterima-kasih kesemua pihak (LPPM-ITS, Panitia APTECS, peserta seminar dan semua pihak yang mendukung acara ini). Akhir kata, kami mengucapkan selamat berseminar semoga sukses dan sampai jumpa tahun depan pada 2nd APTECS 2010.

Surabaya, 22 Desember 2009  
Rektor ITS

**PROF. PRIYO SUPROBO**

# SAMBUTAN KETUA LPPM ITS

Puji syukur patut kita panjatkan kehadapan Tuhan Yang Maha Esa, yang dengan karunia dan rahmatNya APTECS dapat berjalan dengan baik. Dua ratus enam puluh paper ilmiah terpilih akan dipresentasikan, dan lebih dari 400 peneliti, industriawan, dan akademisi dari dalam negeri dan luar negeri akan hadir untuk menyampaikan ide dan kontribusinya terhadap perkembangan Ilmu Pengetahuan, Teknologi, dan Seni untuk kemaslahatan umat manusia. Prestasi ini patut disyukuri dan dengan usaha yang keras penyelenggara, dan ada kebangkitan kesadaran dari para peneliti selaku *Core Creative Community* untuk terus berpartisipasi atmosfir akademika ini.

Seminar ini diselenggarakan oleh LPPM-ITS dalam rangka Dies Natalis ITS yang ke 49 dan menunjang program FIND-11, dan juga dalam rangka membangun jaring dan komunikasi antar peneliti, pelaku industri, dan akademisi di tingkat nasional maupun internasional. Karena salah satu bidang unggulan yang dikembangkan ITS adalah bidang *Energi, pemukiman, dan kelautan*, maka seminar yang pertama ini mengambil tema *Keunggulan Pengelolaan Sumber-sumber Energi dalam Menghadapi Krisis Sosial-Ekonomi Global*.

Sumber daya alam dan sumber daya manusia yang banyak sudah tidak dapat dijadikan modal utama dalam menghadapi persaingan global, tetapi yang sekarang lebih dibutuhkan adalah modal *Ilmu Pengetahuan, Teknologi dan Kreativitas*. Tanpa memiliki tiga modal tersebut maka akan terjadi paradok-paradok yang negatif pada kehidupan yaitu: negara yang berlimpah sumber daya alam, tetapi rakyatnya miskin dan negara dengan banyak sumber daya manusia tetapi menghasilkan nilai tambah yang sangat kecil pada perekonomian dunia. Dalam rangka menguatkan modal Ilmu Pengetahuan, Teknologi dan membangun masyarakat yang kreatif maka LPPM-ITS menyelenggarakan APTECS ini yang akan dikembangkan setiap tahun, dan akan menjadi seminar Internasional di tahun yang akan datang, sehingga dapat menghimpun peneliti-peneliti dunia yang berkualitas dalam mencari pemecahan berbagai persoalan kehidupan umat manusia.

Dalam kesempatan yang berbahagia ini, LPPM-ITS selaku penyelenggara menyampaikan rasa banyak terimakasih dan menyampaikan rasa salut dan berbangga kepada para peneliti yang berpartisipasi. Terimakasih yang sangat dalam juga kami sampaikan kepada pimpinan ITS yang telah mendukung sepenuhnya seminar ini. LPPM-ITS juga merasa patut untuk memberi penghargaan yang tinggi kepada panitia pelaksana yang telah bekerja keras dan cerdas dalam menyiapkan APTECS ini.

LPPM-ITS mengucapkan selamat berpartisipasi dalam seminar, dan teruslah berkarya dan meneliti semoga Tuhan selalu melimpahkan karunia-Nya, sehingga kontribusi yang diberikan oleh para peneliti dapat bermakna untuk kemakmuran, kesejahteraan, dan kemaslahatan umat manusia.

Surabaya, 22 Desember 2009  
Ketua LPPM-ITS

**PROF. I NYOMAN SUTANTRA**

# Welcome to APTECS 2009

Assalamu'alaykum warohmatullaahi wabarokatuh

Selamat datang kepada para peserta 1<sup>st</sup> APTECS, dan semoga Saudara dalam satu hari ini dapat menikmati suasana harmonis di seminar ini dan dapat menikmati keindahan kampus ITS.

Seminar yang dilaksanakan dalam rangka memperingati Dies Natalis ITS ke 49 dan kerjasama FIND-11, sebagai perwujudan dari ajang komunitas para peneliti dan pengkaji bidang Iptek, sosial dan seni yang mengambil tema tahun 2009 "*Keunggulan Pengelolaan Sumber-sumber Energi dalam Menghadapi Krisis Sosial Ekonomi Global*". Di samping tema utama tersebut, beberapa hal yang berhubungan bidang aplikasi teknologi, aplikasi pada sistem pendidikan, aplikasi ICT pada sistem pendidikan, energi dibarukan, efisiensi energi, dan restrukturisasi energi, elektrik, elektronik, bioteknologi, komunikasi dan game technology, transportasi, kebumihan dan kebencanaan, manufaktur, material dan proses industri, dan kelautan (biologi laut, bangunan laut dan kepebisiran). Untuk bidang science terdiri dari ilmu sosial dan humaniora, rekayasa sosial, nano science, medical, medicine, pemodelan, komputasi, dan kecerdasan tiruan, nuclear science, seni dan industri kreatif, pendidikan secara umum, pertanian dan kehutanan. Dalam seminar ini akan dilakukan diskusi secara sinergi antara peneliti, praktisi, dan juga dapat diambil sebagai pijakan dalam pengambilan keputusan oleh para pejabat pengambil keputusan, dan juga akan dipresentasikan hasil karya seni anak bangsa sebagai usaha untuk mengangkat karya seni domestik sebagai karya international.

Pada kesempatan ini kami menyampaikan rasa terima kasih kepada Rektor ITS yang memberi semangat dan fasilitas dalam penyelenggaraan APTECS ini, Kepada Ketua LPPM ITS dan keluarga besar LPPM ITS yang sangat mensupport dan mengawal acara ini hingga sukses, dan Kepada seluruh civitas akademika ITS. Kepada para sponsorship yang ikut berpartisipasi dalam menyukseskan acara ini kami menyampaikan rasa terima kasih, semoga kerjasama ini dapat terjalin dengan lebih hangat lagi di waktu yang akan datang. Kepada rekan-rekan panitia, Dr. Aulia, Dr Bambang Sampurno, Dr. Heru Mirmanto, Dr. Tavio, Mr. Hendra Cordova, Ms Kamilia, Mr Tamaji, Ms Listiani, Ms Efritra, Ms Febriana, Ms Liza, Ms Erni, Ms Syiska, Mr Phonny Aditiawan, dan yang lain yang tidak dapat saya sebut satu-persatu yang telah bekerja dengan semangat luar biasa dengan penuh keceriaan dan loyalitas. Kepada para profesor yang berada di technical program committee, Prof Gamantyo, Prof. Noor Endah, Prof. Ali Altway, Prof Perry Burhan, Prof. Suprpto, Prof Triwulan, Prof Djatmiko, Prof Djauhar M., Prof Endang, Prof Eko Budi, dan Prof IN Pujawan, kami menghaturkan rasa terima kasih yang sangat tinggi dengan kesediaan mereka untuk meluangkan waktu untuk APTECS. Terima kasih kepada Tim Gamelan dari Elektro Budoyo Group pimpinan Pak Joko Susila (Jurusan Teknik Elektro ITS), Tim Tari Ngremo Kolosal pimpinan Pak Solihin Fanani (dari SDM 4 Pucang Surabaya), dan Tari Kiprah Glipang pimpinan Pak Boediono dari PDM Probolinggo yang telah menyumbangkan karya kreativitasnya, semoga dapat menjadi titik tonggak awal kebangkitan kreativitas karya seni Indonesia yang selalu digemari oleh putra-putri Indonesia.

Our special thanksfull to Professor HIYAMA Takashi from Kumamoto Univ., Japan, as Keynote Speaker in this event, and welcome to Surabaya.

Mohon maaf dengan segala kekurangan, dan sampai jumpa di International APTECS, 21 Desember 2010 yang akan datang.

Assalamu'alaykum warohmatullaahi wabarokatuh

General Chair of 1<sup>st</sup> APTECS 2009

**PROF. IMAM ROBANDI**

# **UCAPAN TERIMA KASIH KEPADA**

**REKTOR ITS**

**LPPM ITS**

**REDAKSI MAJALAH IPTEK ITS**

**KUMAMOTO UNIVERSITY, JAPAN**

**UNIVERSITAS MUHAMMADIYAH SURABAYA**

**INSTITUT TEKNOLOGI ADHI TAMA SURABAYA**

**SMP MUHAMMADIYAH 5 SURABAYA**

**SD MUHAMMADIYAH 4 SURABAYA**

**SD MUHAMMADIYAH 26 SURABAYA**

**PT. TIRA AUSTENITE, TBK**

**RAJANT CORPORATION**

**LABORATORIUM UJI MATERIAL-D3 T. SIPIL ITS**



**SCHEDULE**  
**NATIONAL SEMINAR ON APPLIED TECHNOLOGY, SCIENCE, AND ARTS**  
**1<sup>st</sup> APTECS 2009**

<b>6.40 – 7.40 Registrasi</b>										
<b>7.40-8.19 Banjaran Srepeg oleh <i>Elektro Budoyo</i></b>										
<b>08.19 – 08.26 MC</b>										
<b>08.26 – 08.33 Ngremo Kolosal oleh <i>SD Muhammadiyah 4 Surabaya &amp; Elektro Budoyo</i></b>										
<b>08.33 – 08.43 Welcome to APTECS oleh <i>Prof. IMAM ROBANDI</i></b>										
<b>08.43 – 08.50 Musik dan Tari Kiprah Glipang oleh <i>Lembaga Seni dan Budaya PDM Probolinggo</i></b>										
<b>08.50 – 09.00 Sambutan oleh <i>Prof. I NYOMAN SUTANTRA (Ka LPPM ITS)</i></b>										
<b>09.00 – 09.08 Gending Ladrang APTECS oleh <i>Elektro Budoyo</i></b>										
<b>09.08 – 09.28 Opening Term oleh <i>Prof. PRIYO SUPROBO (Rektor ITS)</i></b>										
<b>09.28 – 09.34 Ladrang Parisuko oleh <i>Elektro Budoyo</i></b>										
<b>09.34 – 09.40 Launching Buku oleh <i>Prof. ARIF DJUNAIDY (Pembantu Rektor I ITS)</i></b>										
<b>09.40 – 10.50 Keynote Speech oleh <i>Prof. HIYAMA TAKASHI (Kumamoto University, Japan)</i></b>										
	A	B	C	D	E	F	G	H	I	J
11.00-11.12	ENG-92	ENG-248	ENG-88	MED-13	ENG-219	ENG-245	MED-19	ENG-90	ENG-139	ENG-223
11.12-11.24	ENG-225	SOC-7	ENG-22	ENG-108	ENG-75	ENG-109	SOC-14	ENG-198	ENG-18	ENG-224
11.24-11.36	ENG-134	ENG-40	ENG-144	ENG-85	ENG-77	ENG-129	ENG-233	ENG-199	AGR-4	ENG-201
11.36-11.48	ENG-241	SOC-8	ENG-54	ENG-7	ENG-89	ENG-149	ENG-231	ENG-200	ENG-24	ENG-230
11.48-12.00	ENG-74	ENG-73	ENG-138	ENG-32	ENG-257	ENG-96	AGR-6	ENG-181	ENG-45	ENG-91
12.00-13.00	Break for Lunch									
13.00-13.12	ENG-168	ENG-235	ENG-169	SOC-17	MED-9	ENG-98	ENG-161	ENG-147	ENG-57	ENG-27
13.12-13.24	ENG-171	ENG-172	ENG-124	MED-18	ENG-97	ENG-185	ENG-125	ENG-13	ENG-46	ENG-227
13.24-13.36	ENG-113	ENG-173	ENG-2	ENG-38	ENG-135	ENG-5	MED-20	MED-12	ENG-33	ENG-213
13.36-13.48	ENG-8	ENG-48	ENG-4	ENG-105	ENG-162	ENG-10	ENG-99	ENG-60	ENG-141	ENG-202
13.48-14.00	ENG-86	ENG-21	ENG-115	MED-6	MED-10	ENG-12	ENG-103	ENG-17	ENG-36	ENG-140
14.00-14.12	ENG-87	ENG-132	ENG-55	MED-4	MED-2	ENG-102	ENG-9	ENG-53	ENG-83	MED-17
14.12-14.24	EDU-6	ENG-50	ENG-31	MED-1	ENG-14	ENG-214	ENG-69	MED-8	ENG-68	ENG-165
14.24-14.36	ENG-210	ENG-62	ENG-35	EDU-7	ENG-133	ENG-15	ENG-218	ENG-142	AGR-7	ENG-94
14.36-14.48	ENG-209	SOC-9	ENG-29	ENG-206	ENG-104	ENG-19	MED-5	ENG-64	ENG-112	ENG-146
14.48-15.00	ENG-76	SOC-6	ENG-28	ENG-184	ENG-39	ENG-23	ENG-95	ENG-84	ENG-63	ENG-258
15.00-15.12	ENG-58	ENG-67	ENG-151	SOC-4	ENG-81	ENG-25	ENG-93	ENG-195	ENG-72	ENG-49
15.12-15.24	ENG-79	ENG-6	AGR-8	ENG-56	ENG-42	ENG-187	ENG-59	ENG-107	EDU-4	ENG-80
15.24-15.36	ENG-131	ENG-26	ENG-116	ENG-232	SOC-18	ENG-158	ENG-215	ENG-130	ENG-182	ENG-186
15.36-15.48	ENG-166	ENG-237	SOC-13	ENG-65	ENG-121	ENG-127	ENG-216	ENG-175	ENG-110	ENG-174
15.48-16.00	ENG-128	ENG-164	SOC-12	ENG-34	ENG-156	EDU-1	ENG-137	ENG-119	ENG-37	EDU-2
16.00-16.12	ENG-159	ENG-160	ENG-20	ENG-51	ENG-61	ENG-243	ENG-16	MED-3	ENG-3	ENG-111
16.12-16.24	SOC-10	SOC-5	MED-16	ENG-1	ENG-179	ENG-244	ENG-212	ENG-52	ENG-178	ENG-191
16.24-16.36	ENG-249	ENG-44	ENG-30	ENG-247	MED-21	ENG-192	EDU-5	ENG-177	ENG-193	ENG-228
16.36-16.48	MED-11	ENG-157	ENG-152	ENG-153	ENG-255	ENG-196	ENG-154	SOC-3	EDU-3	ENG-123
16.48-17.00	ENG-71	ENG-194	ENG-203	Eng-208	ENG-253	ENG-211	ENG-220	ENG-197	MED-7	ENG-221
17.00-17.12	ENG-260	ENG-242	ENG-238	ENG-240	ENG-259	SOC-15	SOC-16	ENG-250	SOC-19	ENG-251
17.12-17.24			ENG-254	ENG-252		ENG-183	ENG-246	ENG-256		

- NOTE**
- |                              |                               |
|------------------------------|-------------------------------|
| A : Ruang Argopuro 1 (Lt. 1) | F : Ruang Semeru 2 (Lt. 1)    |
| B : Ruang Argopuro 2 (Lt. 1) | G : Ruang Anjasmoro 1 (Lt. 2) |
| C : Ruang Kawi (Lt. 1)       | H : Ruang Anjasmoro 2 (Lt. 2) |
| D : Ruang Lawu (Lt. 1)       | I : Ruang Anjasmoro 3 (Lt. 2) |
| E : Ruang Semeru 1 (Lt. 1)   | J : Ruang Kelud (Lt. 2)       |

**- 11.32 is time for Dzuhur prayer, 14.58 is time for Ashar prayer.**

**Moderator Sesion 1 (10.00 – 12.00)**

A	Ruang Argopuro 1 (Lt.1)	Prof. Agus Rubiyanto
B	Ruang Argopuro 2 (Lt. 1)	Prof. Djauhar Manfaat
C	Ruang Kawi (Lt. 1)	Prof. Basuki Widodo
D	Ruang Lawu (Lt. 1)	Prof. Djatmiko Ichsani
E	Ruang Semeru 1 (Lt. 1)	Prof. Suprpto
F	Ruang Semeru 2 (Lt. 1)	Prof. Sutardi
G	Ruang Anjasmoro 1 (Lt. 2)	Prof. Paulus Indiyono
H	Ruang Anjasmoro 2 (Lt. 2)	Prof. Noor Endah B. Mochtar
I	Ruang Anjasmoro 3 (Lt. 2)	Prof. Nyoman Pujawan
J	Ruang Kelud (Lt. 2)	Prof. Mauridhi Hery Purnomo

**Moderator Sesion 2 (13.00 – 17.00)**

A	Ruang Argopuro 1 (Lt.1)	Dr. Agus Purwanto
B	Ruang Argopuro 2 (Lt. 1)	Dr. Achmad Arifin
C	Ruang Kawi (Lt. 1)	Dr. Bambang Lelono
D	Ruang Lawu (Lt. 1)	Dr. Sigit Darmawan
E	Ruang Semeru 1 (Lt. 1)	Dr. Endah Wahyuni
F	Ruang Semeru 2 (Lt. 1)	Dr. Djoko Purwanto
G	Ruang Anjasmoro 1 (Lt. 2)	Dr. Ketut Eddy Purnama
H	Ruang Anjasmoro 2 (Lt. 2)	Dr. Surya Rosa Putra
I	Ruang Anjasmoro 3 (Lt. 2)	Dr. Sri Gunani Pertiwi
J	Ruang Kelud (Lt. 2)	Dr. Prabowo

**Aturan Presentasi Seminar**

- a. Waktu presentasi adalah 12 menit/judul termasuk diskusi.
- b. Bel pertama pada menit ke 7, bel kedua pada menit ke 9, sisanya untuk berdiskusi sampai bel ke 3 di menit ke 12.
- c. Presenter dimohon untuk efisien dalam menggunakan waktu.
- d. Time keeper dimohon sangat ketat dalam menjaga waktu

## DAFTAR ISI

<b>Cover</b>	i
<b>Sambutan</b>	iii
<b>Ucapan Terima Kasih</b>	vii
<b>Susunan Acara</b>	viii
<b>Daftar Isi</b>	x

### ENGINEERING

[Eng-1] <b>A Concept Risk Management Model for Ship Construction Process With Externality Factors</b> MINTO BASUKI	1
[Eng-2] <b>Application of Particle Swarm Optimization for Tuning PID Controller in Automatic Generation Control Including Excitation System</b> CHALIS ZAMANI, MUHAMMAD ABDILLAH, AND IMAM ROBANDI	1
[Eng-3] <b>A Random Counter Using Shift Register and Encoder</b> LIANLY ROMPIS	2
[Eng-4] <b>Application of Geographical Information System (GIS) for Mapping Landslide Susceptibility: A Case Study of Timor Tengah Selatan, NTT Province</b> HERRY Z. KOTTA, GREGORIUS KLAU, SILVESTER TENA, HENDRO LAMI, YATURSANCE MANAFE, NIXSON MEOK, GODLIEF E. S. MIGE, AND K. RANTELOBO	2
[Eng-5] <b>Fuzzy PID Controller for Shaft Torque Wind Turbine</b> A.MUSYAFA, A.HUSNA, I.M.YULISTIYA NEGARA, AND IMAM ROBANDI	3
[Eng-6] <b>Application of Interval Type-2 Fuzzy Logic Based Power System Stabilizer for Dynamic Power System Stability</b> WAHYUDI, MUHAMMAD ABDILLAH, AND IMAM ROBANDI	3
[Eng-7] <b>Application of PCMSR Nuclear Power Reactor for Cogeneration as Eceltricity Production and Desalination</b> ANDANG WIDI HARTO, SETIAWAN EKO WAHYUDI, AND ESTER WIJAYANTI	4
[Eng-8] <b>Lead Acid Battery Modeling for Electric Vehicle</b> BAMBANG S.K, ARMAN JAYA, PURWADI A.D,DEDID C.H, AND MAURIDHIE H.P, SOEBAGIO	4
[Eng-9] <b>Maximum Power Point Tracking Using PID and Fuzzy Logic Control for Grid-Connected Photovoltaic System</b> ALI MUSYAFA, AGUS DHARMA, TAMAJI, I. MADE YULISTIYA NEGARA, AND IMAM ROBANDI	5
[Eng-10] <b>Load Forecasting for The Distribution Network of South and Middle Kalimantan Using Artificial Neural Networks Resilient Propagation</b> JAZULI FADIL, ONTOSENO PENANGSANG, AND ADI SOEPRIJANTO	5
[Eng-12] <b>GPU-Based Parallel Algorithm for Construction of Uniform Grid Structure</b> REZA FUAD R AND MOCHAMAD HARIADI	6
[Eng-13] <b>Creative Sublasi in Furniture Design from Used Corrugated Paper</b> THOMAS ARI KRISTIANTO	6
[Eng-14] <b>Design of PSO-SVR for Monthly Maximum Load Forecasting (case of study in Bali)</b> INDRI SURYAWATI AND IMAM ROBANDI	7
[Eng-15] <b>Dissolved Ammonia Removal from Aqueous Solution Through Hollow Fiber Membrane Contactor</b> SUTRASNO KARTOHARDJONO, DODI CANDRA, ACHMAD EFFENDI, AND NYI MAS ASRI M.	7
[Eng-16] <b>Causal Factors of Landslides at Panti Kabupaten Jember</b> AMIEN WIDODO, SUKANDARRUMIDI, DWIKORITA KARNAWATI, AND HERU HENDRAYANA	8
[Eng-17] <b>Craziness Particle Swarm Optimization (CRPSO) Solution for Optimal Economic Dispatch</b> RIO INDRALAKSONO, RIFAD MUBARAK BAMATRAF, AND IMAM ROBANDI	8
[Eng-18] <b>Design of Feedback Control Linear Quadratic Gaussian (LQG) for the Statcom (Case Study: Sulsebar System)</b> INDAR CHAERAH G, MUKHTAR SALEH, AND ADI SUPRIJANTO	9

[Eng-19] <b>Design of Three Phase Half Wave Rectifier With Minimum THD and Power Factor Close to Unity Using PI Fuzzy Switching Control in Boost Converter</b> AINUR ROFIQ N, IRIANTO, AND CAHYO FAHMA S	9
[Eng-20] <b>Dissolved Gas Analysis using Fuzzy Neural Network</b> HASAN BASRI AND LITASARI	10
[Eng-21] <b>Empowering of Information Technology to Increase HDI Level at Jembrana Regency</b> NUR LAILI	10
[Eng-22] <b>Design Optimal Linear Quadratic Regulator for Static Synchronous Compensator (Statcom) Using Particle Swarm Optimization</b> EFRITA ARFAH ZULIARI, MUHAMMAD ABDILLAH, AND MARWAN ROSYADI	11
[Eng-23] <b>Improvement of Dynamic Stability in Single Machine Infinite Bus (SMIB) using Linear Quadratic Regulator (LQR) based Artificial Bee Colony (ABC) Algorithm</b> FAJAR GALIH INDARKO, MUHAMMAD ABDILLAH, AND IMAM ROBANDI	11
[Eng-24] <b>Study of Wastewater Treatment (WWT) Seaweed Factory Capacity: 360 m<sup>3</sup> per day</b> PRAYITNO	12
[Eng-25] <b>Fuzzy Modulation in Networked Control System with Multiple Plant</b> MAHARDHIKA PRATAMA, IMAM ARIFIN, AND MOCH.RAMELI	12
[Eng-26] <b>An Investigation Into the Resistance/Powering and Seakeeping Characteristics of River Catamaran/Trimaran</b> I K A P UTAMA, A JAMALUDIN, AND MURDIJANTO	13
[Eng-27] <b>Internet-Based Information System of Shortest Route Management in Madiun's Transportation Using Greedy Algorithm</b> RUDY SETIAWAN	13
[Eng-28] <b>Binary Response Nonparametric Regression Model With Single Smoothing Predictor</b> JERRY DWI TRIJOYO PURNOMO	14
[Eng-29] <b>Identification of St Segment Changes of ECG Output Signal Using Wavelet Transformation</b> M. R. BILLAH, SUYANTO, AND A. M. T. NASUTION	14
[Eng-30] <b>Model Predictive Control Design Study on Multivariable Tennessee Eastman Plant</b> HARI SOLAGRATIA, SUTANTO HADISUPADMO, AND ESTIYANTI EKAWATI	15
[Eng-31] <b>Early Leak Detection of Pneumatic System using Pressure Differentiator</b> HARUS L.G	15
[Eng-32] <b>Natural Energy Utilization for Simple Walk-Up Flat's Design In Indonesia</b> ROBINHOT JEREMIA LUMBANTORUAN	16
[Eng-33] <b>Optimal Control Design of Power System Stabilizer in Single Machine Infinite Bus Using Crazy Particle Swarm Optimization</b> RIFAD MUBARAK BAMATRAF, MUHAMMAD ABDILLAH, AND IMAM ROBANDI	16
[Eng-34] <b>Optimal Load Frequency Control Design on Multi Area Power System Using Interval Type-2 Fuzzy PI Controller</b> MUH BUDI R WIDODO, MUHAMMAD ABDILLAH, AND IMAM ROBANDI	17
[Eng-35] <b>Optimal Placement of Capacitor for Reactive Power Compensation using Particle Swarm Optimization Time Varying Acceleration Coefficient</b> SEPTIAN DWIRATA, RIFAD M BAMATRAF, RIO INDRALAKSONO, ROBI FAJERIN, AND IMAM ROBANDI	17
[Eng-36] <b>Optimization of Cooling Water Network Using Water Pinch Analysis and Superstructure Optimization at Pulp and Paper Industry</b> RUSLI N, IVAN ANTONI, ELLINA S. PANDEBESIE AND RENANTO	18
[Eng-37] <b>Finding the Best Fishing Ship Principal Dimensions Using a Non-linear Programming Optimization Technique</b> MOHAMMAD NURUL MISBAH, AHMAD NASIRUDIN, AND DJAUHAR MANFAAT	18
[Eng-38] <b>An Implementation of Grid-Computing on Large-Scale Structural Analysis Problems</b> DATA IRANATA, AND RADITYO ANGGORO	19

[Eng-39] <b>Improvement of Respons Frequency and Noise Figure (<math>F_n</math>) of Heterojunction Bipolar Transistor <math>Si_{(1-x)}Ge_x</math> (HBT SiGe) based on Arrangement Mole Fraction (x) and Germanium Profile</b>	19
TOSSIN ALAMSYAH, DJOKO HARTANTO, NR PUSPAWATI, AND E SHINTA DEWI YULIAN	
[Eng-40] <b>Usage of Silica Powder for High Strength Concrete</b>	20
TRIWULAN, DANTO A, AND RUCHI R	
[Eng-42] <b>Performance of High Strength of Self Compacting Concrete with Hyperplasticizer and High Volume Fly Ash</b>	20
M.T. MUNIFSON, TRIWULAN, MUDJI IRMAWAN, AND PRIYO SUPROBO	
[Eng-44] <b>Percentages Influence of Non Organic Waste to Value Briquettes Waste Heat from Organic Waste Biomass Banten City Type Cilegon Rdf - 5 (Refused Derived Fuel 5) as an Alternative Fuel</b>	21
IMAN SAEFULOH, AND NIKETUT CATURWATI	
[Eng-45] <b>Rain Cell Size Determination using Granger Causality Test</b>	21
SIS SOESETIJO, ACHMAD MAULUDIYANTO, AND GAMANTYO HENDRANTORO	
[Eng-46] <b>Reduce Rank and Ensemble Kalman Filter : Analize and Its Application</b>	22
E. APRILIANI, B.A. SANJOYO, D.K. ARIF, AND D. ADZKIYAH	
[Eng-48] <b>Simulation Study of Injection Temperature, Holding Pressure, and Cooling Time Effects on Sink Mark Formation on Plastic Injection Moldings HDPE</b>	22
LATIFAH NURAHMI, AND I MADE LONDEN BATAN	
[Eng-49] <b>Study on Effects of Statcom Installation to Improved Voltage Stability in Sulselbar System</b>	23
INDAR CHAERAH G, ADI SUPRIJANTO, AND ONTOSENO PENANGSANG	
[Eng-50] <b>The Effect of Calcium on Strontium Waste Treatment using Electro Coagulation Method</b>	23
SUSETYO HARIO PUTERO, KUSNANTO, AND RATNA PUPITASARI	
[Eng-51] <b>Controller Design SMIB by Direct Feedback Linearization</b>	24
TAMAJI, MUSYafa A, AGUS DARMA, AND IMAM ROBANDI	
[Eng-54] <b>Task Oriented Behaviour-Based State-Adaptive PID (Proportional Integral Derivative) Control for Low-Cost Mobile Robot</b>	24
IGI ARDIYANTO	
[Eng-53] <b>Increasing The Acceptance And on-Line Transaction of an E-Commerce Site Using Technology Acceptance Model</b>	25
ALI SADIYOKO, CEICALIA TESAVRITA, AND RICKY KURNIAWAN	
[Eng-52] <b>Controller Design of Chua's Circuit by Sliding Mode Control and LMI</b>	25
TAMAJI, MUSYafa A, AGUS DARMA, AND IMAM ROBANDI	
[Eng-55] <b>The Effect of Copper Wire Extension under Grounding Cable to Ground Fault Current</b>	26
FACHRUDIN, MUHAMMAD ABDILLAH, AND IMAM ROBANDI	
[Eng-56] <b>The Performance Analysis of Traffic Patterns on Routing Protocols in Manet Using Network Simulator (Ns-2) and Tracegraph 202</b>	26
YURI ARIYANTO	
[Eng-57] <b>The Role of Control Systems for Improvement Quality of Human Resources</b>	27
H. ROHANI JAHJA WIDODO	
[Eng-58] <b>The Synthesis of Carbon Nanotube from the Waste of Ethanol Plant with Ni/Co Catalyst and Natural Zeolite as Supported Catalyst</b>	27
ADRIAN NUR, BREGAS SISWAHYONO T.S., CHRISTIAN WIDI NUGROHO, VINA VIKRYANA, AND RIAN HENDRATA	
[Eng-59] <b>The Use of Ceramic Membrane Contactor for Dissolved Ammonia Removal from Aqueous Solution</b>	28
SUTRASNO KARTOHARDJONO, DODI CANDRA, ACHMAD EFFENDI, AND NYI MAS ASRI M.	
[Eng-60] <b>Transient Stability Study on Sulselbar Interconnection System</b>	28
INDAR CHAERAH GUNADIN, NADJAMUDDIN HARUN, AND ADI SUPRIJANTO	

[Eng-61] <b>Application Technology Vacuum for Making Packaging Sea Pearl and Polymer Material Transparent</b> ADI WARDOYO	29
[Eng-62] <b>Implementation Airport Sequence Flasher using Cascade Villard Methode</b> DJOKO SUPRAJITNO R., SUWITO, AND ACHMAD AFFANDI	29
[Eng-64] <b>Development of Graph Mining for Activity Network Prediction in Real Time Gross Settlement (RTGS) Payment System</b> SAIFUL BUKHORI, MOCH. HARIADI, I KETUT EDDY PURNAMA, AND MAURIDHI HERI PURNOMO	30
[Eng-65] <b>Short Term Load Forecasting Using Hybrid Artificial Neural Networks and Particle Swarm Optimization</b> BAGUS HANDOKO, RIFAD M. BAMATRAF, RIO INDRALAKSONO, MUHAMMAD ABDILLAH, AND IMAM ROBANDI	30
[Eng-67] <b>Design of Linear Quadratic(LQ) Optimal Control using Bacteria Foraging Algorithm (BFA) for Frequency Performance Improvement on Power System</b> ISNAINI LAILI IZZATI, MUHAMMAD ABDILLAH, AND IMAM ROBANDI	31
[Eng-68] <b>Potential of Waste Biomass Palm Oil Energy as a Source of Electrical Energy in Indonesia</b> INDRA PERMATA KUSUMA	31
[Eng-69] <b>Design to Develop Build with Modular System Sludge as Mixture of Material Wall Partisi and Plafond Simple Building</b> ADI WARDOYO	32
[Eng-73] <b>The Characterization of Ring Laser Gyroscope System for Aircraft Navigation</b> SAYUTI SYAMSUAR USMAN AND P. S PRIAMBODO	32
[Eng-76] <b>Reconstruction of Object 3D using Poisson Surface</b> HERU ARWOKO AND MOCHAMAD HARIADI	33
[Eng-81] <b>Design of 12 Pulse AC to DC Converter With Power Factor Closed Unity and Minimum Harmonics Using Fuzzy Logic Controller On Boost Converter</b> AINUR ROFIQ N. AND SETYO SUKA WAHYU	33
[Eng-83] <b>Simulation Design Control System PID for Flexible-Link Cantilever Beam</b> AHMAD YANI, BAMBANG PRAMUJATI, AND AGUS SIGIT	34
[Eng-84] <b>Effect of Residual Stress to Behavior of Stub-Column Stress-Strain Curve</b> BUDI SUSWANTO AND DATA IRANATA	34
[Eng-85] <b>Optimization Coolpad and Auto Charger with PI Controller</b> BENNY SINGGIH SANTOSO AND RENNY RAKHMAWATI	35
[Eng-86] <b>Early Detection for Short Circuit Symptom at Single Phase Induction Motor Winding Using Neural Networks</b> DICKY N. WARDANA, DIMAS ANTON A., AND MAURIDHI HERY P.	35
[Eng-87] <b>Transistor Gas Sensor from Conducting Polymer as the Material</b> ICCHA HAMIDAH N AND MADE ASMAWATI	36
[Eng-88] <b>The Solution of Economic Dispatch for 26 Bus Power System Using Chaotic Ant Swarm Optimization (CASO)</b> EFRITA ARFAH ZULIARI AND IMAM ROBANDI	36
[Eng-90] <b>Pumping Station for Kali Medokan Flood Control using HecRas Program</b> S. KAMILIA AZIZ	37
[Eng-91] <b>Amperometric Glucose Biosensor based on Adsorption of Glucose Oxidize at Electrode by Screen Tension and Deflection Thick Film Method</b> AMINUDDIN DEBATARAJA, LATIF MAWARDI, AND NUR FAUZI SOELAIMAN	37
[Eng-92] <b>Application of Quasi-Passive Filter for Reduce Harmonic Distortion in Distribution Networks</b> SYISKA YANA, MOCHAMAD ASHARI, AND M. HERY PURNOMO	38
[Eng-93] <b>Application of Empirical Mode Decomposition Technique for Identifying Damage in a Frame Structure Excited by Earthquake Loadings</b> AGUNG BUDIPRIYANTO	38

[Eng-94] <b>Low Cost Method for the Fabrication Of SNO<sub>2</sub>:F Film for Transparent Conductive Glass Application</b>	39
AGUS PURWANTO, ARIF JUMARI, AGUS NUGROHO, DONI KURNIAWAN	
[Eng-97] <b>Natural Coastal Defence in Indonesia as Wave Energy Dissipation</b>	39
ANDRE FELIKS SETIAWAN, AND OLGA PATTIPAWAEJ	
[Eng-98] <b>Fuzzy Logic Controler Optimal for Charger Battery to Photovoltaic with Buck Boost Converter</b>	40
JEFRI LIANDA AND JOHNY CUSTER	
[Eng-99] <b>Design for Reconfigurable Manufacturing Systems (RMS)</b>	40
KHAMDI MUBAROK	
[Eng-105] <b>Integrated Model of <i>Balanced Score Card</i> and Technology Component Measurement : a Strategic Perspective in Indonesia Biofuel Engineering Development</b>	41
ARMAN HAKIM NASUTION, SUKARDI, AND ADITHYA SUDIARNO	
[Eng-107] <b>The Formation of Star Topology in Zigbee Network on the JN5139 Microcontroller Based</b>	41
BAMBANG SUGIARTO	
[Eng-108] <b>The Effect of Air Entry Velocity Variation to the Temperature Distribution of Conditioned Room, a Three Dimensional Experiment Study</b>	42
DENNY M.E. SOEDJONO	
[Eng-109] <b>Application of Biodiesel in Transportation Aspects a Review</b>	42
DHIKA RAMADHANNY PUTRA, SOKMA PRIMA, M. INDAH ZAINI, MUHAMMAD ARDIAN W, MARISON FERIANDI, CIPTO HADI PURNOMO, M. HENDRAJAT, AND RIDHO ROBBANI	
[Eng-110] <b>Design and Fabrication of Heater System NiCr Thin Films for the Application Gas Sensor Carbon Monoxide (CO) Environmental Monitoring</b>	43
AMINUDDIN DEBATARAJA, JAMSER SIMANJUNTAK, AND SURIPTO	
[Eng-111] <b>Grouting Application for Strengthening Foundation Structure of Dam Construction</b>	43
DWANDARI RALANARKO AND GUNTAR WIDIOKO	
[Eng-112] <b>Reduction of Fuel Consumption And CO<sub>2</sub> Emmisions as Impact of Economic Global Crisis and Imo Regulations</b>	44
EDDY SETYO KOENHARDONO AND EKO BUDI DJATMIKO	
[Eng-113] <b>Slope Stability Analysis to Determine Slope Strengthens Method in Avoiding Landmass Movement: Case Study in Gombel Lama Golf Course Semarang, Central Java</b>	44
DWANDARI RALANARKO AND AL HILAL	
[Eng-116] <b>Genetic Programing and L-System Method for Representing Identification of Plant Growth Visualization</b>	45
SUHARTONO, MOCHAMMAD HARIADI, AND MAURIDHI HERY P	
[Eng-121] <b>Petroleum Derivative Test with Clusters Gas Sensor</b>	45
SOETARNO, SUPRPTO, AND R.Y. PERRY BURHAN	
[Eng-124] <b>Analisy of Fully Controlled 12 Pulse Converte R System And Single Tuned Passive Filter Design to Reduce Harmonics</b>	46
MOH. MARHAENDRA ALI, MOCHAMAD ASHARI, AND MAURIDHI HERY PURNOMO	
[Eng-125] <b>Rainfall-Runoff Modelling in Deluwang Watershed With Storm Water Management Model (SWMM)</b>	46
MAHENDRA ANDIEK MAULANA AND NADAJDI ANWAR	
[Eng-130] <b>Modelling of Temperature Distribution During Machining Process using HSS Cutting Tool</b>	47
MOCHAMAD MAS'UD AND BAMBANG PRAMUJATI	
[Eng-131] <b>Biodiesel Production Continuous System using Oscilation Flow Reactor (OFR)</b>	47
NUR HAMZAH, SURYANTO, AND ZULMANWARDI	
[Eng-132] <b>Optimal Tuning of PSS and AVR Gain Using Particle Swarm Optimization Time Varying Acceleration in Single Machine Infinite Bus (SMIB)</b>	48
AS'ADI, RIFAD MUBARAK BAMATRAF, RIO INDRALAKSONO, MUHAMMAD ABDILLAH, AND IMAM ROBANDI	
[Eng-137] <b>Design and Manufacturing Electronics Control of Brown Gas Electrolyzer System</b>	48
RASIAWAN, I NYOMAN SUTANTRA, AND BAMBANG SAMPURNO	

[Eng-138] <b>Optimal Power Flow by Improved Adaptive Genetic Algorithm</b> PATRIA JULIANTO AND IMAM ROBANDI	49
[Eng-139] <b>Utilization of Renewable Energy Sources in Rural (a Case Study in the Village Slawu, Patrang, Jember)</b> HERU MIRMANTO	49
[Eng-141] <b>The Application of Reduced Rank Ensemble Kalman Filter to Estimate Heat Conduction Distribution</b> DIEKY ADZKIYA AND ERNA APRILIANI	50
[Eng-142] <b>The Soil Layer Clasification in Panti – Jember Based on Geoelectric Data’s Intepretation</b> NURUL PRIYANTARI, AGUS SUPRIANTO, AND SUPENO	50
[Eng-144] <b>Bending Strength Test and Fatigue Test in Composite Material AlSi10Mg + SiC (as Alternative Material for Ship Building)</b> PRANTASI HARMI TJAHJANTI	51
[Eng-146] <b>Biofuel Production from Catalytic Cracking Process of Oleic Acid and Metil Ester</b> NURJANNAH, ACHMAD ROESYADI, AND DANAWATI HP	51
[Eng-147] <b>Application Maintenance Engineering Technology Based Predictive Analysis and Experimental Review of Vibration Signals Bearing Damage Internal Combustion Engine</b> ACHMAD ZUBAYDI, I MADE ARIANA, LAHAR BALIWANGI, FRANSISKUS LOUHENAPESSY, MARCUS TUKAN, BSE, AND SEMUEL M. TARIBUKA	52
[Eng-151] <b>Influence of Shock Loading (4-Chlorophenol and 2,4 Dichlorophenol) Concerning Submerged Adsorption Hybrid Bioreactor (SMAHBR) Performance</b> TRI WIDJAJA, ALI ALTWAY, AND MUSFIL AS	52
[Eng-152] <b>Ethanol Production from Molasses with Immobilized Cells Technique in Packed Bed Bioreactor by Extractive Fermentation</b> MUSFIL AS, TRI WIDJAJA, AND ALI ALTWAY	53
[Eng-153 ] <b>Enzimatic Hydrolysis of Rice Straw to Glucose</b> NADIEM ANWAR, ARIEF WIDJAYA, AND SUGENG WINARDI	53
[Eng-154] <b>The Sunda Strait Infrastructure : a Concept Selection</b> DANIEL MOHAMMAD ROSYID	54
[Eng-156] <b>Ethanol Production from Molasses by Using of Mutated <i>Zymomonas Mobilis</i> which is Immobilized on <math>\kappa</math>-Carrageenan with Continous Stirred Tank Reactor</b> PRISKILA GITA MARIA SINAMBELA, AND TONTOWI ISMAIL	54
[Eng-157] <b>Design of AC to DC 3 Phase Fullwave Rectifier with Minimum THD and Unity Power Factor use PID Fuzzy Switching Control</b> IRIANTO, AINUR ROFIQ, AND HENDRA MARINTA ADITIA	55
[Eng-158] <b>Mass Transfer Modelling of Extraction of Asbuton using Kerosene Solvent</b> SUSIANTO, ALI ALTWAY, KUSNO BUDHIKARJONO, NOVI AKBA, AND YULIA RACHMAWATI	55
[Eng-159] <b>Safety Footpegs Design for Motorcycles Passenger</b> PRIMADITYA AND KRESNO SULASMONO	56
[Eng-162] <b>Frequency Control on Micro Hydro Power Plant using Fuzzy PI Controller</b> SOEDIBYO, IMAM ROBANDI, AND MOCHAMAD ASHARI	56
[Eng-164] <b>Solid Waste Digestate of Biogas Production from Blotong and <i>Azotobacter Chroococcum – Aspergillus Niger</i> Microbe Combined as Sources of Compost Production</b> S.R JULIASTUTI ,SOEPRIJANTO, A. PRAMONO AND H. PRABOWO	57
[Eng-166] <b>The First Design Automation System Power Crank Press Machine Based on PLC and Electro Pneumatic</b> SAMPURNO AND MOH. DWI NURO SODRUL HUDA	57
[Eng-168] <b>Isolation and Modification of Starch from Breadfruit</b> WILLY E HALIM, IRWAN SK PUTRA, FELYCIA E SOETAREDO, AND ANING AYUCITRA	58
[Eng-169] <b>Flood Mitigation by Application in Situ Early Warning System in Panti – Jember, East Java</b> ALBERTUS DJOKO LESMON AND SUPRIYADI	58



[Eng-171] <b>The Aliphatic Hydrocarbon of Medium Rank Coal From Kalimantan as Feasibility Indicator for Coal Liquefaction</b>	59
AMIEN SISWOYO, YULFI ZETRA, AGUS WAHYUDI AND R. Y. PERRY BURHAN	
[Eng-172] <b>Design of one phase AC- DC Full Wave Rectifier with Flyback Converter as DC Regulator Using PI Fuzzy Switching Controller</b>	59
SUTEDJO, RENNY RAKHMAWATI, AND YAMUDI	
[Eng-173] <b>Human Motion Variation Synthesis using BVH Data</b>	60
TRI MARYANTO AND MOCHAMAD HARIADI	
[Eng-175] <b>Vibration Modeling of Flexible-Link Arm Robot</b>	60
I.B. PUTU PUTRA ARIAWAN, AGUS SIGIT PRAMONO, AND BAMBANG PRAMUJATI	
[Eng-177] <b>Design and Development of Weather Forcase Simulators for Surabaya City by using Neural Network</b>	61
SYAMSUL ARIFIN	
[Eng-178] <b>Performance of Ventilation at Housing in Limited Area in Hot-Humid Region</b>	61
YUSWINDA FEBRITA, SRI NASTITI N EKASIWI, AND I.G. NGURAH ANTARYAMA	
[Eng-179] <b>Fabrication of Magnetic Field Censor's Base on Fluxgate Magnetometer</b>	62
AGUS SUPRIANTO. A, BOWO EKO CAHYONO, AND MITRA DJAMAL	
[Eng-181] <b>Behaviour of Precast Concrete Beam Column Joint for Earthquake Resistant House and Fast Build with Open Frame Structure</b>	62
DIAN ISLAMIYAH, ENDAH WAHYUNI, AND AMAN S	
[Eng-182] <b>An Investigation into the Mechanism System of Wave Movement to Power Catamaran</b>	63
MURDIJANTO, I.K.A.P UTAMA, R.HANTORO, AND A. YOGHI	
[Eng-184] <b>A Study Into the Development of Catamaran Fishing Vessel</b>	63
D. SETYAWAN, I K A P UTAMA, A SUGIARSO, AND MURDIJANTO	
[Eng-185] <b>Optimal Capacity of Capasitor using Particle Swarm Optimization (PSO) for Economic Dispatch</b>	64
JANITA DIAH INDIARTI, RIFAD MUBARAK BAMATRAF, RIO INDRALAKSONO, AND IMAM ROBANDI	
[Eng-187] <b>Reduction of Marine Diesel Exhaust Emission Using Seawater Electrolysis</b>	64
I MADE ARIANA	
[Eng-191] <b>Influence of Glucose from Enzymatic Hydrolysis of Sorghum Flour on Etanol Production Using Baker's Yeast Saccharomyces Cerevisiae</b>	65
SOEPRIJANTO, ARIEF WIDJAJA, ARINO ANZIP AND SUHARMADI	
[Eng-192] <b>Interpretation of Resistivity Data to Determine Distribution and Geometric of Sulphide Mineralization at Silo Jember East Java</b>	65
SUPENO AND NURUL PRIYANTARI	
[Eng-194] <b>Permanent Magnet Fabrication With Lumajang's IRON ORE as Raw Material</b>	66
LIZDA JOHAR MAWARANI, TAUFIK HIDAYAT, DYAH SAWITRI, ZULKIFLI A, AND SEKARTEDJO	
[Eng-195] <b>Flexural and Shear Behavior at Beam Column Joint Precast Concrete for Fast Build House and Earthquake Resistance with Infill Frame System</b>	66
BUDIANTO, TAVIO, AND DATA IRANATA	
[Eng-197] <b>Seismic Design of Precast Concrete House</b>	67
YUYUN TAJUNNISA, ANANTA SIGIT, TAVIO, AND ENDAH WAHYUNI	
[Eng-198] <b>Behaviour of Precast Concrete Beam for Earthquake Resistance and Fast Build House using Infill Frame System</b>	67
RETNO TRIMURTININGRUM, TAVIO, AND AMAN SUBAKTI	
[Eng-199] <b>Behavior of Precast Concrete Column for Fast-Build and Earthquake-Resistant House with Open Frame System</b>	68
FATHMAH MAHMUD, TAVIO, AND DATA IRANATA	
[Eng-200] <b>Design of Precast Concrete Column for Earthquake Resistant and Fast-Build House with Infill Frame System</b>	68
RECKY TIRTAJAYA, TAVIO, KURDIAN SUPRAPTO, AND AMAN SUBAKTI	

[Eng-201] <b>Design of Smart Course Control System Based on Fuzzy Logic in the Tracking Ship at Tanjung Perak Port Surabaya</b> AULIA SITI AISJAH	69
[Eng-202] <b>Islamic Urinal Design to Increase the Quality of Sholat and Business Opportunity of Sanitary Industry in Indonesia</b> BUDIONO, ERI NAHARANI USTADZAH, ANDHIKA ESTIYONO, AND EKO NURMIANTO	69
[Eng-203] <b>The Making of Natural Food Colours from Roselle Flowers (Hibiscus sabdariffa)</b> NILEM ONG, ROBY SUGIANTO, ERY S. RETNONINGTYAS, AND SURATNO LOURENTIUS	70
[Eng-208] <b>The Modeling Development of Induction Motor Propulsion for Electric Vehicle by Vector Control Model</b> ERA PURWANTO, SUBAGYO, MAURIDHI HERY P, ARMANJAYA, DEDID CH, PURWADI, AND BAMBANG KALOKO	70
[Eng-209] <b>Applying of Open Source Software : a Smart Solution to Face the Emulation in Creative Industries of Design and Architecture</b> FILIPUS PRIYO SUPROBO, AND FAILASUF HERMAN HENDRA	71
[Eng-210] <b>Inhibition of Development Stages and Globin Accumulation of P. Falciparum by Giving Prenylated Xanthenes from Garcinia Tetranda Pierre Stem Bark</b> HADI KUNCORO, ATY WIDYAWARUYANTI, AND TASLIM ERSAM	71
[Eng-211] <b>Predicting Silica Deposition in Enhanced Geothermal Systems</b> DONNY S. BHUANA1, PETER J. ASHMAN, AND GRAHAM J. NATHAN	72
[Eng-212] <b>Multivariable Predictive Control of the Anaerobic Digestion Based Generalized Predictive Control Algorithm</b> KATHERIN INDRIAWATI	72
[Eng-214] <b>Improvement Performance of Micro Hydro Power Plant Model Based Power Electronics</b> SOEDIBYO, ONTOSENO PENANGSANG, AND BAMBANG SUJANARKO	73
[Eng-215] <b>Application Model Adaptive Neuro-Fuzzy Inference System (ANFIS) Controller Simulator as a Steam Turbine Speed</b> SYAMSUL ARIFIN	73
[Eng-216] <b>Removal of Iron and Manganese using Micro Bubbles Ozonation and Membrane Filtration</b> EVA FATHUL KARAMAH, SETIJO BISMO, AND FAHRUR ROZI	74
[Eng-219] <b>Simulation of Distributorless Digital with Software Proteus 62.S4</b> LIZA RUSDIYANA AND BAMBANG SAMPURNO	74
[Eng-221] <b>Build the Control of Temperature and Dampness at Automatic Process Nesting Egg of Industrial Scale Home</b> BUDI LUWAR SANYOTO, SRI BANGUN SETYAWATI, AND NUR HUSODO	75
[Eng-223] <b>Increasing Indonesia Sea Endurance by Designing Fast Patrol Boat Maneuvering Control</b> AULIA SITI AISJAH	75
[Eng-224] <b>Increasing the Safety and Efficiency Sea Transportation by Designing Monitoring and Control System at Tanjung Perak Port</b> AULIA SITI AISJAH	76
[Eng-225] <b>Maximum Power Point Tracker based on Fuzzy Logic Controller for Stand-alone Photovoltaic</b> SYISKA YANA AND MOCHAMAD ASHARI	76
[Eng-227] <b>The Use of Acetylated Sago Starch as Soy Milk Ice Cream Stabilizer</b> HENDY HERYANTO, BOB M HOESAN, ANING AYUCITRA, AND FELYCIA E SOETAREDJO	77
[Eng-228] <b>Design and Implementation of Infrared Wireless Sensor Networks and RS-485 Network for Multi-floor Parking Information System</b> ALI HUSEIN ALASIRY, ENDAH SURYAWATI N, EDI SATRIYANTO, AND RIDLA RIZALANI A	77
[Eng-230] <b>Mixing Urea and Zeolite for Slow Release Fertilizer using Orbiting Screw Mixer</b> SEMUEL PATI SENDA, RENANTO HANDOGO, ACHMAD ROESYADI, AND WAHONO SUMARYONO	78
[Eng-231] <b>The Application of an Hybrid Trilateration Method for Multi-Robot Localization System</b> ENDAH S. NINGRUM AND ALI HUSEIN A.	78

[Eng-232] <b>Human-Friendly Arm Robot using Interactive Genetic Algorithm</b> INDRA ADJI SULISTIJONO, ENDAH S. NINGRUM, AND BAMBANG SUMANTRI	79
[Eng-233] <b>Energy Efficiency and Optimization of Hybrid Power System Configuration in Sebesi Island (Krakatau Conservation Area)</b> HERLINA, EKO ADHI SETIAWAN, AND IMADE ARDITA	79
[Eng-237] <b>Housing Provision for Low Income Household in Bekasi Case Study : Self-help Housing</b> SARAH CAHYADINI, COLLINTHIA ERWINDI, AND PURWANITA SETIJANTI	80
[Eng-238] <b>Internet Filter Software for Pornography Sites</b> JOSEPH DEDY IRAWAN	80
[Eng-240] <b>Materials Engineering of CuZn/Al<sub>2</sub>O<sub>3</sub> Composite for Bullet Application</b> WIDYASTUTI, ROCHMAN ROCHIEEM, AND MOCTAR KAROKARO	81
[Eng-241] <b>The Role of Art, Spiritual, Science, Engineering &amp; Technology (ASSET) for Improving Quality of the Indonesian Human Resources (IQIHR)</b> SUSANTO SAMBASRI AND ROHANI JAHJA WIDODO	81
[Eng-242] <b>Optimization of Heat Exchanger Network at Unit CDU on Petroleum Refinery</b> GALIH ABIPRAJA, SAIFUL ARIF RAMADHAN, AND RENANTO	82
[Eng-243] <b>Characteristics of Bottom Shear Stress and the Net Sediment Transport for Solitary Wave</b> SUNTOYO	82
[Eng-244] <b>Influence of Temperature Increase with Respect to Absorbed Energy, Lateral Expansion, and Shear Fracture Area of This Material (SA 350 LF 2 Class 1) to Determine the Transition Temperature</b> HARI SUBIYANTO AND SUBOWO	83
[Eng-245] <b>Comparative Study of Connection Quality of Welding (Submerged Arc Welding) between SS400 and Q235 Plate</b> SUBOWO AND HARI SUBIYANTO	83
[Eng-249] <b>Designing and Testing of Heat Engine for Small Scale Biomass Power Generation in Rural Area</b> WARINDI, HERI T. SETIAWAN, AGUNG B. MULJONO, AND SUPRIONO	84
[Eng-250] <b>Application of Interval Type 2 Fuzzy PI based Power System Stabilizers for Dynamic Stability Improvement in Single Machine Infinite Bus</b> MUHAMMAD RIDHA FAUZI, MUHAMMAD ABDILLAH, MUH. BUDI R. WIDODO, AS'ADI, AND IMAM ROBANDI	84
[Eng-251] <b>Optimal Sizing of Static Var Compensators (SVCs) for Reducing Power Losses in 500 kV JAMALI Grid Power System using Bacteria Foraging Algorithm (BFA)</b> JUNINGTIJASTUTI, MUHAMMAD ABDILLAH, FAJAR GALIH INDARKO, AND IMAM ROBANDI	85
[Eng-252] <b>The Prospect of Developing Combined Cooling, Heating and Power System with Biomass Energy in China</b> HAI-BIN GUAN, RONGF-FENG SUN, LI SUN, MIN XU, GUI-HUAN YAN, WEI-JIE ZHANG, JIAN-GUO JIANG, AND XIAO-XIA LI	85
[Eng-253] <b>Preliminary Experiments of Biomass Gasification in a Self-Heated fluidized Bed</b> FAN XIAOXU, XIAO QI, JIANG GUILIN, LI SONG, AND GUO DONGYAN	86
[Eng-254] <b>Kinetic Study of Acetol Formation (2-Hidroxy Propanone) through Dehydration of Glycerol</b> ABDUL CHALIM AND SUPRAPTO	86
[Eng-255] <b>Making Biodiesel from Rubber Seed Oil by Transesterification Process using Packed Bed Reactor</b> HARDJONO DAN RACHIMOELLAH	87
[Eng-256] <b>Material Stone Box</b> POERWADI	87
[Eng-259] <b>Design of Remote Terminal Unit (RTU) for Sea Water Quality Monitoring</b> IWAN MUHAMMAD ERWIN	88

## EDUCATION

- [Edu-1] **Weblog: a Selected Means for Promoting Learners' Autonomy in Learning English in Big Classes** 88  
KARTIKA NUSWANTARA
- [Edu-4] **Influence of Smart Game to Upgrade Memorize Ability in Social Science Subject of Fifth Grade Elementary School** 89  
SUGIARTO AND MULA KARTIKA YUDHA
- [Edu-5] **Implementation of Information Technology in Improving Service Management Quality at Stakeholders on SMA Muhammadiyah 1 Gresik** 89  
WARDIKIN
- [Edu-6] **Education in Family: Strategy to Antisipate Side Effects Technology Development** 90  
SITI ATIYYATUL FAHIROH
- [Edu-7] **Material Development in Life Skill Education in Indonesian Text Book by using Literacy Learning Model** 90  
SYAMSUL SODIQ

## SOCIAL ENGINEERING, SCIENCE, AND ARTS

- [Soc-3] **Market Branding and Macro Ergonomic Intervention to Revitalize Traditional Market using Dynamic System Model** 91  
EKO NURMIANTO, RAHMATSYAM LAKORO, MAHENDRA WARDHANA, AND NUGROHO PRIYO NEGORO
- [Soc-7] **The Mediating Effect of Satisfaction in Relationship Service Quality toward Word of Mouth of Passengers' Ferry's Transport after Suramadu Bridge Building** 91  
PRIBANUS WANTARA
- [Soc-8] **Study in Aesthetic "Budoyo Resik", a Basic Guide one of the Trust Java Community** 92  
R.BAMBANG GATOT SOEBROTO
- [Soc-9] **Earthquake : Mitigation Action , Hazard Mitigation Goals and Objectives, Grand Challenge for Disaster Reduction** 92  
SUNIK
- [Soc-10] **Case Study of Housing Subsidies Formal in Gresik** 93  
ANGGER SUKMA MAHENDRA, DIAN RACHMAWATI, AND HASIAN SIREGAR
- [Soc-12] **Housing Condition in Mataram, Nusa Tenggara Barat, in 2009** 93  
ISPURWONO SOEMARNO, ANDARITA ROLALISASI, AND ARFIANI SYARIAH
- [Soc-14] **In Search of New "Religion "in George Elliot's Middle March** 94  
MASULAH
- [Soc-15] **The Needs of Formal Housing, Housing by People, and Housing in Slum Area of Bengkulu** 94  
HAPPY RATNA SANTOSA
- [Soc-16] **Housing Delivery Systems in Banjarmasin** 95  
MUH.FAQIH, HARTATIK, AND EMA UMLIA
- [Soc-17] **Energy and Behavior in Term of Interior Design** 95  
YUSITA KUSUMARINI AND SRI NASTITI NUGRAHANI EKASIWI
- [Soc-18] **Ergonomic Design Emergency Disaster Kitchen using Mobile and Portable Concept** 96  
EKO NURMIANTO, BAROTO TAVIP INDROJARWO, AND TAUFIK HIDAYAT
- [Soc-19] **Identification of Green Open Space Private on Simple Housing Estate in Surabaya** 96  
IMA DEFIANA
- [Soc-20] **Adapting to Changing Times: Energy, Economy and Environment Alternatives in Sidoarjo Regency, Indonesia** 97  
JOHN MCLACHLAN

## MEDICAL AND LIFE SCIENCE

- [Med-1] **Three Prenylated Xhantone from *Garcinia* as Cancer Inhibitor** 97  
DWI OKTAVIANI JAMIL AND TASLIM ERSAM

[Med-3] <b>Evaluation of Mucoadhesive Metronidazole Tablets Containing Hydroxy Propyl Methyl Cellulose In Vitro</b> AGNES NUNIEK WINANTARI, ESTI HENDRADI, AND BAMBANG WIDJAJA	98
[Med-4] <b>Voltammetric Determination of Antimalarial Xanthone Compounds</b> MEGA VANIA, SUPRAPTO, AND TASLIM ERSAM	98
[Med-5] <b>Effect of Citric Acid and Tartaric Acid to Physical Characteristics of Spray Dried Effervescent Kemuning (<i>Murraya paniculata</i> (L.) Jack) Leaf Extract</b> AGNES NUNIEK WINANTARI	99
[Med-6] <b>Optimization of Chitin Production from <i>Penaeus Monodon</i> Shells at Ambient Temperature</b> CRESCENTIANA D. POELOENGASIH, HERNAWAN, SATRIYO K. WAHONO, SUHARTO, AND M. KISMURTONO	99
[Med-7] <b>Live Hope Prediction for Diabetes Patients Using Adaptif Swam Optimized Organizing Map (ASWOM)</b> LILIK ANIFAH DAN MAURIDHI HERY PURNOMO	100
[Med-8] <b>Dreg and Husk of Jathropa Seed and the Mixed of Organic Garbage for Making the Briquette as an Alternatif Energy</b> ANDRI DHARMAWAN, THOMAS SUGIARTO GUNAWAN, ANTARESTI, AND SURATNO LOURENTIUS	100
[Med-9] <b>Synthesis and Characterization of Mesoporous ZSM-5: Influence of Aging Time</b> TRI ESTI PURBANINGTIAS, DJOKO HARTANTO, AND DIDIK PRASETYOKO	101
[Med-11] <b>Development Indonesian Wood Qualities by Complex Reaction</b> TASLIM ERSAM, VIVI AYU MUNAS AROFAH, AND ANIS IKA ROSYDA	101
[Med-12] <b>Bioactivity Study of Alkaloid Compounds from <i>Actinodaphne Glomerata</i></b> YULFI ZETRA, R.Y. PERRY BURHAN, AND DINA W.	102
[Med-13] <b>Sustainability of <i>Fragraea Elliptica</i> as an Endemic Species of Karimunjawa Island</b> LISTIANI AND TUTIK NURHIDAYATI	102
[Med-16] <b>Preliminary Observation on Marine Sponge Diversity at Pecaron Bay Pasir Putih Situbondo - East Java</b> EDWIN SETIAWAN, AWIK PUDJI DIAH NURHAYATI, SRI NURHATIKA, AND FARID KAMAL MUZAKI	103
[Med-17] <b>Simple <i>Microbial Soil Slant</i> Technological Application in the Dish-washing Greywater Recycling Process</b> ALI BUDHI KUSUMA, ANDINI WARUH WEDARINGTYAS, AND MALIKI UTAMA PUTRA	103
[Med-18] <b>Design and Fabrication Gas Sensor Based on Conductive Polymer</b> AGUSTIANA, IKA ATIKAWATI, ITA ULFIN, AND SUPRAPTO	104
[Med-19] <b>Transient Stability Analysis with Solving Differential Equation Of Multimachine Power System</b> FEBRIANA KRISTANTI	104
[Med-20] <b>The Influence of Nursing Intervention through Family Pathnership toward the Practice of Feeding Pattern on Infant of Age 6-24 Months for Nuclear and Extended Family</b> A.AZIZ ALIMUL HIDAYAT, MOERSINTOWARTI B. NARENDRA, AND WINDHU PURNOMO	105
[Med-21] <b>Reducing Large Data by Squashing Method</b> WAHYUNI SURYANINGTYAS	105
 <b>AGRICULTURE AND ENVIRONMENT</b>	
[Agr-4] <b>Application Agrogeology Geotech in Landslide Disaster Langkap – Purbalingga</b> INDRA PERMANAJATI AND SUBANA	106
[Agr-6] <b>The Subsurface Interpretation of The Mrawan Tunnel Based on Ground Penetrating Radar Data's</b> PUGUH HISKIAWAN AND AGUS SUPRANTO	106
[Agr-7] <b>Ecological Function of Tree as Noise Abatement for Supporting Environment Health Surrounding Streetscape</b> IMAWAN WAHYU HIDAYAT	107

## ENGINEERING

- [Eng-63] **Rancang Bangun Perlengkapan Motor untuk Penumpang Sebagai Solusi Peningkatan Keamanan Penumpang** 108  
KRESNO S. DAN PRIMADITYA
- [Eng-71] **“PLAZORE” Sistem Goreng Kantung Plastik untuk Bahan Baku Produk Kerajinan** 108  
ELLYA ZULAIKHA DAN WALUYOHADI
- [Eng-72] **Pengembangan Simulasi Aliran Air pada Saluran Drainase Kota Menggunakan Pemodelan Network Flow** 109  
EVI SEPTIANA PANE DAN KETUT EDDY P.
- [Eng-75] **Aplikasi Fuzzy Logic Controller (FLC) Untuk Optimasi Penjadwalan Perawatan Unit Pembangkit Thermal** 109  
JEFRI LIANDA DAN STEPHAN
- [Eng-77] **Variabilitas Spasial Hujan Bulanan dan Hujan Tahunan Di Jawa Timur** 110  
SRI WAHYUNINGSIH, INDARTO, AND MARTA ADI KIRANA
- [Eng-79] **Monitoring Eutrofikasi Secara *In Situ* dengan Teknik *Diffusive Gradient in Thin Film (DGT)*: Kajian Interaksi antara Sedimen dan Badan Air** 110  
BARLAH RUMHAYATI
- [Eng-80] **Kinetika Dekomposisi Metana dengan Katalis Ni/Cu/Al<sub>2</sub>O<sub>3</sub> Menggunakan Reaktor Katalis Terstruktur** 111  
PRASWASTI PDK WULAN, YUSWAN MUHARAM, DAN WIDODO WAHYU PURWANTO
- [Eng-89] **Kolaborasi Mahasiswa dan Masyarakat dalam Pembangunan dan Swakelola Sistem Pengangkatan Air Menggunakan Energi Matahari** 111  
GAMA HAFIZH ADITYA , MULYANA KARIM, BAYU BUANA NATANAGARA, SHOFIAH HAYATI, AISYA VELASOFI, DHANIS WORO F., ANTON HIDAYAT, TEUKU LUKMAN NH, DAN AHMAD AGUS S.
- [Eng-95] **Desain, Implementasi, dan Analisa Kinerja Sistem Pengaturan Berjaringan pada Skala Laboratorium** 112  
ALI FATONI, YUSUF BILFAQIH, DAN SHOLIKUL DARMA SETYAWAN
- [Eng-96] **Perancangan dan Realisasi Kontroler PID Adaptif pada Pressure Process Rig 38-714** 112  
IMAM ARIFIN, MOCHAMMAD RAMELI, DAN FAJAR KURNIAWAN
- [Eng-102] **Sistem Pengaturan Berjaringan: Perancangan dan Realisasi Koneksi Plant pada Jaringan** 113  
ALI FATONI, ASEP ARWAN SULAEMAN, DAN ZULKFLI HIDAYAT
- [Eng-103] **Perancangan dan Realisasi Kontroller untuk Pengaturan Motor DC melalui Jaringan** 113  
IMAM ARIFIN, MUHAMMAD YANUAR H, DAN MOCHAMMAD RAMELI
- [Eng-119] **Optimalisasi daya pada Solar Cell menggunakan Power Tracker** 114  
HARTONO DAN M.ASHARI
- [Eng-115] **Pengembangan Mekanisme Multiplatform Robot Pencari Korban Bencana Alam** 114  
INDRA ADJI SULISTIJONO, SON KUSWAD, EKO HENFRI BINUGROHO, DAN ACHMAD JAZIDIE
- [Eng-104] **Studi Eksperimen Sistem Pengaturan Berjaringan dengan Pendekatan Logika Fuzzy pada Motor DC berbasis LabVIEW** 115  
IMAM ARIFIN, DIMAS SYARIF, DAN KATJUK ASTROWULAN
- [Eng-123] **Model Hidrologi DAS ITN 2, Mengakomodasi Pengaruh Penggunaan Lahan dalam Analisa Potensi Sumberdaya Air** 115  
KUSTAMAR, SELVESTER SARI SAI, DAN ERNI YULIANTI
- [Eng-127] **Proses Produksi Dietil Eter dengan Berbagai Jenis Katalis dan Reaktor Unggun Tetap** 116  
WIDAYAT, A ROESYADI, DAN M RACHIMOELLAH
- [Eng-128] **Identifikasi Partial Discharge pada Motor Tegangan Tinggi Menggunakan ANFIS Berdasarkan Spektrum RTDs** 116  
INDRA BUDI HERMAWAN, I MADE YULISTYA NEGARA, DAN MAURIDHI HERY PURNOMO
- [Eng-129] **Peningkatan Prosentase Fe<sub>2</sub>O<sub>3</sub> dari Pasir Besi sebagai Bahan Baku Magnet Permanen Keramik dengan Metode Hydrothermal Oxidation** 117  
DYAH SAWITRI, SEKARTEDJO, ZULKIFLI, DAN LIZDA JOHAR

[Eng-133] <b>Peningkatan Produktifitas Etanol oleh <i>Sacharomyces cerevisiae</i> dengan Operasi Tekanan Vakum</b> ABDULLAH DAN WIDAYAT	117
[Eng-134] <b>Analisis Manfaat Teknis Pengintegrasian PLTM Tersebar pada Sistem Distribusi (Studi Kasus pada Rencana Pembangunan PLTM Muaro Sako Di Wilayah Kerja PLN Ranting Balai Selasa, Kab. Pesisir Selatan, Sumatera Barat)</b> REFDINAL NAZIR DAN AHMAD TOPAN	118
[Eng-135] <b>Pengembangan Klasifikasi Berbasis Gravitasi Data untuk Data Pelatihan yang Tidak Imbang</b> MUHAMAD ARIEF HIDAYAT DAN ARIF DJUNAIDY	118
[Eng-140] <b>Pembuatan Aplikasi Peta Potensi Rawan Banjir Berbasis Gis pada Badan Lingkungan Hidup Surabaya</b> NUR NAFISA AMINA DAN JOKO LIANTO BULIALI	119
[Eng-148] <b>Development of Integrated Hydro Powerplant Design Module</b> RACHMAWAN BUDIARTO, AYODYA PRADHIPTA TENGGARA, ALEXANDER AGUNG, HANGGORO, DAN RACHMAD JAYADI	119
[Eng-149] <b>Rancang Bangun Text to Sound Menggunakan Metode Hybrid sebagai Sarana Membantu Komunikasi Tuna Netra dan Tuna Wicara</b> LILIK ANIFAH, HAINUR RASID ACHMADI, DWIKORANTO, DAN HARYANTO	120
[Eng-160] <b>Rancang Bangun Pembangkit Listrik Tenaga Surya Portable untuk Daerah Terpencil</b> ISDAWIMAH, ISMUJIANTO, DAN SILO WARDONO	120
[Eng-161] <b>Rancang Bangun Interior Modular Car Body Kereta Api Kelas Satu Generasi Baru untuk Meningkatkan Daya Saing Industri Transportasi Nasional</b> BAMBANG TRISTIYONO, AGUS WINDHARTO, YUNENDAR ARYO HANDOKO, DAN BAMBANG ISKANDRIAWAN	121
[Eng-165] <b>Sistem Pengaturan Berjaringan: Analisis Kinerja Kontroler terhadap Delay dan Packet Dropout</b> MOCHAMMAD SAHAL, GALIH WIDODO, DAN KATJUK ASTROWULAN	121
[Eng-174] <b>Efisiensi Peredaman Energi dan Oksigen Terlarut dalam Aliran di Bendung Dawuan Situbondo</b> EDIJATNO, N. ANWAR, DAN V. DERMAWAN	122
[Eng-183] <b>Penempatan Multigate pada Produk Plastik Injection Mold untuk Meminimasi Cacat Lentingan (Warpage) Studi Kasus Rak Kandang Ayam</b> DADAN HERYADA, BAYU PRATAMA, HARTONO, JATA BUDIMAN, DAN YOSEPH ARDIANTO	122
[Eng-186] <b>Perancangan dan Realisasi Kontroler Linear Quadratic Regulator (LQR) pada Pressure Process RIG 38-714</b> KATJUK ASTROWULAN, ARIE WIBOWO, DAN IMAM ARIFIN	123
[Eng-193] <b>Pengendalian Rasio Continuous Variable Transmission (CVT) Terbaru dengan 2 Penggerak untuk Kendaraan Roda 4 Berbasis Close Loop Control</b> WIDJOKONGKO H, BAMBANG SAMPURNO, I.N. SUTANTRA, DAN SUHERIYANTO	123
[Eng-196] <b>Analisa Statistik untuk Studi Karakteristik Hidrologi Das-Das di Jawa Timur</b> INDARTO, SRI WAHYUNINGSIH, DAN ISHAK AFFANDI	124
[Eng-206] <b>Teknologi Informasi dan Pendataran Indonesia</b> AHMAD LABIB	124
[Eng-213] <b>Digitalisasi – AWLR(Automatic Water Level Recorder) Pada FEWS (Flood Early Warning System) DAS Sampean Madura Di Kab. Situbondo – Jawa Timur dengan Komunikasi GSM (DIAL &amp; SMS) Gateway</b> FITRI ADI ISKANDARIANTO, HERI JUSTIONO, AND HENDRA CORDOVA	125
[Eng-218] <b>Aplikasi Gelombang Ultrasonik Efek Doppler untuk Pengukuran Kecepatan Pergerakan Benda</b> HARRIS PIRNGADI, MUHAMMAD RIVAI, DAN MIFTAH NURUL KARIM	125
[Eng-220] <b>Pengembangan Material Karet Bantalan Mesin (Engine Mesin) pada Formula Kompon Karet Alam</b> NUR HUSODO	126

[Eng-235] <b>Pengembangan Teknologi PLTPH dalam Upaya Meningkatkan Daya Gunanya sebagai Sumber Energi Listrik Rumah Tangga</b> REFDINAL NAZIR	126
[Eng-246] <b>City Branding Surabaya sebagai Pusat Industri Kreatif Nasional</b> BAROTO TAVIP INDROJARWO, SABAR, DAN ELLYA ZULAIKHA	127
[Eng-247] <b>Improvement of Process Data Quality Using Data Reconciliation and Gross Error Detection, Case: Steam Metering System – Methanol Synthesis Unit</b> IMAM ABADI DAN ALI MUSYAFA	127
[Eng-248] <b>Aplikasi SIS (Safety Instrumented System) pada Kontrol Temperatur Turbin Gas</b> HENDRA CORDOVA DAN MASRUL ARIF	128
[Eng-258] <b>Experiment and Simulation for Drying Characteristics of Ammonium Sulphate Fertilizer</b> SUSIANTO, ALI ALTWAY, KUSNO BUDIKARJONO, MARGONO, RADITYA CAESARYANTO, DAN SALMAN AL RASYID	128
[Eng-260] <b>Estimator Growth Rate of Anaerob Microorganism Based on Artificial Neural Network</b> TOTOK SOEHARTANTO, RONNY DWI NORIYATI, AND RADIATMOKO	129
<b>EDUCATION</b>	
[Edu-2] <b>Kualitas Kekaryaan dan Komitmen Terhadap Kinerja Guru Sekolah Dasar di Kecamatan Wonokromo Surabaya</b> GENDUT SUKARNO	129
[Edu-3] <b>Kajian Pendidikan Menengah Formal di Indonesia dalam Kaitan Menyeimbangkan antara Lulusan dengan Kebutuhan Kerja ( Studi Kasus Sistem Pendidikan di Jawa Timur )</b> TOTOK MULYONO	130
<b>SOCIAL ENGINEERING, SCIENCE, AND ARTS</b>	
[Soc-4] <b>Logofilosofi dan Unconditional Forgiveness : Sebuah Upaya Pelembagaan Ingatan Sosial pada Korban dan Keluarga Korban Tragedi Politik yang Traumatis</b> RIZQY AMELIA ZEIN BADJABIR DAN JONNY EKO YULIANTO	130
[Soc-5] <b>Pengaruh Penentuan Lokasi Backing Plate dengan Pendekatan Teori ABC dan Skenario Simulasi Monte Carlo</b> NENGAH KARTA DAN NYOMAN PUJAWAN	131
[Soc-6] <b>Mempergunakan Paradigma Seni untuk Membangun Identitas dalam Desain: Estetika Terintegrasi</b> JULY HIDAYAT	131
[Soc-13] <b>Konsep Housing Queue dalam Menentukan Prioritas Subsidi Perumahan</b> WAHYU SETYAWAN, RITA ERNAWATI, DAN JOHAN SILAS	132
<b>MEDICAL AND LIFE SCIENCE</b>	
[Med-2] <b>Pembuatan Sensor Elektrokimia Berbasis Emas Nanopartikel untuk Kuantisasi Rasa Pedas secara Voltametri</b> FREDY KURNIAWAN, LIANA ARI WIDYANTI, DAN KUNTHI FATMAWATI	132
[Med-10] <b>Uji Senyawa Antimalaria Golongan Alkaloid secara Voltametri Siklik</b> DEVYANA DYAH WULANDARI, TASLIM ERSAM, DAN SUPRAPTO	133
<b>AGRICULTURE AND ENVIRONMENT</b>	
[Agr-8] <b>Potensi dan Prospek Pengembangan Tanaman Sorgum Manis (Sorghum Bicolor L.) sebagai Sumber Energi Baru dan Terbarukan</b> SAMANHUDI	133



# Controller Design of Chua's Circuit by Sliding Mode Control and LMI

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**Abstract**— In this paper, we studied controller design of Chua's circuit which is chaos system. This system contents the non linear part and we applied the sliding mode control as design controller. Here, it is given the dynamic compensator to avoid the chattering in the sliding mode control. The dynamical compensator is design by using the linear matrix inequality (LMI). The simulation has been done by Matlab. Some of dynamic compensator is tried to observe the performance of system.

**Keywords**— Chaos control, sliding mode control, dynamic compensator, LMI

## 1. Introduction

The study of chaos system has been done by some researchers. The chaos is happen because the system has certain parameter, and if the parameter has little changes then the system performance is changing and uncontrollable For long time ago, it is stated that the chaos is unpredictable and uncontrollable. But in 1990, Ott did research in the chaos system [1], and after that a lot of research are doing in various fields. Chua's circuit and Lorenz system are chaos systems. In 2007, [2] studied the chaos synchronization by control based on the three diagonal structure, and [2] studied the synchronize method of fractional Lorenz system, Chen system and Chua's circuit.

Sliding mode control is one of the controller design method which is used in a lot of area. The sliding mode controller is applied in the chaos system [1]. The sliding mode controller is adopted for the robust design controller of uncertain system, because the sliding mode controller is easy o apply, has a quick response, has good transient performance and insensitivity in plant parameter and external disturbance [1].

Usually, the process has two steps, those are design Of sliding surface to assure that the sliding mode equation is stable, and the second is the controller design to drive the state system to sliding surface in finite time. In recent year, variable

structure design technique of sliding mode is a popular method in chaos system. Such as [3] studied the chaos control by using sliding, mode theory, and also [4].

In sliding mode controller usually the chattering is happen, the chattering disturbs the performance of system. [1] proposed the new reached law and derived the continue controller to reduce the chattering phenomena. The parameter of sliding surface is obtained by solving the linear matrix inequality (LMI). To handle the linearity part, [1] give the dynamic compensator such that the stability of system is increased.

In this paper, we applied the sliding mode controller to Chua's Circuit, we derive the feedback control, the LMI by using the Lyapunov stability theorem. We choose some value of dynamic compensator and sliding coefficient such that the LMI is satisfied. Some simulation are made by Matlab program. The performance of Chua's circuit system is observed.

## 2. Mathematical Model of Chua's Circuit.

The Chua's Circuit is a simple electronic circuit made of two capacitors, one linear resistor, one inductor and one non linear diode [5]. Suppose  $x_1, x_2, x_3$  is a current through the inductor, a voltage across capacitor  $C_1$  and across the inductor and the voltage across the

capacitor  $C_2$ , respectively then system can be written as mathematical model [1]:

$$\begin{aligned}\dot{x}_1(t) &= -x_1 + x_2 + x_3 \\ \dot{x}_2(t) &= -\beta x_1 + u_1 \\ \dot{x}_3(t) &= \alpha(x_1 - x_3 - g(x_3)) + u_2\end{aligned}\quad (1)$$

with non linear part

$$g(x_3) = nx_3 + \frac{1}{2}(m-n)(|x_3 + 1| - |x_3 - 1|)$$

The chaos will be happen if the value of parameters are

$$\alpha = 40, \beta = 93.333, m = -1.139, n = -0.711$$

and  $u_1 = u_2 = 0$ .

The system Eq (1) can be written as state space system

$$\begin{aligned}\begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \\ \dot{x}_3 \end{bmatrix} &= \begin{bmatrix} -1 & 1 & 1 \\ -\beta & 0 & 0 \\ \alpha & 0 & -\alpha \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} \\ &+ \begin{bmatrix} 0 \\ 0 \\ -\alpha g(x_3) \end{bmatrix} + \begin{bmatrix} 0 & 0 \\ 1 & 0 \\ 0 & 1 \end{bmatrix} \begin{bmatrix} u_1 \\ u_2 \end{bmatrix}\end{aligned}\quad (2)$$

And we can write as general equation

$$\dot{x}(t) = Ax + f(x) + Bu \quad (3)$$

The system (2) and (3) is unstable. Now, we design the controller such that those system are stable. Here we use the sliding mode controller as design control and we observe the system performance.

### 3. Sliding Mode Controller

The sliding mode controller method, usually has two steps. The first one is the design sliding surface and the second is the design controller such that the states of system reach the sliding surface.

#### 3.1. Sliding Surface Design

Suppose the sliding surface is

$$s = Cx + z \quad (4)$$

where  $C, s, x, z$ , are matrix which is determined, sliding surface, state variable, the state dynamic compensator, respectively. The state dynamic compensator satisfied:

$$\dot{z} = Kx - z \quad (5)$$

Matrix  $K$  will be determined by solving the linear matrix inequality (LMI).

If we take the differential of sliding surface in Eq (5) respect to system Eq (3) we obtained

$$\dot{s} = C\dot{x} + \dot{z} = CAx + Cf(x) + CBu + Kx - z \quad (6)$$

In sliding surface,  $\dot{s} = 0$  so that we get the control equivalent

$$u_{eq} = (CB)^{-1}(-CAx - Cf(x) - Kx + z) \quad (7)$$

The matrix  $C$  will be determined and satisfies  $CB = I$  such that control equivalent become

$$u_{eq} = -CAx - Cf(x) - Kx + z \quad (8)$$

We substitute the equation (8) to equation (3) then we get

$$\begin{aligned}\dot{x} &= Ax + f(x) + B(-CAx - Cf(x) - Kx + z) \\ &= \{A - BCA - BK\}x + Bz\end{aligned}\quad (9)$$

In sliding surface, we know that  $s = 0$  so that  $z = -Cx$  and equation (9) can be written as

$$\begin{aligned}\dot{x} &= \{A - BCA - BK\}x - BCx \\ &= \{A - BCA - BK - BC\}x \\ &= \{A - B(K + C + CA)\}x\end{aligned}\quad (10)$$

Suppose matrix,  $M = -(K + C + CA)$  then the equation (10) can be written as

$$\dot{x} = (A + BM)x \quad (11)$$

According the control theory, if (A,B) is controllable then there is always exist the matrix  $M$  such that matrix  $A + BM$  negative definite ( $A + BM < 0$ ).

And the eigen value of matrix  $A + BM$  can be place in half left plane or have a negative real part. Therefore, we can adopt the pole assignment method to obtain matrices  $K, C$ . The matrices  $K$  and  $C$  can be obtained by solving the linear matrix inequality (LMI). The LMI is derived from the Lyapunov stability criteria.

Suppose a vector  $V(x) = x^T x$  is a Lyapunov function candidate of equation (11). The system (11) is stable if satisfies:

$$a. V(x, t) \geq 0, V(0, t) = 0$$

$$b. \dot{V}(x, t) < 0$$

We know that  $V(x) = x^T x > 0$  and

$$\dot{V} = \dot{x}^T x + x^T \dot{x} \quad (12)$$

Substitute from equation (11) to equation (12) we get

$$\begin{aligned} \dot{V} &= (A - B(K + C + CA))x^T x \\ &+ x^T (A - B(K + C + CA))x \\ \text{or} \\ \dot{V} &= x^T (A^T - K^T B^T - C^T B^T - A^T C^T B^T \\ &+ A - BK - BC - BCA)x \end{aligned} \quad (13)$$

Suppose

$$\begin{aligned} \Omega &= A^T - K^T B^T - C^T B^T - A^T C^T B^T \\ &+ A - BK - BC - BCA \end{aligned}$$

Then we can write equation (13) as  $\dot{V} = x^T \Omega x$ .

If  $\Omega < 0$  (negative definite) then  $\dot{V} < 0$  that is mean the system (11) asymptotical stable. The inequality

$$\begin{aligned} A^T - K^T B^T - C^T B^T - A^T C^T B^T \\ + A - BK - BC - BCA < 0 \end{aligned} \quad (14)$$

is known as linear matrix inequality (LMI).

Now, we must determine matrices C and K such that the matrix inequality  $\Omega < 0$  satisfies.

In the Chua's circuit equation (2) we have matrices

$$\begin{aligned} A &= \begin{bmatrix} -1 & 1 & 1 \\ -\beta & 0 & 0 \\ \alpha & 0 & -\alpha \end{bmatrix}, B = \begin{bmatrix} 0 & 0 \\ 1 & 0 \\ 0 & 1 \end{bmatrix}, \\ C &= \begin{bmatrix} C_{11} & 1 & 0 \\ C_{21} & 0 & 1 \end{bmatrix}, K = \begin{bmatrix} k_{11} & k_{12} & k_{13} \\ k_{21} & k_{22} & k_{23} \end{bmatrix}, \end{aligned}$$

So that we get

$$\Omega = \begin{bmatrix} -2 & 1-k_{11} & 1+k_{21} \\ -k_{11}+1 & -2k_{12}-2C_{11}-2 & -k_{13}-C_{11}-k_{22}-C_{21} \\ -k_{21}+1 & -k_{22}-C_{21}-k_{13}-C_{11} & -2k_{23}-2C_{21}-2 \end{bmatrix}$$

By Liapunov stability criteria, if matrix  $\Omega$  negative definite then the system (11) asymptotical stable.

The value of matrices C and K such that matrix  $\Omega$  negative definite that is mean we solve the linear matrix inequality-LMI equation (14).

### 3.2. Design Controller

According [1], suppose we take the reached law

$$\dot{s}(t) = -(\mu + \eta \|s\|^{p-1})s, 0 < \gamma < 1, \mu, \eta > 0$$

Then the state variable  $x(t)$  will reach the sliding surface  $\{x | s = 0\}$  in finite time, and by applying the control vector

$$u = -CAx - Cf - Kx + z - (\mu + \eta \|s\|^{\gamma-1})s \quad (15)$$

Then the state of system (11) from arbitrary initial condition will toward to sliding switching and reach the sliding surface in finite time [1].

So, the system (2) or (3) will be asymptotical stable if we apply the control input (15) with value of matrices C and K satisfies equation (14).

### 4. Simulation Result

In this simulation we take the parameter as follows [5]

$\alpha = 40, \beta = 93.333, m = -1.139, n = -0.711$ , the

initial state  $(x_1(0), x_2(0), x_3(0)) = (1, 0, -1)$  and the

initial compensator state  $(z_1(0), z_2(0)) = (1, -2)$ ,

parameter  $\mu = 1, \eta = 2, \gamma = \frac{1}{2}$ . Here we take

some values of C and K which is satisfies equation (14). For case 1

$$C = \begin{bmatrix} 31 & 1 & 0 \\ -40 & 0 & 1 \end{bmatrix}; K = \begin{bmatrix} 1 & -30 & 30 \\ -1 & 2 & 50 \end{bmatrix}$$

The inequality (14) is satisfies and the system asymptotical stable. Figure 1a. shows the performance

of Chua's circuit without control ( $u=0$ ). The system (2) is unstable, but after we applied the sliding mode

control with dynamical compensator, the system is asymptotical stable (Fig. 1b.). Figure (1c) shows the

Chua's circuit system with control in three dimensional. The control input is showed in Figure (1d).

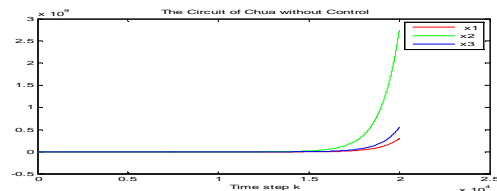


Figure 1a. The system without control

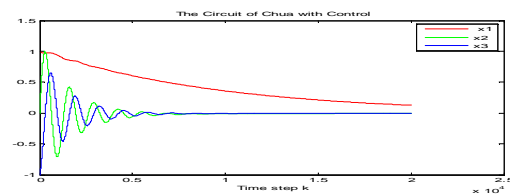


Figure 1b. The system with control

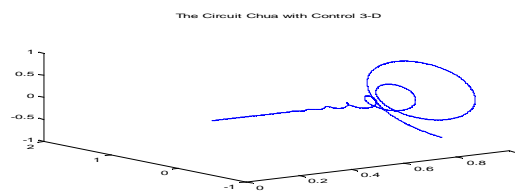


Figure 1c. The system with control 3-D

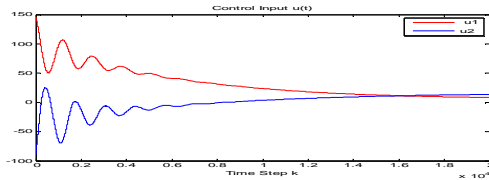


Figure 1d. Control input u(t)

For case 2:

$$C = \begin{bmatrix} 3 & 1 & 0 \\ -4 & 0 & 1 \end{bmatrix}; K = \begin{bmatrix} 1 & -3 & 3 \\ -1 & 2 & 5 \end{bmatrix}$$

The performance Chua's circuit with control is showed Figure 2a. The system with control in three dimension is showed Figure 2b. and the control input vector is showed Figure 2c.

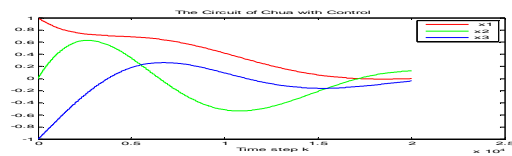


Figure 2a. The system with control

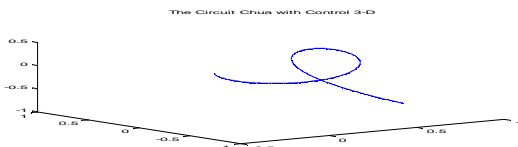


Figure 2b. The system with control 3-D

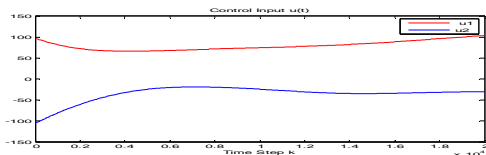


Figure 2c. The control input vector u(t)

For those case 2, the performance is go to stable condition slower than the case 1.

For case 3:

$$C = \begin{bmatrix} 71.4856 & 1 & 0 \\ -137.935 & 0 & 1 \end{bmatrix};$$

$$K = \begin{bmatrix} 1 & -70.9894 & 33.2247 \\ -1 & 3.2247 & 138.4314 \end{bmatrix}$$

The value of C and K are taken from [1]. For this case, Figure 3a. shows the Chua's circuit with control. System (2) converge to zeros, with an oscillation. Case 1 and Case 2 have less oscillation than case 3. The Figure 3b. is a system state in three dimension, and the Figure 3c. shows the control input u(t). This input has a sinusoidal form.

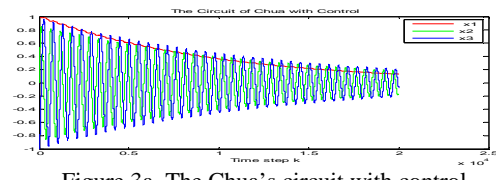


Figure 3a. The Chua's circuit with control

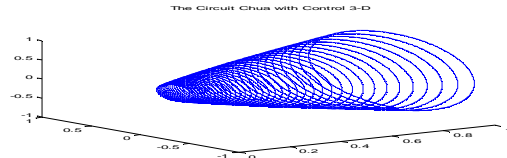


Figure 3b. The Chua's circuit with control in 3-D

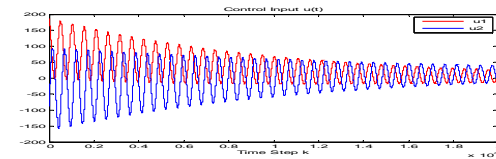


Figure 3c. Control input u(t)

From those simulation, we know that the value of C and K are influenced the stability of system. The control input u(t) also influences the system behavior. If the input control with sinusoidal form, give the behavior system is also has the sinusoidal form. The performance of case 1 is the best of three cases, because the system toward the stability condition with less oscillation.

### 5. Concluding Remark

From those discussion and the simulation, we conclude that:

- The sliding mode control with dynamical compensator can be used as controller design for non linear system the Chua's circuit.
- The value of sliding coefficient C and the dynamic compensator K can be determined by solving the LMI which is derived from the Liapunov stability criteria.
- The values of C and K are influence the speed of the system become stable
- The performance of case 1 is better than the others. Because case 1 has less oscillation, and faster to go stable position.

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