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"Managing Digital Development for Sustainable Economy"

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FOREWORD

We welcome you to the First International Conference on Information Technology Applications and Systems (ICITAS) held February 3, 2018 in Surabaya, East Java, Indonesia. ICITAS 2018 provides a highly competitive forum for global exploration of the latest developments in Information Technology and their direct impact on the economic sustainability. Therefore, we carefully chose and embraced the theme of this conference as "Managing Digital Development for Sustainable Economy".

We are pleased to present the proceedings of the conference as its published record. In overall, the technical committee has selected 40 papers to be published, which comprises authors from various countries and regions. The topics may include, but not limited to the following: Information and Communication Technology, Business and Economics Applications, and Applications of Digital Media Technology in Arts Design.

We want to express our gratitude to the members of the Program Committee and the Technical Committee, as well as the external reviewers for their hard work in reviewing all the submission papers. We also thank the three invited speakers, Prof Nai-Wei Lo (National Taiwan University of Science and Technology), Prof. Kamarul Hawari bin Ghazali (Universiti Malaysia Pahang), and Mr. Kresnayana Yahya, for sharing their insights with us. Finally, the conference would not be possible without the excellent papers contributed by authors. We thank to all the authors for their contributions and their participation in ICITAS 2018! We hope that this program will further stimulate research in Information Technology systems and their applications in the present time and in the future, and provide practitioners with better techniques, algorithms, and tools for deployment.

Dr. Jusak

Head of Committee of the ICITAS 2018

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Keynote Speaker 2

Dr. Nai-Wei Lo got his Ph.D. degree in Electrical Engineering from State University of New York at Stony Brook, USA, in 1998. He worked as research assistant at TNT Information Systems Inc. in 1997 to 1998. From 1998 to 2000, he worked at H&L Technique Inc. as a software consultant for AT& T Business and Global Services. From 2000 to 2002, he worked at Lucent Technologies as member of technical staff.

Dr. Nai-Wei Lo joined the Department of Information Management in National Taiwan University of Science and Technology in 2003, and he has become professor from 2015. In addition, he has been the director of Taiwan Information Security Center, National Taiwan University of Science and Technology (TWISC@NTUST) since 2014. His research interests include smart grid security, IoT/IoV security, web technology, and cloud security.

Keynote Speech Title: Indoor Positioning-based Mobile Payment System Using BLE Technology

Abstract – The development of information technology has paved the way for faster and convenient payment process flows and new methodology of design and implementation for next generation payment system. The usage growth of smartphones in nowadays has fostered a new and popular mobile payment environment. Most of the current generation smartphones support BLE technology to communicate with nearby BLE-enabled devices. It is plausible to construct an Over-the-Air BLE-based mobile payment system as one of the payment methods for people living in modern societies. In order to secure the BLE-based mobile payment system, a secure indoor positioning-based mobile payment authentication protocol and corresponding mobile payment system is designed. The authentication protocol consists of three phases: initialization phase, session key construction phase, and authentication phase. A prototype is implemented to assess the performance of the designed mobile payment system.

Keynote Speaker 3

Krenayana Yahya is a Director of Enciety Business Consult and also aLecturer at Department of Statistics ITS. Not only served as Director of Enciety Business Consult, this Jakarta-born man is also listed as a Commissioner of PT Petrokimia Gresik. In addition he is also a Board of Trustees LEAD Indonesia (one of the program The Foundation of Sustainable Development or Foundation for Sustainable Development of the UK). Not only that, a number of important positions in several organizations such as the Chairman of the Association of Indonesia Manager Surabaya Branch, President of the Association of Indonesian Marketing area of East Java, and various other important positions in the field of statistics, environment, marketing to democracy. Mr. Yahya who holds a master's degree at the University of Wisconsin, USA is known to actively fill interactive dialogue in various mass media such as Suara Surabaya and JTV radio. His writing was often appeared in print media Java Post and Kompas Daily.

Keynote Speech Title : Digital development for sustainable economy

The development issues today is strongly related to the developments of Technology. Technology introduction to a society is mainly a choice and related to the readiness to accept and utilized for the good of the improvement of welfare. Digitalization becomes a mean and a purpose to achieve sustainable development. Educating the young and bridging the digital divide becomes the most important aspect before to decide what and which technology should be implemented in a society, in a public sector and overall for business development. Disruptions will come and replacing, renewing, through innovation and developing application to reduce time, increasing speed and integrating most activities that reduce the impact on the degradation of the earth.

The role of development should define and prioritize the steps toward improving quality of life through managing the digital policy in the stages of development. Consideration the impact and the negative side of the use of IT should be anticipated through policy developments. Technology by itself is neutral, but preparing the infrastructure to used, to be used by whom and for what purposes will the main cause to regulate. The digital divide should be considered as a real concern not to widen the welfare gaps and the increase of economic disparity.

Currently in Indonesia the IT Index of developments showed that Jakarta has the most advanced IT usage, Infrastructure and supported for business, while most villages and outer Island like Papua has very poor access for internet

Indonesian archipelago has its problems in disparity of level support for mostly several infrastructure. Better and more justice in prioritizing is on the way to make it even and more welfare instruments will cover.

On the other hand better access for communication and improving connectivity will improve the chances to integrate IT with most public sectors like transportation, online courses, retail, and public utility access. The future of IT will certainly a great help for human development in general. The improvement of policy development will be a real support for most development instrument. Specifically policy development for digitalization will be most valuable through the better understanding and the right implementation of sustainable development

 ISBN : 978 – 602 -51367 – 0 – 2

TABLE OF CONTENT

A. EDITORIAL BOARD i
B. COMMITTEE iii
C. TOPIC iv
D. FOREWORD vi
E. KEYNOTE SPEAKER vii
F. TABLE OF CONTENT xi

I. INFORMATION AND COMMUNICATION TECHNOLOGY

1. A Fast Fourier Transform-based ECG Security Framework I-1
Jusak, Seedahmed S. Mahmoud
2. Analysis of Quality of Service Routing Protocols AODV and AOMDV on MANET Using NS2 I-6
Alamsyah, Eko Setijadi, I Ketut Eddy Purnama, Mauridhi Hery Purnomo
3. Application Evaluation of Simulation of Agribusiness Concept of Livestock (SPEKTRUM) at SMK Al Jauhar Ngawi, East Java I-11
Marya Mujayana, Endra Rahmawati
4. Building The Network Infrastructure and E-Hospital Using Cloud Computing I-15
Norma Ningsih, Teguh Sutanto, Anjik Sukmaaji
5. Comparison between PID and Fuzzy Controller to Hydroponic Temperature I-21
Yosefine Triwidyastuti, Ira Puspasari, Harianto
6. Comparison of Retina Blood Vessel Segmentation Based On K Means and Fuzzy C Means I-28
Agus Dwi Churniawan
7. Design of SLM IT Services on Academic Services in Higher Education I-32
Erwin Sutomo
8. IbM (Science and Technology for Society): Electronic Game Device Implementation To Train the Memories of Kids in Playing Group I-36
Weny Indah Kusumawati, Pauladie Susanto, Musayyanah
9. Implementation Of Online Sales Information System For Sandals Craftsmen In Berbek Village I-41
A.B. Tjandrarini, Sulistiowati, Julianto Lemantara
10. Implementation Text Mining for Recommendation Follow Up Customer I-46
Vivine Nurcahyawati
11. Iris Detection and Localization Based on Contrast Shrinking and Stretching of CIELab Color I-49
Susijanto T. Rasmana, Pauladie Susanto, Heri Pratikno
12. Lead Time Reduction Through Production Process Analysis Of XYZ E-Commerce Company Using Simulation Model I-54
Fabio Jeremia Sunarjo, Mursyid Hasan Basri

 ISBN : 978 – 602 -51367 – 0 – 2

13. N-TEA (New-Text Encryption Algorithm) For Android Chatting Application Security I-62
Sugiyanto
14. Scheme Of Application Study Of Kanji Characters Japan To Children Base On Android I-67
I Gusti Ngurah Alit Widana Putra, Yoppy Mirza M., Dinastuti Mulia L.
15. Pareto Analysis for Agile Requirements Prioritization I-72
Tan Amelia
16. Sentiment Classification of Microblogging in Indonesia Airline Services using Support Vector Machine I-76
Tien Rahayu Tulili, Muhammad Farman Andrijasa
17. The Analysis Of Service Quality At Academic And Student Affairs Department (Asa Department) Institute Of business And Informatics Stikom Surabaya I-82
Sulistiowati, Henry Bambang Setyawan, Tutut Wurijanto
18. Evaluation of User Experience in Using Web-based Study Planning Application I-87
Tri Sagirani, Puspita Katikasari, Nunuk Wahyuningtyas
19. The Comparation of The Duration of Five Software to Restore The Operating System I-91
Achmad Arrosyidi, Edo Yonatan Koentjoro
20. Twitter Mining to Explore Perceptions of Tourism Objects in Indonesia: A case study of Borobudur and Prambanan Temple I-94
Valentinus Roby Hananto
21. User Evaluation GKJW Waru's Website for Improving Brand Awareness I-98
Siswo Martono, Florens Debora Patricia
22. Utilizing ADDIE Model for Developing Brilian, Learning Application in Institute of Business and Informatics Stikom Surabaya, Indonesia I-105
Bambang Hariadi, M.J. Dewiyani Sunarto, Pantjawati Sudarmaningtyas

II. DIGITAL MEDIA TECHNOLOGY IN ARTS DESIGN

1. Collaboration Between Designers And Marketers In Developing A New Product Development II-1
Yosef Richo Adrianto
2. Content Analysis Television Program Featured on Disability by Title "Dunia Tanpa Batas" (Episode Tiara Handycraft Embracing Persons with Disabilities With Social Entrepreneurs) II-5
Novan Andrianto, Rike Verlita, Fuad Amsyari
3. Design Product Packaging Chocolate Using With Design Element Inside It II-9
Yosef Richo, Ixsora Gupita Cinantya, Ardian Jaya Prasetya

 ISBN : 978 – 602 -51367 – 0 – 2

4. Environmental Graphic Design Of Ecotourism Mangrove Surabaya As Efforts To Provide Information To Visitors II-17
Hardman Budiardjo, Dhika Yuan Yurisma, Darwin R. Yuwono
5. Making A Short Film With The Thriller Genre Using Canted Angle Techniques About Psychopates Titled Hate II-24
Karsam, Nirwana Wahyu, Puspita Prawiswari
6. Multimedia as a Media Development Skill to Improve the Quality of Learning II-31
Ardian Jaya Prasetya
7. Song Arrangement Can You Feel The Love Tonight Using Sibelius On Movie Soundtrack "The Lion King" II-35
Yunanto Tri Laksono

III. BUSINESS AND ECONOMICS APPLICATIONS

1. Analysis the Impact of Management Information System Usage on the Performance of Business Company Using DeLone And McLean Model III-1
Haryanto Tanuwijaya
2. Effect Of Mobile Technology, Information Services, Price, Company's Integrity Of Shopping On Line III-7
Antok Supriyanto
3. Framework Business Model on Private College Using Business Model Canvas: Case Study in Institute of Business and Informatics Stikom Surabaya III-10
Ayouvi Poerna Wardhanie
4. Science And Technology For Communities: Internet Utilization For Brand Rejuvenation Of Al Qur'an Al Falah Institution III-14
Achmad Yanu Alif Fianto, Rudi Santoso, Abdullah Khoirriqoh
5. The Effect Of Big Five Personality On Lectures And Employee's Performance III-19
Sri Suhandiah, Ayuningtyas, Oktaviani
6. The Effect Of Motivation And The Work Environment To Competence And Performance Of Permanent Lecturerat Sekolah Tinggi Teknologi Angkatan Laut Surabaya III-25
Rahayu Arya Shintawati
7. The Influence of Brand Trust, Brand Communication and Brand Satisfaction toward Brand Loyalty for iPhone's Customer in Surabaya, East Java, Indonesia III-32
Achmad Yanu Alif Fianto
8. The Management Of Online-Based Supply Of GoodsAt Pt.Indoberka Investama III-36
Mochammad Arifin, Marya Mujayana
9. Science And Technology For Communities: Martketing Strategic Development and Packaging Design for Kelompok Tani Elok Mekarsari Surabaya III-42
Candraningrat, Yosef Richo Adrianto, Januar Wibowo

 ISBN : 978 – 602 -51367 – 0 – 2

10. Analysis of Public Trust Factors on Online Media of Travel Website III-47
Putri Pradnyawidya Sari
11. Clicking For Physical Security, Can It Be? III-53
Cakti Indra Gunawan, Putriyana Asmarani

 ISBN : 978 – 602 -51367 – 0 – 2

I : INFORMATION AND COMMUNICATION TECHNOLOGY

Comparison between PID and Fuzzy Controller to Hydroponic Temperature

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***Abstract*—Nowadays, there are many researches about automatic controlling system of hydroponic temperature. The two most well-known controller systems are PID Controller and Fuzzy Logic Controller. This study discusses and compares the performance of these two main controller systems to control the room temperature of a wick-based hydroponic system for cherry tomato cultivation. In this comparison system, we use an SHT11 module as the sensor and an air conditioner as the actuator. From the test result, PID controller has 2.2 times longer rise time, whereas Fuzzy controller yields 25.3 times larger overshoot in day time measurement.**

Keywords—temperature controlling, PID controller, fuzzy controller, hydroponic system, cherry tomatoes

I. INTRODUCTION

Recently, plant cultivation in urban area is more difficult because of the rapid development in housing and industries. Then, many plants are grown using hydroponic system because hydroponic system can be cultivated in various media instead of soil, be resistant to plant diseases, be applied in less space like city area, be irrigated with less water and be harvested in shorter term.

Another advantage of the hydroponic system is that it has greater possibilities to be combined with an automatic system easily and efficiently. There are numerous amount of researches dwelt on automatic hydroponic system because maintaining plant cultivation system manually requires extra power [1]-[3]. One of the control methods that are commonly applied is PID controller. PID has simple concept in using the error value to decide the next control value [2]. In addition, Fuzzy controller is also commonly used due to the uncertainty between the control elements [3].

The purpose of this study is to discuss and compare the performance of the two most well-known control methods, which are PID controller and Fuzzy controller. In this study, the two controller methods are implemented alternately in a temperature controlling system for hydroponic cultivation. The performances of their stability are calculated and analyzed to help characterizing the control methods and deciding the suitability of the control methods with the system characteristics, especially in the hydroponic temperature controlling system.

Authors would like to thank to DRPM Ditjen Penguatan Risbang from Ristekdikti Ministry for the funding of "Penelitian Dosen Pemula" in 2017.

II. HYDROPONIC SYSTEM

A. Wick-based Hydroponic System

Hydroponics is a technique to cultivate plan without soil. Because hydroponics is soilless system, the nutrients needed for the plants are obtained from the distribution of nutrient solution regularly from the nutrient tank to the hydroponic container. As the alternative to the growing medium, we can use perlite, rockwool, vermiculite, sand, clays, sawdust and others.

There are many various types of hydroponic system. The six basic types of hydroponic system are Wick, Deep Water Culture (DWC), Ebb and Flow, Drip Irrigation, Nutrient Film Technique (NFT) and aeroponics. Generally, the various types of hydroponic system implemented in the plant cultivation are the combination or modification from these six basic types [1].

The simplest type that is easily used by beginners in hydroponics is wick system, because it applies passive irrigation for the plants. Wick is a hydroponic technique to grow plants by delivering the nutrient solution using wicks made from flannels. The scheme of a wick-based hydroponic system is shown in Fig. 1.

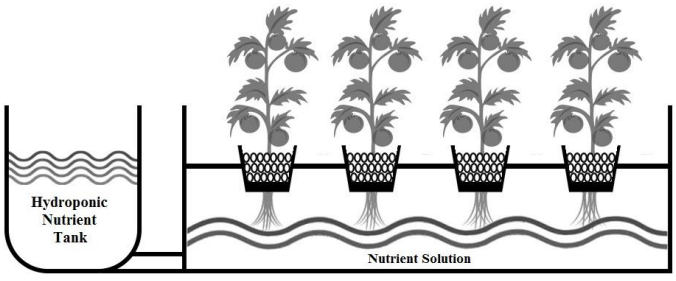


Fig. 1. Wick-based Hydroponic System

Wick system contains a nutrient solution tank connected to the hydroponic container through a pipe. The hydroponic

container in wick system consists of several pots with flannels to absorb the nutrient solution beneath it. Wick system uses the principle of capillarity [4].

The benefit of wick system is the equality in nutrition distribution because all of the pots are in the same hydroponic container. Thus, the plants could get the same amount and quality of the hydroponic nutrient solution. This simplicity and uniformity is the main advantages of the wick system.

B. Hydroponic System for Cherry Tomatoes

Cherry Tomato is a tropical fruit that has high economic value in agriculture. Its price is ranging from 20,000 to 30,000 rupiahs per kilogram [5], so cherry tomato cultivation could be rated as a perspective business in agroindustry.

Generally, cherry tomatoes are cultivated using hydroponic system. It can produce more fruit than traditional culture. Tomato cultivation using traditional method needs intensive maintenance system, while only produces 1.5-2 kilograms per plant. On the other hand, hydroponic system could produce 5.1-5.8 kilograms per plant [6]. This high production rate makes hydroponic system becomes preferable among farmers.

However, there are five sources of risk in cherry tomato production, which are the weather condition, pest infection, plant disease, seed quality and human skills. The highest production risk comes from the bad weather condition with the probability of 44%. This high weather effect could cause a production risk until 9,722,492 rupiahs [7].

Hence, the hydroponic cultivation room of cherry tomatoes should be sophisticated controlled to fulfill the weather requirement of the plants to grow, especially the temperature requirement. The required room condition to cultivate cherry tomatoes should have a temperature of 24^{o}C [8].

III. TEMPERATURE CONTROLLING METHODS

In this study, PID controller and Fuzzy controller are implemented alternately in a temperature controlling system for cherry tomatoes cultivated using hydroponic technique.

A. Hydroponic Temperature Controlling System Design

The temperature controlling system is designed to maintain the room temperature of hydroponic system around the temperature target which is 24^{o}C. In order to achieve good performance, the control system should be able to adjust the actuator precisely based on the control methods, so the temperature value has less error from the target and stable. The block diagram of the temperature controlling system for the hydroponic cultivation is shown in Fig. 2.

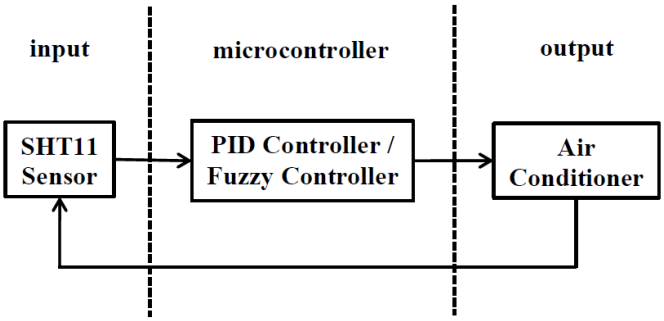
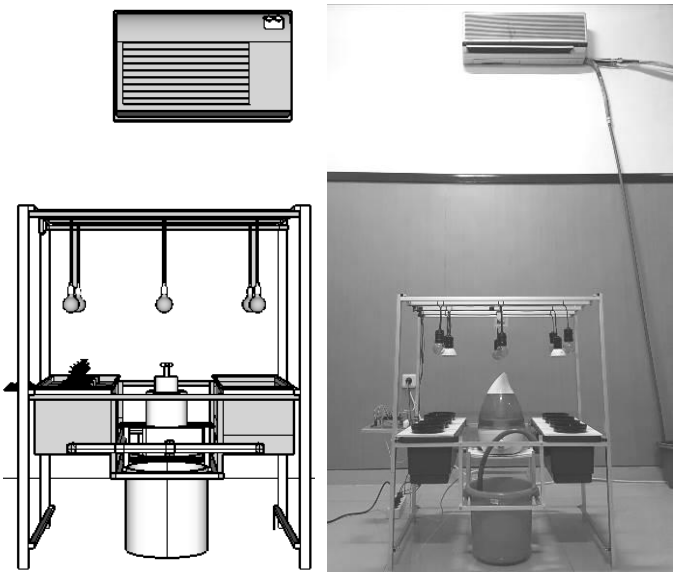


Fig. 2. Block Diagram of the Hydroponic Temperature Controlling System

In Fig. 2, the temperature controlling system contains a DT sense SHT11 sensor as its input, a microcontroller to implement the control methods and a room air conditioner as the output. Every time the control system obtains an input data, it should calculate the controlling adjustment as its output. The output value from the control methods is used to set the controlling actuator via infrared communication and turn the temperature recent value into the target value. Then, the next temperature value is measured and inserted again as the input of the control process.

The system mechanic design of the temperature controlling system for the hydroponic system is shown in Fig. 3. The prototype has size of 72 x 55 x 90 cm^3. It comprises of eight pots, rockwool, plants, water bucket, hydroponic container, grow lights, fluorescent lights, SHT11 sensor, infrared, air conditioner, humidifier and a control panel.



(a) (b)

Fig. 3. System Mechanic Design; (a) 3-D Design (b) Implemented System Mechanic

The sensor used in this control system is DT-sense SHT11 module that is shown in Fig 4. This sensor can measure the value of air temperature and relative humidity. The temperature range is from -40^{o}C to +123.8^{o}C, while the humidity range is from 0% RH to 100% RH [9].

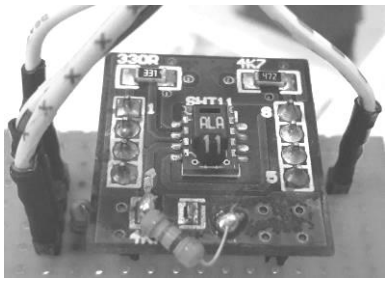


Fig. 4. DT-sense SHT11 Module

The system electronic design to control the hydroponic temperature is shown in Fig. 5 and the pin configuration connected to the microcontroller is shown in Table 1. The data input of the control system is obtained from SHT11 sensor via I2C pin, whereas the output of the control system would be the temperature value addressed to set the air conditioner through the infrared communication.

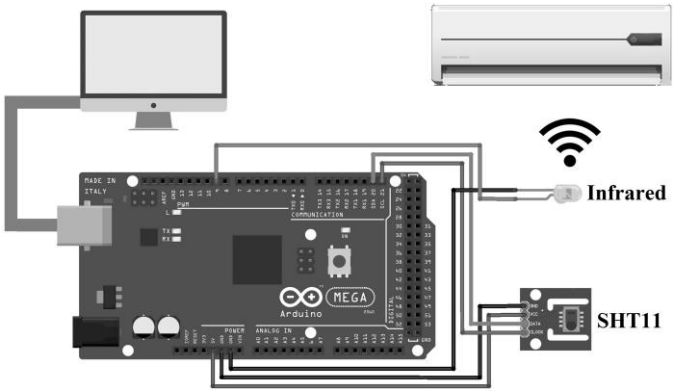


Fig. 5. Electronic Design of the Temperature Controlling System

TABLE 1. PIN CONFIGURATION IN MICROCONTROLLER

Microcontroller Pin Number	Connection
20	SHT11 Data Output (Pin 1)
21	SHT11 Clock (Pin 3)
9	Infrared Data Input

B. PID Controller

The PID controller consists of proportional, integral, and derivative components to calculate the controlling adjustment. The scheme of the PID controller can be seen in Fig. 6. The attribute of the PID controller is the feedback process to address the evolution characteristics of the error signal $e(t)$ throughout the control process.

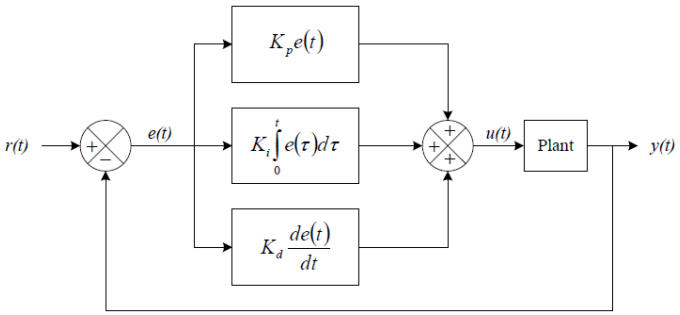


Fig. 6. PID Controller Scheme

In Fig. 6, $r(t)$ is the set point value that would like to be achieved. The parameters that should be set in PID controller are the K_p (proportional constant), K_i (integral constant) and K_d (derivative constant) parameters.

Proportional output is the result of multiplication between the proportional constant K_p and the current error value. If the value of K_p is too small, proportional control is only capable of making minor error correction, so it will produce slow system response. If the value of K_p is too large, the control system could oscillates around the set point.

In Integral control, the system response increases the error value continuously until the limit of the integral part. Integral controls have the characteristics of reducing rise time, adding overshoot and eliminating steady state error.

Derivative control affects the amount of control signal generated in proportional to the error change. The faster the error changes, the greater the control signal generated. The differential control output has properties as well as a derivative operation. Sudden changes in the controller input will result in enormous changes. In the transition period, the derivative control causes a damping in the system to further reduce the spike.

The three components of the PID controller would form the control signal $u(t)$ as described in (1).

$$u(t) = K_p e(t) + K_i \int_0^t e(\tau)d\tau + K_d \frac{de(t)}{dt} \quad \text{K (1)}$$

In the temperature controlling system, the control signal denotes the temperature adjustment value that is sent to the air conditioner to stabilize the current room temperature around the required hydroponic temperature. The error signal is the difference between the current temperature value measured from the sensor and the target temperature value required in the cherry tomato cultivation.

In order to be applicable in the microcontroller system, the formation of the control signal and the processing of the proportional, integral and derivative parts should be transformed into discrete form as in (2).

$$u(t_k) = K_p e(t_k) + K_i \Delta t \sum_{i=1}^{k} e(t_i) + \frac{K_d}{\Delta t}\left(e(t_k) - e(t_{k-1})\right) \quad \text{K (2)}$$

C. Fuzzy Logic Controller

Fuzzy logic is a technique to map the input values to the output value based on its degree of membership. In order to be optimum, a fuzzy controller should contain minimum two inputs. Thus, the second input from the DT-sense SHT11 module is used in the control system.

The membership function of the first input which is the temperature value (x) is shown in Fig. 7. It is divided into five levels, which are "Cold", "Cool", "Normal", "Warm" and "Hot". The required temperature which is 24°C for cherry tomato cultivation is put in the center point in the level of "Normal".

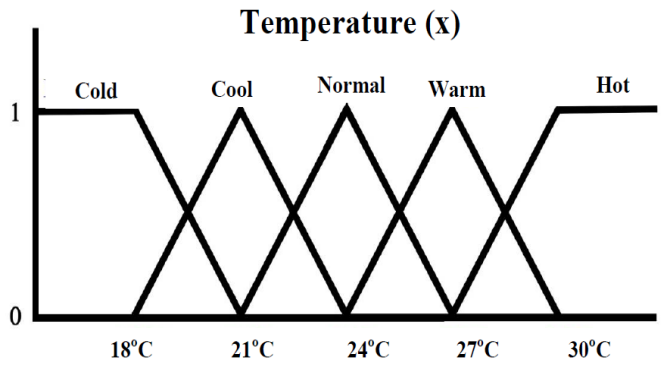


Fig. 7. Membership Function of the Temperature Variable

The membership function of the humidity parameter (y) is shown in Fig. 8. It is divided into three levels, which are "Low", "Normal" and "High". The normal humidity for the growth of cherry tomatoes is 80%.

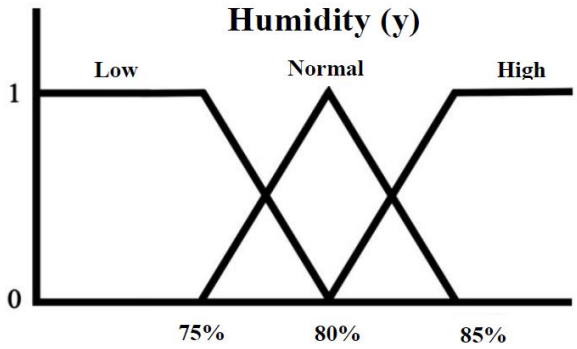


Fig. 8. Membership Function of the Humidity Variable

In the fuzzification process, each input value should be mapped into its membership degree (μ) in all levels based on the membership function. Then in the inference process, we apply the fuzzy rules described in Table 2. Because there are five levels in the first input and three levels in the second input, so there are 15 rules to map the input values into the output [3].

TABLE 2. FUZZY RULES

Hmd.[a] / Temp.[b]	Low	Normal	High
Cold	Cool[1]	Cool[2]	Normal[3]
Cool	Cool[4]	Cool[5]	Normal[6]
Normal	Cool[7]	Normal[8]	Normal[9]
Warm	Cold[10]	Cold[11]	Cool[12]
Hot	Cold[13]	Cold[14]	Cold[15]

[a.] Hmd = Humidity
[b.] Temp = Temperature

In the inference process, we use the minimum inference function. We produce the fire strength (α) of each rule by choosing the minimum value of the membership degrees (μ) from the two inputs based on Table 2. For example, the 10th fuzzy rule states that if the temperature is "Warm" and the humidity is "Low" then the adjustment of the air conditioner would be "Cold" can be described as in (3).

$$\alpha_{10} = \min(\mu_{Warm}, \mu_{Low}) \quad \text{K (3)}$$

Next, we calculate the output value (z) for all of the 15 fire strengths (α) based on the membership function of the air conditioner temperature adjustment shown in Fig. 9. The output membership function is divided into 3 levels, which are "Cold", "Cool" and "Normal". We use maximum composition rule to obtain a single value of z.

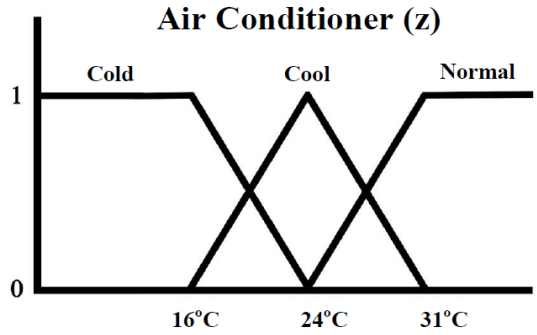


Fig. 9. Membership Function of the Air Conditioner Variable

In the defuzzification process, we use Tsukamoto method. The output value (z) is obtained using weighted average calculation as described in (4).

$$z = \frac{z_1\alpha_1 + z_2\alpha_2 + \Lambda + z_{15}\alpha_{15}}{\alpha_1 + \alpha_2 + \Lambda + \alpha_{15}} \quad \text{K (4)}$$

Then, this output value (z) is sent to the air conditioner to stabilize the current room temperature of the hydroponic system.

IV. Results and Discussion

A. Temperature Controlling Actuator

Fig. 10 shows the result of temperature controlling actuator when it is given a threshold of 24°C without using any control method. The purpose of this experiment is to find the characteristics of the actuator which is the room air conditioner solely.

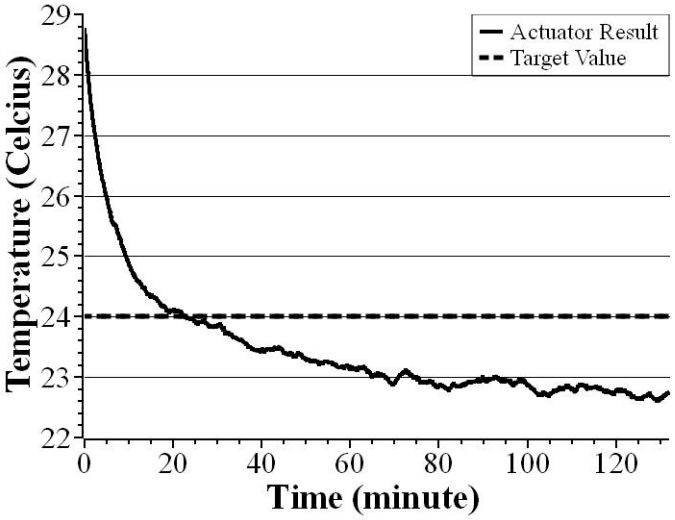


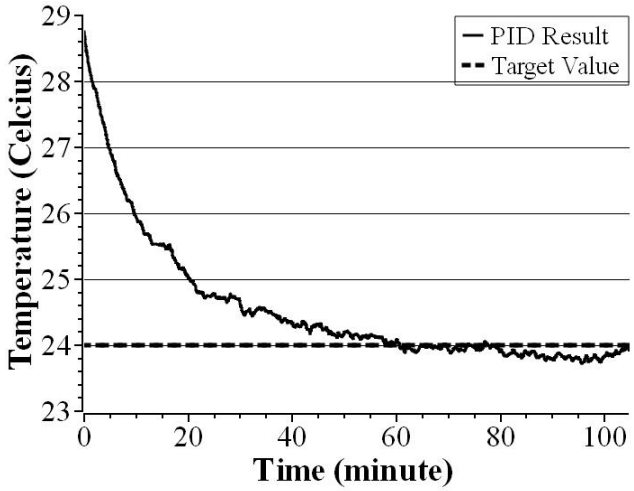
Fig. 10. The Result of the Temperature Controlling Actuator

As we can see in Fig. 10, the actuator of air conditioner could not maintain the temperature target. It cools the room without noticing the current value. The error gets bigger until 1.4ºC. If this condition is stayed for a long time, the room temperature will not suit the growth requirement for the plants. Thus, the need of a control method implementation is important in hydroponic system.

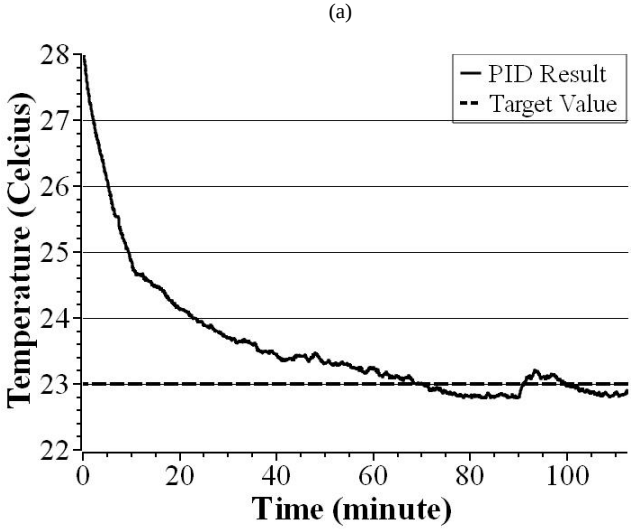
B. PID Parameter Setting

One of the control methods that are commonly used in a controlling system is PID. As the PID controller is the combination of proportional, integral and derivative process, the parameters related with these three components should be set first. Generally, the parameters are set with trial and error process.

In this study, we set K_p, K_i and K_d as 3, 2 and 10 respectively [2]. We tried these parameter settings into the hydroponic temperature controlling system. Fig. 11 shows the results of temperature controlling using the PID's parameter setting with different temperature target.



(a)



(b)

Fig. 11. PID Controlling Result; (a) Temperature Target 24ºC; (b) Temperature Target 23ºC

In Fig. 11a with the parameter setting of 3, 2 and 10, PID controller can maintain the temperature becomes stable at 24ºC. The error is only 0.28ºC or 1.16%. Furthermore, in Fig. 11b PID also results a stable temperature around the target which is 23ºC. The error is 0.23ºC or only 1%.

Hence, with the low error level, the PID parameter setting of 3, 2 and 10 is suitable for the hydroponic temperature controlling system. The high value of the derivative constant (K_d) could tackle the slow change in the temperature value and avoid a large overshoot to occur.

C. Comparison Result in Day Time

The final experiment in this study is to implement the PID controller and Fuzzy controller alternately in order to compare their characteristics in a hydroponic temperature controlling system. Fig. 12 shows the result of temperature controlling using PID and Fuzzy in day time, whereas Table 3 shows their characteristics in producing rise time, overshoot and settling time.

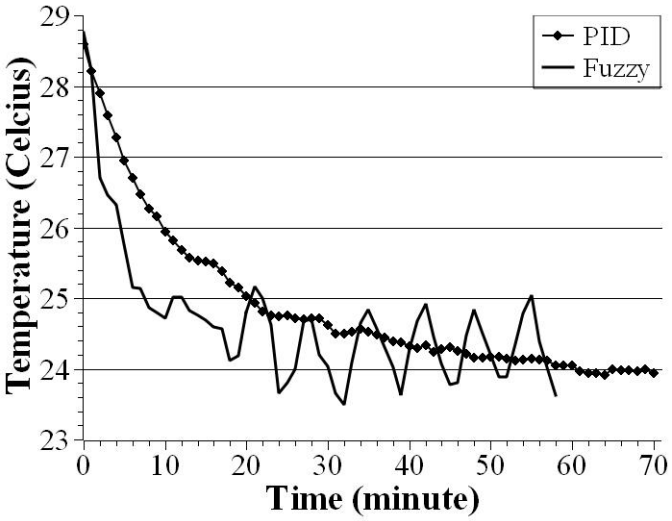


Fig. 12. PID and Fuzzy Performance in Day Time

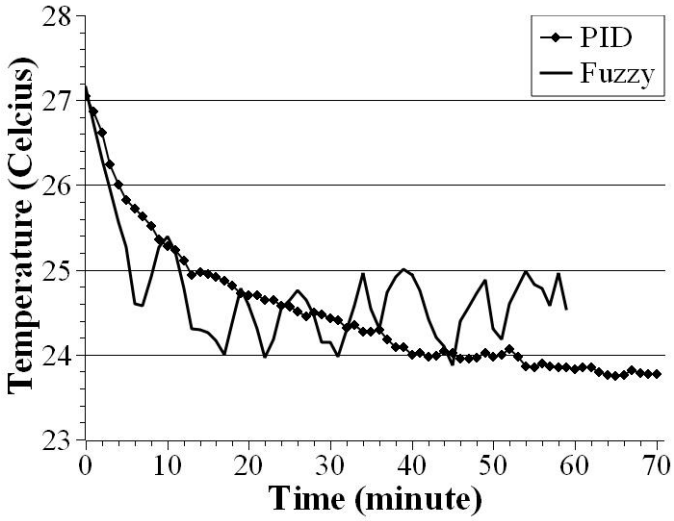


Fig. 13. PID and Fuzzy Performance in Night Time

TABLE III. PID and Fuzzy Performance in Day Time

Controller	Rise Time	Overshoot	Settling Time
PID	35 minutes	0.87 %	18 minutes
Fuzzy	16 minutes	22 %	22 minutes

Based on Fig. 12 and Table 3, PID controller has longer rise time, smaller overshoot and shorter settling time. On the other hand, Fuzzy controller yields shorter rise time, larger overshoot and longer settling time. Other difference between PID and Fuzzy controller is that Fuzzy controller produces more oscillations to reach the target, because the output decision in Fuzzy controller depends on the classification in the membership function and the complexity of the rules. However, PID controller could produce smoother result because PID controller contains derivative component to help reducing the oscillation.

D. Comparison Result in Night Time

Fig. 13 shows the result of temperature controlling using PID and Fuzzy in night time, meanwhile Table 4 shows their characteristics of rise time, overshoot and settling time.

TABLE IV. PID and Fuzzy Performance in Night Time

Controller	Rise Time	Overshoot	Settling Time
PID	35 minutes	5.6 %	11 minutes
Fuzzy	12 minutes	32 %	12 minutes

As in day time, in night time PID controller still has longer rise time, smaller overshoot and more stability. The high derivative constant helps the controller to be smoother. On the other hand, in night time Fuzzy controller also results shorter rise time, larger overshoot and more oscillations. The oscillation results in Fuzzy are related with the classification in the membership function and fuzzy rules during the defuzzification process.

E. Comparison Ratio

The last comparison result is the performance ratio between PID and Fuzzy controller both in day time and night time. Table 5 shows the ratio of the performance of PID and Fuzzy controller during the same time duration which is 60 minutes.

Table 3. Comparison Ratio of PID and Fuzzy Controller

Measurement Time	Ratio of PID to Fuzzy		
	Rise Time	Overshoot	Settling Time
Day Time	2.2 : 1	1 : 25.3	1 : 1.2
Night Time	2.9 : 1	1 : 5.7	1 : 1.1

Based on Table 5, we can see the characteristics of each method. Fuzzy controller has better rise time which is 2.2 times faster but yields larger overshoot that is 25.3 times higher. However, PID controller is more stable but needs longer rise time. The highest overshoot difference between PID and Fuzzy controller happens in day time due to the high value of the initial temperature in day time which is 28.75ºC. Whilst, the

initial temperature in night time is 27.15ºC while both time has the same target temperature value that is 24ºC.

Regarding the slow changes in the temperature of hydroponic room, PID controller is found to be more reliable in the hydroponic temperature controlling system. Fuzzy controller could be better to be implemented in a system that needs shorter rise time but can compromise on the overshoot. Meanwhile, PID controller would be viably applied in a system that needs good stability but can compromise its long rise time.

V. CONCLUSION

There are many methods that could be implemented to make an automatic controlling system for hydroponic room temperature. From the comparison result between PID and Fuzzy controller, PID controller has 2.2 times longer rise time, whereas the Fuzzy controller produces 25.3 times larger overshoot in day time measurement. PID controller is found to be more reliable in maintaining a good stability in the hydroponic temperature controlling system.

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Comparison between PID and Fuzzy Controller to Hydroponic Temperature

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Abstract—Nowadays, there are many researches about automatic controlling system of hydroponic temperature. The two most well-known controller systems are PID Controller and Fuzzy Logic Controller. This study discusses and compares the performance of these two main controller systems to control the room temperature of a wick-based hydroponic system for cherry tomato cultivation. In this comparison system, we use an SHT11 module as the sensor and an air conditioner as the actuator. From the test result, PID controller has 2.2 times longer rise time, whereas Fuzzy controller yields 25.3 times larger overshoot in day time measurement.

Keywords—temperature controlling, PID controller, fuzzy controller, hydroponic system, cherry tomatoes

I. Introduction

Recently, plant cultivation in urban area is more difficult because of the rapid development in housing and industries. Then, many plants are grown using hydroponic system because hydroponic system can be cultivated in various media instead of soil, be resistant to plant diseases, be applied in less space like city area, be irrigated with less water and be harvested in shorter term.

Another advantage of the hydroponic system is that it has greater possibilities to be combined with an automatic system easily and efficiently. There are numerous amount of researches dwelt on automatic hydroponic system because maintaining plant cultivation system manually requires extra power [1]-[3]. One of the control methods that are commonly applied is PID controller. PID has simple concept in using the error value to decide the next control value [2]. In addition, Fuzzy controller is also commonly used due to the uncertainty between the control elements [3].

The purpose of this study is to discuss and compare the performance of the two most well-known control methods, which are PID controller and Fuzzy controller. In this study, the two controller methods are implemented alternately in a temperature controlling system for hydroponic cultivation. The performances of their stability are calculated and analyzed to help characterizing the control methods and deciding the suitability of the control methods with the system characteristics, especially in the hydroponic temperature controlling system.

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II. Hydroponic System

A. Wick-based Hydroponic System

Hydroponics is a technique to cultivate plan without soil. Because hydroponics is soilless system, the nutrients needed for the plants are obtained from the distribution of nutrient solution regularly from the nutrient tank to the hydroponic container. As the alternative to the growing medium, we can use perlite, rockwool, vermiculite, sand, clays, sawdust and others.

There are many various types of hydroponic system. The six basic types of hydroponic system are Wick, Deep Water Culture (DWC), Ebb and Flow, Drip Irrigation, Nutrient Film Technique (NFT) and aeroponics. Generally, the various types of hydroponic system implemented in the plant cultivation are the combination or modification from these six basic types [1].

The simplest type that is easily used by beginners in hydroponics is wick system, because it applies passive irrigation for the plants. Wick is a hydroponic technique to grow plants by delivering the nutrient solution using wicks made from flannels. The scheme of a wick-based hydroponic system is shown in Fig. 1.

Fig. 1. Wick-based Hydroponic System

Wick system contains a nutrient solution tank connected to the hydroponic container through a pipe. The hydroponic container in wick system consists of several pots with flannels to absorb the nutrient solution beneath it. Wick system uses the principle of capillarity [4].

The benefit of wick system is the equality in nutrition distribution because all of the pots are in the same hydroponic container. Thus, the plants could get the same amount and quality of the hydroponic nutrient solution. This simplicity and uniformity is the main advantages of the wick system.

B. Hydroponic System for Cherry Tomatoes

Cherry Tomato is a tropical fruit that has high economic value in agriculture. Its price is ranging from 20,000 to 30,000 rupiahs per kilogram [5], so cherry tomato cultivation could be rated as a perspective business in agroindustry.

Generally, cherry tomatoes are cultivated using hydroponic system. It can produce more fruit than traditional culture. Tomato cultivation using traditional method needs intensive maintenance system, while only produces 1.5-2 kilograms per plant. On the other hand, hydroponic system could produce 5.1-5.8 kilograms per plant [6]. This high production rate makes hydroponic system becomes preferable among farmers.

However, there are five sources of risk in cherry tomato production, which are the weather condition, pest infection, plant disease, seed quality and human skills. The highest production risk comes from the bad weather condition with the probability of 44%. This high weather effect could cause a production risk until 9,722,492 rupiahs [7].

Hence, the hydroponic cultivation room of cherry tomatoes should be sophisticated controlled to fulfill the weather requirement of the plants to grow, especially the temperature requirement. The required room condition to cultivate cherry tomatoes should have a temperature of 24°C [8].

III. Temperature Controlling Methods

In this study, PID controller and Fuzzy controller are implemented alternately in a temperature controlling system for cherry tomatoes cultivated using hydroponic technique.

A. Hydroponic Temperature Controlling System Design

The temperature controlling system is designed to maintain the room temperature of hydroponic system around the temperature target which is 24°C. In order to achieve good performance, the control system should be able to adjust the actuator precisely based on the control methods, so the temperature value has less error from the target and stable. The block diagram of the temperature controlling system for the hydroponic cultivation is shown in Fig. 2.

Fig. 2. Block Diagram of the Hydroponic Temperature Controlling System

In Fig. 2, the temperature controlling system contains a DT sense SHT11 sensor as its input, a microcontroller to implement the control methods and a room air conditioner as the output. Every time the control system obtains an input data, it should calculate the controlling adjustment as its output. The output value from the control methods is used to set the controlling actuator via infrared communication and turn the temperature recent value into the target value. Then, the next temperature value is measured and inserted again as the input of the control process.

The system mechanic design of the temperature controlling system for the hydroponic system is shown in Fig. 3. The prototype has size of 72 x 55 x 90 cm^3. It comprises of eight pots, rockwool, plants, water bucket, hydroponic container, grow lights, fluorescent lights, SHT11 sensor, infrared, air conditioner, humidifier and a control panel.

(a) (b)

Fig. 3. System Mechanic Design; (a) 3-D Design (b) Implemented System Mechanic

The sensor used in this control system is DT-sense SHT11 module that is shown in Fig 4. This sensor can measure the value of air temperature and relative humidity. The temperature range is from -40°C to +123.8°C, while the humidity range is from 0% RH to 100% RH [9].

Fig. 4. DT-sense SHT11 Module

The system electronic design to control the hydroponic temperature is shown in Fig. 5 and the pin configuration connected to the microcontroller is shown in Table 1. The data

input of the control system is obtained from SHT11 sensor via I2C pin, whereas the output of the control system would be the temperature value addressed to set the air conditioner through the infrared communication.

Fig. 5. Electronic Design of the Temperature Controlling System

Table 1. Pin Configuration in Microcontroller

Microcontroller Pin Number	Connection
20	SHT11 Data Output (Pin 1)
21	SHT11 Clock (Pin 3)
9	Infrared Data Input

B. PID Controller

The PID controller consists of proportional, integral, and derivative components to calculate the controlling adjustment.[1] The scheme of the PID controller can be seen in Fig. 6. The attribute of the PID controller is the feedback process to address the evolution characteristics of the error signal e(t) throughout the control process.

Fig. 6. PID Controller Scheme

In Fig. 6, r(t) is the set point value that would like to be achieved. The parameters that should be set in PID controller are the K_p (proportional constant), K_i (integral constant) and K_d (derivative constant) parameters.

Proportional output is the result of multiplication between the proportional constant K_p and the current error value. If the value of K_p is too small, proportional control is only capable of making minor error correction, so it will produce slow system response. If the value of K_p is too large, the control system could oscillates around the set point.

In Integral control, the system response increases the error value continuously until the limit of the integral part. Integral controls have the characteristics of reducing rise time, adding overshoot and eliminating steady state error.

Derivative control affects the amount of control signal generated in proportional to the error change. The faster the error changes, the greater the control signal generated. The differential control output has properties as well as a derivative operation. Sudden changes in the controller input will result in enormous changes. In the transition period, the derivative control causes a damping in the system to further reduce the spike.

The three components of the PID controller would form the control signal u(t) as described in (1).[0]

(1)

In the temperature controlling system, the control signal denotes the temperature adjustment value that is sent to the air conditioner to stabilize the current room temperature around the required hydroponic temperature. The error signal is the difference between the current temperature value measured from the sensor and the target temperature value required in the cherry tomato cultivation.

In order to be applicable in the microcontroller system, the formation of the control signal and the processing of the proportional, integral and derivative parts should be transformed into discrete form as in (2).

(2)

C. Fuzzy Logic Controller

Fuzzy logic is a technique to map the input values to the output value based on its degree of membership. In order to be optimum, a fuzzy controller should contain minimum two inputs. Thus, the second input from the DT-sense SHT11 module is used in the control system.

The membership function of the first input which is the temperature value (x) is shown in Fig. 7. It is divided into five levels, which are “Cold”, “Cool”, “Normal”, “Warm” and “Hot”. The required temperature which is 24°C for cherry tomato cultivation is put in the center point in the level of “Normal”.

Fig. 7. Membership Function of the Temperature Variable

The membership function of the humidity parameter (y) is shown in Fig. 8. It is divided into three levels, which are “Low”, “Normal” and “High”. The normal humidity for the growth of cherry tomatoes is 80%.

Fig. 8. Membership Function of the Humidity Variable

In the fuzzification process, each input value should be mapped into its membership degree (μ) in all levels based on the membership function. Then in the inference process, we apply the fuzzy rules described in Table 2. Because there are five levels in the first input and three levels in the second input, so there are 15 rules to map the input values into the output [3].

Table 2. Fuzzy Rules

Temp.[b] \ Hmd.[a]	Low	Normal	High
Cold	Cool[1]	Cool[2]	Normal[3]
Cool	Cool[4]	Cool[5]	Normal[6]
Normal	Cool[7]	Normal[8]	Normal[9]
Warm	Cold[10]	Cold[11]	Cool[12]
Hot	Cold[13]	Cold[14]	Cold[15]

[a] Hmd = Humidity
[b] Temp = Temperature

In the inference process, we use the minimum inference function. We produce the fire strength (α) of each rule by choosing the minimum value of the membership degrees (μ) from the two inputs based on Table 2. For example, the 10th fuzzy rule states that if the temperature is “Warm” and the humidity is “Low” then the adjustment of the air conditioner would be “Cold” can be described as in (3).

(3)

Next, we calculate the output value (z) for all of the 15 fire strengths (α) based on the membership function of the air conditioner temperature adjustment shown in Fig. 9. The output membership function is divided into 3 levels, which are “Cold”, “Cool” and “Normal”. We use maximum composition rule to obtain a single value of z.

Fig. 9. Membership Function of the Air Conditioner Variable

In the defuzzification process, we use Tsukamoto method. The output value (z) is obtained using weighted average calculation as described in (4).

(4)

Then, this output value (z) is sent to the air conditioner to stabilize the current room temperature of the hydroponic system.

IV. Results and Discussion

A. Temperature Controlling Actuator

Fig. 10 shows the result of temperature controlling actuator when it is given a threshold of 24°C without using any control method. The purpose of this experiment is to find the characteristics of the actuator which is the room air conditioner solely.

Fig. 10. The Result of the Temperature Controlling Actuator

As we can see in Fig. 10, the actuator of air conditioner could not maintain the temperature target. It cools the room without noticing the current value. The error gets bigger until 1.4°C. If this condition is stayed for a long time, the room temperature will not suit the growth requirement for the plants. Thus, the need of a control method implementation is important in hydroponic system.

B. PID Parameter Setting

One of the control methods that are commonly used in a controlling system is PID. As the PID controller is the combination of proportional, integral and derivative process, the parameters related with these three components should be set first. Generally, the parameters are set with trial and error process.

In this study, we set K_p, K_i and K_d as 3, 2 and 10 respectively [2]. We tried these parameter settings into the hydroponic temperature controlling system. Fig. 11 shows the results of temperature controlling using the PID's parameter setting with different temperature target.

(a)

(b)

Fig. 11. PID Controlling Result; (a) Temperature Target 24°C; (b) Temperature Target 23°C

In Fig. 11a with the parameter setting of 3, 2 and 10, PID controller can maintain the temperature becomes stable at 24°C. The error is only 0.28°C or 1.16%. Furthermore, in Fig. 11b PID also results a stable temperature around the target which is 23°C. The error is 0.23°C or only 1%.

Hence, with the low error level, the PID parameter setting of 3, 2 and 10 is suitable for the hydroponic temperature controlling system. The high value of the derivative constant (K_d) could tackle the slow change in the temperature value and avoid a large overshoot to occur.

C. Comparison Result in Day Time

The final experiment in this study is to implement the PID controller and Fuzzy controller alternately in order to compare their characteristics in a hydroponic temperature controlling system. Fig. 12 shows the result of temperature controlling using PID and Fuzzy in day time, whereas Table 3 shows their characteristics in producing rise time, overshoot and settling time.

Fig. 12. PID and Fuzzy Performance in Day Time

Table 3. PID and Fuzzy Performance in Day Time

Controller	Rise Time	Overshoot	Settling Time
PID	35 minutes	0.87 %	18 minutes
Fuzzy	16 minutes	22 %	22 minutes

Based on Fig. 12 and Table 3, PID controller has longer rise time, smaller overshoot and shorter settling time. On the other hand, Fuzzy controller yields shorter rise time, larger overshoot and longer settling time. Other difference between PID and Fuzzy controller is that Fuzzy controller produces more oscillations to reach the target, because the output decision in Fuzzy controller depends on the classification in the membership function and the complexity of the rules. However, PID controller could produce smoother result because PID controller contains derivative component to help reducing the oscillation.

D. Comparison Result in Night Time

Fig. 13 shows the result of temperature controlling using PID and Fuzzy in night time, meanwhile Table 4 shows their characteristics of rise time, overshoot and settling time.

Fig. 13. PID and Fuzzy Performance in Night Time

Table 4. PID and Fuzzy Performance in Night Time

Controller	Rise Time	Overshoot	Settling Time
PID	35 minutes	5.6 %	11 minutes
Fuzzy	12 minutes	32 %	12 minutes

As in day time, in night time PID controller still has longer rise time, smaller overshoot and more stability. The high derivative constant helps the controller to be smoother. On the other hand, in night time Fuzzy controller also results shorter rise time, larger overshoot and more oscillations. The oscillation results in Fuzzy are related with the classification in the membership function and fuzzy rules during the defuzzification process.

E. Comparison Ratio

The last comparison result is the performance ratio between PID and Fuzzy controller both in day time and night time. Table 5 shows the ratio of the performance of PID and Fuzzy controller during the same time duration which is 60 minutes.

Table 5. Comparison Ratio of PID and Fuzzy Controller

Measurement Time	Ratio of PID to Fuzzy		
	Rise Time	Overshoot	Settling Time
Day Time	2.2 : 1	1 : 25.3	1 : 1.2
Night Time	2.9 : 1	1 : 5.7	1 : 1.1

Based on Table 5, we can see the characteristics of each method. Fuzzy controller has better rise time which is 2.2 times faster but yields larger overshoot that is 25.3 times higher. However, PID controller is more stable but needs longer rise time. The highest overshoot difference between PID and Fuzzy controller happens in day time due to the high value of the initial temperature in day time which is 28.75°C. Whilst, the initial temperature in night time is 27.15°C while both time has the same target temperature value that is 24°C.

Regarding the slow changes in the temperature of hydroponic room, PID controller is found to be more reliable in the hydroponic temperature controlling system. Fuzzy controller could be better to be implemented in a system that needs shorter rise time but can compromise on the overshoot. Meanwhile, PID controller would be viably applied in a system that needs good stability but can compromise its long rise time.

V. Conclusion

There are many methods that could be implemented to make an automatic controlling system for hydroponic room temperature. From the comparison result between PID and Fuzzy controller, PID controller has 2.2 times longer rise time, whereas the Fuzzy controller produces 25.3 times larger overshoot in day time measurement. PID controller is found to be more reliable in maintaining a good stability in the hydroponic temperature controlling system.

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