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2024

**The Collaboration of
Smart Technology and
Good Governance
for Sustainable
Development Goals**

ICSINTESA

2024 4th International Conference of Science and Information Technology in Smart Administration (ICSINTESA)

Balikpapan - Indonesia
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Preface

The world is experiencing rapid technological advances and dynamic social changes; technopreneurs operating in the digital era must balance it with innovation and transformation. Technopreneurship combines elements of technology and entrepreneurship, facing new challenges and opportunities that require creative thinking and rapid adaptation. In the context of today's global world, technopreneurship refers to the activity of creating and managing a business based on technological innovation, with a particular focus on the use of the latest tools and methods, including artificial intelligence (AI) to the Internet of Things (IoT), technology provides tools for technopreneurs to create innovative and relevant solutions. AI includes a variety of technologies that enable machines to learn, analyze data, and make decisions automatically. Adopting agile methodologies allows technopreneurs to experiment quickly and respond to customer feedback. It not only increases competitiveness but also facilitates sustainable innovation. Technopreneurs play a crucial role in addressing environmental and social issues and must integrate sustainable practices into their business models. It includes developing environmentally friendly products, reducing waste, and implementing ethical production methods. AI enables technopreneurs to build more innovative and more responsive products and services. Businesses focusing on sustainability meet consumer expectations and strengthen their position as market leaders. By leveraging AI, technopreneurs can reduce operational costs and increase productivity. Previously time-consuming and resource-intensive processes can now be done faster and more accurately. Data is now considered a valuable asset in the business world. With greater access to big data, technopreneurs can use data analytics to identify trends, optimize operations, and understand customer preferences. This data-driven approach increases efficiency and enables more informed and strategic decision-making.

The International Conference of Science and Information Technology in Smart Administration (ICSINTESA) is an annual scientific meeting agenda that creates a space for experts to exchange knowledge and ideas. In this forum, participants can discuss the latest research, technology trends, and challenges faced in the industry. Scientific meetings provide a platform for professionals to stay updated with the latest information on research and technological developments, which is crucial for staying relevant in their fields. These meetings often catalyze innovation by discussing new ideas and the latest technologies, and active involvement in them is essential for individuals and organizations who want to stay at the forefront of technology. By participating in scientific meetings, professionals can gain insights, network with peers, and contribute to advancing their fields. Hopefully, this conference will significantly drive progress and innovation in various fields.

Editor in Chief

Ferry Wahyu Wibowo

Welcome

Welcome Statement
Chair of Conference

Assalamu'alaikum Warahmatullahi Wabarakatuh

Greetings to all,

Distinguished presenters and conference participants, esteemed guests, dedicated reviewers, and cherished attendees. I am immensely proud and grateful to welcome you all to this esteemed event. This year's conference has seen a significant increase in the number of paper submissions, with a total of 444 papers received from over 30 countries. Out of these, 137 papers have been meticulously selected through a rigorous review process conducted by our dedicated reviewers. Each paper was reviewed by three experts, reflecting our commitment to maintaining high scientific quality and integrity. ICSINTESA 2024 marks the fourth iteration of this international conference, and we are proud to announce that the selected papers will be published in IEEE Xplore. The increased quality and quantity of accepted papers this year demonstrate the enthusiasm and trust of the academic community in this conference.

We aspire for Universitas Mulia to consistently uphold and enhance the quality of this seminar, establishing it as a benchmark for scientific conferences both in Indonesia and globally. I would like to extend my heartfelt thanks to all the organizers, reviewers, and participants who have contributed to this event. May we all gain valuable insights and inspiration from this conference, driving forward the advancement of knowledge and technology. With that, I wish you all an enriching and successful conference.

Wassalamu'alaikum Warahmatullahi Wabarakatuh

Warm Regard

Richki Hardi

Chair of Universitas Mulia Conference

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Dr. Ferry Wahyu Wibowo, S.Si., M.Cs. (Editor in Chief)

Author	Session	Start page	Title
A			
Abd, Yaqeen	OL2.05.2	593	<i>Enhancing Reliability in Wireless Sensor Networks through Cluster-based Optimization</i>
Abd Ali, Haneen	OL1.02.6	72	<i>Extracting Gender Textual Nuances Using Text Similarity for Gender Classification Improvement</i>
Abdiwijaya, Edwin	OL1.06.2	259	<i>Polkadot Cryptocurrency Close Price Prediction Using Machine Learning</i>
Abubaker, Ibrahim	OL2.04.1	546	<i>Multi-Channel Fusion Model for Data Logs Analysis and Anomaly Detection in Data Centers</i>
Abumihsan, Ahmad	OL2.03.1	505	<i>Solar Power Generation Forecasting Based on Machine Learning Techniques</i>
	OL2.03.2	511	<i>Detection of DDoS Attack on Software-Defined Networking Controller Using Convolutional Neural Networks</i>
Abumohsen, Mobarak	OL2.03.1	505	<i>Solar Power Generation Forecasting Based on Machine Learning Techniques</i>
	OL2.03.2	511	<i>Detection of DDoS Attack on Software-Defined Networking Controller Using Convolutional Neural Networks</i>
Adiba, Fhatiah	OL1.03.6	125	<i>Enhanced Flood Detection on Highways: A Comparative Study of MobileNet and VGG16 CNN Models Based on CCTV Images</i>
	OL1.05.9	248	<i>Eye Disease Classification System Based on Fundus Image Using Transfer Learning Convolutional Neural Network Model ResNet50</i>
	OL2.05.3	599	<i>Application of MobileNet Architecture for Pneumonia Disease Classification Based on Lung X-Ray Images</i>
Adithya, Muh.	OS1.01.4	16	<i>Examining Reliability in Delay Tolerant Networks: A Study of Protocol Behavior</i>
Agatep, John Lenon	OL1.03.8	136	<i>Model Development in Recognizing Affect through Facial Expressions of Students' Engagement in Synchronous Class</i>
Agung, Hendi	OL2.06.6	656	<i>DC Fast-Charging for Electric Vehicle with LiFePO4 Battery based on Fuzzy Logic System</i>
Agusta, Yudi	OL1.06.8	293	<i>Area Grouping Based on Inflation During Covid-19 Using Minimum Message Length</i>
Ahamed, Imam Uddin	OL2.07.6	696	<i>Confronting the Challenges of Alzheimer's Diagnosis: A Deep Dive into MRI-Based Early Detection Methods</i>
Ahamed, Imtiaj Uddin	OL2.07.6	696	<i>Confronting the Challenges of Alzheimer's Diagnosis: A Deep Dive into MRI-Based Early Detection Methods</i>
Al-Amiry, Shibly	OL2.06.3	639	<i>OCTm: Custom Deep Learning Model for Diagnosing Retinal Diseases</i>
Al-Hemiary, Emad	OL1.03.2	101	<i>Integrating blockchain with IoT-edge-cloud network for tracking offloaded task</i>
Al-juboori, Ali	OL2.06.3	639	<i>OCTm: Custom Deep Learning Model for Diagnosing Retinal Diseases</i>
Al-Libawy, Hilal	OL2.02.2	469	<i>Low-Cost Blind Spot Detection System Based on Lite Object Detection Algorithm and Limited Resources Hardware</i>
	OL2.08.5	730	<i>An Efficient Hybrid Model for Federated Learning Systems to Deal with Medical Heterogeneous Datasets</i>
Alamsyah, Andry	OL1.05.1	201	<i>Dark Web Content Exploration using Network Analysis based on Data Crawling</i>
Alani, Omar	OL2.09.4	766	<i>A novel mathematical model for optimizing energy consumption in OLSRv2</i>

			<i>routing protocol</i>
Albu-Salih, Alaa	OL2.07.1	666	<i>A CNN- based Improved Walrus Optimization Algorithm to Detect Driver Drowsiness</i>
Alfin, Muhammad Reza	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Alghozali, Muhammad	OL1.08.5	378	<i>Performance Analysis of Discrete Wavelet Transformation Method with K-Nearest Neighbor in Eye Disease Identification</i>
Alifa, Jasmine	OL1.04.3	159	<i>Viral Melodies: Exploring the Factors Influencing Music Virality in TikTok Engagement</i>
Aljebori, Saad	OL1.05.7	236	<i>Clustering Algorithms to Handle IoT Stream of Data</i>
	OL2.02.4	481	<i>Evaluating the Effects of Sensors Clustering on Wireless Sensor Networks Performance</i>
	OL2.05.2	593	<i>Enhancing Reliability in Wireless Sensor Networks through Cluster-based Optimization</i>
	OL2.06.4	644	<i>A Developed Safety Distance Model to Predict the Vehicles Traffic Flow</i>
Almiahi, Osama	OL2.07.1	666	<i>A CNN- based Improved Walrus Optimization Algorithm to Detect Driver Drowsiness</i>
Alomari, Mohammed	OL2.04.4	564	<i>Optimizing Cloud Storage Costs: Introducing the Pre-Evaluation-Based Cost Optimization Mechanism (PECSCO)</i>
Alshakarchy, Noor	OL1.02.4	61	<i>Predicting the Severity of Parkinson's Disease Based on Voice Analysis Using Deep Learning</i>
Alwan, Hiba	OL1.02.5	67	<i>Long Short-Term Memory Utilization for Non-Invertible Transformation Face Biometric Recognition System</i>
Amalia, Amalia	OL1.08.4	372	<i>Performance Analysis of KNN and C4.5 Algorithms, with Kappa Measure Evaluation Case Study: Student Graduation Rate at Kemenkes Poltekkes Medan</i>
	OL2.05.4	605	<i>Sentiment Analysis Using K-NN Algorithm Through Random Search Cross Validation Approach</i>
	OL2.09.5	772	<i>Performance of Term Frequency - Inverse Document Frequency and K-Means in Government Service Identification</i>
Amin, Ahmad	OS1.01.5	22	<i>Comparing Fuzzy Logic Controller (FLC) and Adaptive Neuro-Fuzzy Inference System (ANFIS) for Auto-Cooling System in Generator Rotor Straightening</i>
Amin, Muhammad	OL2.03.3	517	<i>Performance Improvement of Apriori Algorithm with Transaction Reduction and Hash Based Approach</i>
Amril, Muhammad	OL1.09.9	451	<i>Classification Of Indonesian Rupiah Currency Using Convolutional Neural Network For Visually Impaired Individuals</i>
Anggreainy, Maria Susan	OL1.08.2	364	<i>Implementation of the EfficientNet Model for Identification of Wild Edible Plants</i>
	OL1.08.3	368	<i>Performance Analysis of Heart Disease Prediction using Kernels in Support Vector Machine Model</i>
Apriono, Catur	OL2.03.6	534	<i>Design of Bidirectional TWDM-PON Network for High-Speed Internet Access in Industrial Zones</i>
Aries Tantya, Henny Sukmawati	OL1.09.5	427	<i>Maximum Power Point Tracking (MPPT) using Differential Evolution Algorithm on the SEPIC Converter for Solar Panels under Partially Shaded Conditions</i>
Arifin, Zainal	OS1.01.2	7	<i>Implementation of Distributed Wide Area Monitoring System Server</i>

Configuration on Java-Madura-Bali Power System

Ariyani, Linda Fauziyah	OS1.01.7	33	<i>Artificial Intelligence: Investigating the Impact of Teacher's Awareness, Perception, and Learning Motivation on Learning Evaluation</i>
Ariyanto, Gabrielle	OL1.03.3	107	<i>Enhancing Online Learning Experience: An Ensemble Approach for Classifying Student Adaptivity Level</i>
Aung, Myo Min	OL1.03.1	96	<i>Kinematic and Dynamic Equations for the Design and Simulation of 2DOF PID-Controlled Exoskeleton</i>

B

B, zhraa	OL2.02.1	463	<i>Skin Melanoma diagnoses using machine learning and ABCD rule</i>
Badriyah, Tessy	OL1.09.6	433	<i>A Comparative Analysis of Logistic Regression and Decision Trees for Mortality Risk Prediction using Laboratory Data</i>
Baihaqi, Mahesa	OL2.03.4	523	<i>Use of an Expert System to Diagnose and Provide Solutions for Pests and Diseases in Hydroponic Mustard Plants Using Certainty Factor and Forward Chaining Methods</i>
Baihaqi, Thirza	OL1.05.2	207	<i>Breast Cancer Image Classification Obtained Through Dynamic Thermography using Deep Learning</i>
Bali, Fajar	OS1.01.3	12	<i>Implementation P-Wave Detection in a Seismic Waveform Using PhaseNet</i>
Ballera, Melvin	OL1.05.5	225	<i>Modified Recommender Algorithm based on Technique for Order of Preference by Similarity to Ideal Solution (TOPSIS) Methodology with Entropy Weighting Method (EWM)</i>
Beu, Donny	OL2.05.6	616	<i>Texture Analysis of Scalogram Image from Alcoholic EEG Signals using CNN</i>
Budiarti, Dewi	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Budiman, Mohammad	OL2.03.7	540	<i>Construction of a Self-balancing Cube with Embedded Reaction Wheel Drive and Preliminary Investigation of Simple Harmonic Motion Patterns</i>
Budiwati, Sari Dewi	OL1.04.4	165	<i>Opinion Classification on MSME Social Media Comments using Support Vector Machine and Random Forest Models</i>
	OL1.06.6	282	<i>Classification for Human Resource Talent Management Using Support Vector Machine Model</i>
Bui, Rin	OL2.08.2	714	<i>Proposing a Support System to Identify Stroke Patients Using RetinaFace and Resnet50 Model</i>
Bunu, Sanusi	OL2.09.4	766	<i>A novel mathematical model for optimizing energy consumption in OLSRv2 routing protocol</i>

C

Candra, Ade	OL2.03.3	517	<i>Performance Improvement of Apriori Algorithm with Transaction Reduction and Hash Based Approach</i>
	OL2.06.7	662	<i>Determining The Parameter K of K-Nearest Neighbors (KNN) using Random Grid Search</i>
Chamim, Anna Nur Nazilah	OL1.03.7	131	<i>Classification System of Breast Cancer using Machine Learning on Hu Moment Invariants and GLCM Features</i>
Chandra, Kelvin	OL1.09.1	407	<i>Leveraging IndoBert for CyberBullying Classification on Social Media</i>
Chasanah, Umi	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Crisnapati, Padma Nyoman	OL1.03.1	96	<i>Kinematic and Dynamic Equations for the Design and Simulation of 2DOF PID-Controlled Exoskeleton</i>

D

Dahlan, Iqbal	OL1.08.9	402	<i>Regression Modeling for Predicting House Prices in Java Island</i>
Dang Dang, Dinh	OL2.08.2	714	<i>Proposing a Support System to Identify Stroke Patients Using RetinaFace and Resnet50 Model</i>
Dani Prasetyo Adi, Puput	OL1.07.8	347	<i>Light Fidelity Internet of Things based for Medical Applications</i>
Darma Andayani, Dyah	OL1.03.6	125	<i>Enhanced Flood Detection on Highways: A Comparative Study of MobileNet and VGG16 CNN Models Based on CCTV Images</i>
	OL1.05.9	248	<i>Eye Disease Classification System Based on Fundus Image Using Transfer Learning Convolutional Neural Network Model ResNet50</i>
	OL2.05.3	599	<i>Application of MobileNet Architecture for Pneumonia Disease Classification Based on Lung X-Ray Images</i>
Darma Paramartha, I Gusti Ngurah	OL1.04.8	189	<i>IoT Design of Ornamental Fish Aquarium Management Could Monitor Water Conditions</i>
Devassy, Deepa	OL2.05.1	587	<i>Advancing Neuro-Oncological Diagnostics: A Comparative Analysis of Machine and Deep Learning Models for Brain Tumor Classification</i>
Dewi, Sri	OL2.04.5	570	<i>Automatic Text Review Summarization of Digital Library System Application using TextRank Algorithm and TF-IDF</i>
Dharmawan, Gregorius	OS1.01.1	1	<i>A technique utilizing Machine Learning and Convolutional Neural Networks (CNN) for the identification of SQL Injection Attacks</i>
Dinakar, Punarv	OL1.02.8	83	<i>Multi-Organ 3D Reconstruction and Virtual Reality Visualization Using Graph-Based Segmentation</i>
Divayana, Dewa Gede	OL1.04.8	189	<i>IoT Design of Ornamental Fish Aquarium Management Could Monitor Water Conditions</i>
	OL1.05.8	242	<i>The Presence of the JOFF Formula as an Effort to Optimize the DIVAYANA Formula Ranking Results</i>
Duong, Tan Nghia	OL2.08.3	720	<i>Smart Stick Detecting Obstacles Early Using Random Forest Algorithm</i>
	OL2.08.4	725	<i>Designing of System for Monitoring and Forecasting Air Environment Using LSTM Model</i>

E

Ebrahim, Ruqaya	OL2.02.2	469	<i>Low-Cost Blind Spot Detection System Based on Lite Object Detection Algorithm and Limited Resources Hardware</i>
Effendi, Eri Kusuma	OL2.07.4	684	<i>Transient Stability and Power Flow Evaluation on On-Grid Diesel and WHRPG with PV Study Case</i>
Effendi, Syahril	OL1.02.1	45	<i>Reduction of Microarray Data Dimensions to Enhance Performance of Naïve Bayes in Classification</i>
	OL2.03.3	517	<i>Performance Improvement of Apriori Algorithm with Transaction Reduction and Hash Based Approach</i>
El Moudni, Mohammed	OL2.09.2	754	<i>A New Model for Securing Personal Sensitive Information Storage in Multi-Cloud</i>
Elamvazuthi, Irraivan	OL1.07.6	335	<i>Analysis and Modeling of Electroencephalography Bio Signals based on Motor Imagery for Rehabilitation</i>
Estrada, Jheanel	OL1.03.4	113	<i>Lightweight Convolutional Neural Network (CNN) and Long Short-Term Memory Network (LSTM) for Dynamic Hand Gesture Recognition</i>

F

Facta, Mochammad	OL2.06.2	634	<i>Analysis of Three-Phase Grid Synchronization Algorithms Performance Under Harmonic Pollution to Grid Voltage</i>
Fahmi, Fahmi	OL2.03.7	540	<i>Construction of a Self-balancing Cube with Embedded Reaction Wheel Drive and Preliminary Investigation of Simple Harmonic Motion Patterns</i>
Faradisa, Rosiyah	OL1.09.6	433	<i>A Comparative Analysis of Logistic Regression and Decision Trees for Mortality Risk Prediction using Laboratory Data</i>
Farasalsabila, Fidya	OL1.04.9	195	<i>Multi-Label Classification using BERT for Cyberbullying Detection</i>
Farikin, Farikhin	OL1.02.7	77	<i>Hybrid Model Of Unified Theory of Acceptance and Use of Technology (UTAUT), HOT, And Contextual Variables For Analyzing Farmers' Behavior Towards Internet Of Things (IoT)-Based Agricultural Technology</i>
Fatichah, Chastine	OL2.04.3	558	<i>Object Detection in Low-Light Conditions: A Comparison using YOLOv5 and YOLOv8</i>
Fatimah, Caesyerra	OL1.07.1	305	<i>Investigating Generation Z's Technostress During Fintech Adoption: Security and Customer Service with Theory of Planned Behavior in Indonesia</i>
Fatin, Ainiyyah	OL1.07.7	341	<i>The Influence of Perceived Authenticity and EWOM on Price Sensitivity, Perceived Value, Perceived Risk, and Repurchase Intentions in E-commerce Sites</i>
Fernandis, Rasio	OL1.06.9	299	<i>Topic Modeling Using Latent Dirichlet Allocation Method Based On Child Anecdotal Record Data</i>
Fithria, Shaumi	OL1.07.5	329	<i>Performance Analysis of IoT Message Queuing Telemetry Transport Implementation in Smart Home Systems</i>
Fithriasari, Kartika	OL2.08.1	708	<i>Random Forest With Adaptive Synthetic Sampling- Nominal Continuous and Cost Sensitive Learning on Imbalanced Binary Classification</i>
Florenca, Florenca	OL1.03.3	107	<i>Enhancing Online Learning Experience: An Ensemble Approach for Classifying Student Adaptivity Level</i>

G

Gama, Adie Wahyudi Oktavia	OL1.04.8	189	<i>IoT Design of Ornamental Fish Aquarium Management Could Monitor Water Conditions</i>
	OL1.05.8	242	<i>The Presence of the JOFF Formula as an Effort to Optimize the DIVAYANA Formula Ranking Results</i>
Gautam, Manish	OL1.02.2	50	<i>Hybrid Golden Jackal-Sea Lion and Sea Horse Optimization Algorithm for Improved Keystroke Dynamics User Authentication</i>
Gharaei, Niayesh	OL2.04.4	564	<i>Optimizing Cloud Storage Costs: Introducing the Pre-Evaluation-Based Cost Optimization Mechanism (PECSCO)</i>
Gonzales, Clark Justine	OL1.08.8	396	<i>Performance Analysis of Caraga State University's Network Infrastructure: A Software-Defined Networking Approach</i>
Gunawan, Alexander	OL1.03.3	107	<i>Enhancing Online Learning Experience: An Ensemble Approach for Classifying Student Adaptivity Level</i>
	OL1.04.3	159	<i>Viral Melodies: Exploring the Factors Influencing Music Virality in TikTok Engagement</i>
	OL1.05.2	207	<i>Breast Cancer Image Classification Obtained Through Dynamic Thermography using Deep Learning</i>
Gunawan, Gunawan	OS1.01.6	27	<i>Enhancing Computational Strategies to Decode ChatGPT's Influence on the Critical Thinking Abilities of University Students</i>

Gunawan Zain, Satria	OL2.05.3	599	<i>Application of MobileNet Architecture for Pneumonia Disease Classification Based on Lung X-Ray Images</i>
Guoyun, Lv	OL1.06.4	271	<i>Wavelet Entropy and Support Vector Machine multi-class fall detection based on IMU wearable sensors data</i>
Gupta, Uchchas Das	OL2.07.6	696	<i>Confronting the Challenges of Alzheimer's Diagnosis: A Deep Dive into MRI-Based Early Detection Methods</i>

H

Hadi, Asmaa	OL2.04.6	576	<i>Modified Positive Output Super Lift Luo Converter Based on Switched Capacitor Technique</i>
Hadi, Israa	OL2.02.4	481	<i>Evaluating the Effects of Sensors Clustering on Wireless Sensor Networks Performance</i>
Hamami, Faqih	OL1.08.9	402	<i>Regression Modeling for Predicting House Prices in Java Island</i>
	OL1.09.9	451	<i>Classification Of Indonesian Rupiah Currency Using Convolutional Neural Network For Visually Impaired Individuals</i>
Hamid, Sabaa	OL2.02.7	499	<i>Generation Method of Dynamic Coverless Arabic Text Information Hiding Using First-Order Markov Chain</i>
Hamzah, Ali	OL2.09.1	748	<i>Optimizing Face Recognition Accuracy with HOG Features and SVM Classifier: A Study on ORL and Yale Databases</i>
Hanif, Fitra	OL1.04.1	148	<i>Optimizing Self-Learning Forwarding Strategies in Vehicular Named Data Network through Protocol Simplification</i>
Hardi, Richki	OS1.01.6	27	<i>Enhancing Computational Strategies to Decode ChatGPT's Influence on the Critical Thinking Abilities of University Students</i>
Harefa, Jeklin	OL1.06.5	276	<i>Transfer Learning using IndoBERT with Long Short-Term Memory Classifier for Detection of Suicide Ideation Themed Indonesian Twitter Posts</i>
Hartono, Ferry	OL1.07.7	341	<i>The Influence of Perceived Authenticity and EWOM on Price Sensitivity, Perceived Value, Perceived Risk, and Repurchase Intentions in E-commerce Sites</i>
Harun Pamungkas, Alim	OS1.01.7	33	<i>Artificial Intelligence: Investigating the Impact of Teacher's Awareness, Perception, and Learning Motivation on Learning Evaluation</i>
Hasan, Ali	OL2.02.6	493	<i>Breast Masses in Dynamic Contrast-Enhanced Magnetic Resonance Imaging Classification Based on Combining Deep Learning and Local Binary Pattern Features</i>
Hasan, Hussain	OL2.02.6	493	<i>Breast Masses in Dynamic Contrast-Enhanced Magnetic Resonance Imaging Classification Based on Combining Deep Learning and Local Binary Pattern Features</i>
Hasan, Riyam	OL2.04.4	564	<i>Optimizing Cloud Storage Costs: Introducing the Pre-Evaluation-Based Cost Optimization Mechanism (PECSCO)</i>
Hasanah, Rini	OL2.05.7	622	<i>Active Gate Driver with RC Snubber and Proportional-Integral (PI) Controller for Voltage Balancing of Series Connected SiC MOSFETs</i>
Hasani, Muhammad Fikri	OL1.09.1	407	<i>Leveraging IndoBert for CyberBullying Classification on Social Media</i>
Hernawati, Elis	OL1.06.6	282	<i>Classification for Human Resource Talent Management Using Support Vector Machine Model</i>
Hidayatulloh, Zulkifli	OS1.01.1	1	<i>A technique utilizing Machine Learning and Convolutional Neural Networks (CNN) for the identification of SQL Injection Attacks</i>

Hirsi, Abdinasir	OL2.04.2	552	<i>Design and Simulation of a Secured Enterprise Network Architecture for All Departments at East Africa University (EAU), Somalia</i>
Hossain, Al-Amin	OL2.07.6	696	<i>Confronting the Challenges of Alzheimer's Diagnosis: A Deep Dive into MRI-Based Early Detection Methods</i>
Hreshee, Saad	OL2.08.6	736	<i>Performance Evaluation of Film Bulk Acoustic wave Resonator with different piezoelectric materials</i>
Hugo, Bryan	OL2.06.6	656	<i>DC Fast-Charging for Electric Vehicle with LiFePO4 Battery based on Fuzzy Logic System</i>
Humairoh, Siti	OL1.03.5	119	<i>Indonesian Sign Language Detection for The Deaf using Convolutional Neural Network Algorithm</i>
Hussein, Ehab	OL2.02.2	469	<i>Low-Cost Blind Spot Detection System Based on Lite Object Detection Algorithm and Limited Resources Hardware</i>
Hussein, Farah	OL1.05.7	236	<i>Clustering Algorithms to Handle IoT Stream of Data</i>
Hussein, Zaid	OL2.07.2	672	<i>Design Improved Transimpedance CMOS amplifier for optical Receiver front end</i>
Huu Hoang, Nhan	OL2.08.2	714	<i>Proposing a Support System to Identify Stroke Patients Using RetinaFace and Resnet50 Model</i>

I

Inayatulloh, Inayatulloh	OL1.02.3	56	<i>Adoption of Blockchain Technology for Digital Heritage to Improve Heritage Security</i>
Indrawan, Gede	OL1.04.8	189	<i>IoT Design of Ornamental Fish Aquarium Management Could Monitor Water Conditions</i>
Indrayani, Novi	OS1.01.7	33	<i>Artificial Intelligence: Investigating the Impact of Teacher's Awareness, Perception, and Learning Motivation on Learning Evaluation</i>
Indrayanto, Cecep	OL1.02.7	77	<i>Hybrid Model Of Unified Theory of Acceptance and Use of Technology (UTAUT), HOT, And Contextual Variables For Analyzing Farmers' Behavior Towards Internet Of Things (IoT)-Based Agricultural Technology</i>
Intan Caesarista, Valentine Kilau	OL2.06.2	634	<i>Analysis of Three-Phase Grid Synchronization Algorithms Performance Under Harmonic Pollution to Grid Voltage</i>
Irmawati, Irmawati	OL1.06.3	265	<i>Localizing Copy-Move Manipulations in Digital Images Using U-Net Architecture with Various Backbone Models</i>
	OL2.02.3	475	<i>Detection of Image Splicing and Copy-Move Forgery Using the Prewitt Operator and CNN Approach</i>
Iskandar, Riyadi	OL2.04.3	558	<i>Object Detection in Low-Light Conditions: A Comparison using YOLOv5 and YOLOv8</i>
Istikmal, Istikmal	OL1.04.1	148	<i>Optimizing Self-Learning Forwarding Strategies in Vehicular Named Data Network through Protocol Simplification</i>
Iyer, Saanchita	OL1.02.8	83	<i>Multi-Organ 3D Reconstruction and Virtual Reality Visualization Using Graph-Based Segmentation</i>

J

Jasim, Huda	OL1.02.4	61	<i>Predicting the Severity of Parkinson's Disease Based on Voice Analysis Using Deep Learning</i>
Jayaraj, Akshaya	OL2.05.1	587	<i>Advancing Neuro-Oncological Diagnostics: A Comparative Analysis of Machine and Deep Learning Models for Brain Tumor Classification</i>
Jie, Ferry	OL2.03.4	523	<i>Use of an Expert System to Diagnose and Provide Solutions for Pests and Diseases in Hydroponic Mustard Plants Using Certainty Factor and Forward</i>

Chaining Methods

Joseph, Willson	OL2.05.1	587	<i>Advancing Neuro-Oncological Diagnostics: A Comparative Analysis of Machine and Deep Learning Models for Brain Tumor Classification</i>
Jumaah, Maha	OL2.07.1	666	<i>A CNN- based Improved Walrus Optimization Algorithm to Detect Driver Drowsiness</i>
Jusman, Yessi	OL1.03.7	131	<i>Classification System of Breast Cancer using Machine Learning on Hu Moment Invariants and GLCM Features</i>
	OL1.07.3	317	<i>Enhanced Denoising of Cervical Pre-cancerous Cell Images through Advanced Color Filtering</i>
	OL1.09.7	439	<i>Comparative Analysis of Image Filtering for Dental Caries Image</i>

K

Kadhim, Rabab	OL2.02.6	493	<i>Breast Masses in Dynamic Contrast-Enhanced Magnetic Resonance Imaging Classification Based on Combining Deep Learning and Local Binary Pattern Features</i>
Kaittan, Kadhim	OL2.08.7	742	<i>Wastewater Aeration process based Cloud-SCADA/PLC System</i>
Karo Karo, Ichwanul	OL2.04.5	570	<i>Automatic Text Review Summarization of Digital Library System Application using TextRank Algorithm and TF-IDF</i>
Kartika, Afriyanti	OL1.04.2	154	<i>Monitoring Railway Journeys at Unauthorized Crossings in Padang City using Geographic Information System (GIS)</i>
Kasih, Patmi	OL1.06.9	299	<i>Topic Modeling Using Latent Dirichlet Allocation Method Based On Child Anecdotal Record Data</i>
Kaswar, Andi Baso	OL1.03.6	125	<i>Enhanced Flood Detection on Highways: A Comparative Study of MobileNet and VGG16 CNN Models Based on CCTV Images</i>
	OL1.05.9	248	<i>Eye Disease Classification System Based on Fundus Image Using Transfer Learning Convolutional Neural Network Model ResNet50</i>
	OL2.05.3	599	<i>Application of MobileNet Architecture for Pneumonia Disease Classification Based on Lung X-Ray Images</i>
Khalsum, Ummu	OL1.07.9	353	<i>Enhancement of Voltage Quality through D-STATCOM Implementation in the Electrical Infrastructure of Semen Tonasa</i>
Khamiss, Nassr	OL2.09.6	778	<i>VVC Encoded Video Transmission over 5G-based Multiple Access Systems</i>
Kimberly, Sofie	OL1.06.5	276	<i>Transfer Learning using IndoBERT with Long Short-Term Memory Classifier for Detection of Suicide Ideation Themed Indonesian Twitter Posts</i>
Kurniawan, M.	OL1.09.10	457	<i>Evaluating Quality of Service: Throughput, Packet Loss, and Delay in Tree Topology with Ryu and Pox Controllers in Software Defined Networks</i>
Kusnadi, Maria Darlene	OL1.06.3	265	<i>Localizing Copy-Move Manipulations in Digital Images Using U-Net Architecture with Various Backbone Models</i>
Kusrini, Kusrini	OL2.05.5	611	<i>Multilingual Named Entity Recognition Model for Location and Time Extraction of Forest Fire</i>
Kusuma, Ivan	OS1.01.2	7	<i>Implementation of Distributed Wide Area Monitoring System Server Configuration on Java-Madura-Bali Power System</i>
Kusuma, Selvia	OL1.09.6	433	<i>A Comparative Analysis of Logistic Regression and Decision Trees for Mortality Risk Prediction using Laboratory Data</i>
Kyaw, Khin Yadana	OL1.03.1	96	<i>Kinematic and Dynamic Equations for the Design and Simulation of 2DOF PID-Controlled Exoskeleton</i>

L

Lamada, Mustari	OL1.05.9	248	<i>Eye Disease Classification System Based on Fundus Image Using Transfer Learning Convolutional Neural Network Model ResNet50</i>
Liu, ShiYa	OL1.06.4	271	<i>Wavelet Entropy and Support Vector Machine multi-class fall detection based on IMU wearable sensors data</i>
Lizo, Leander	OL1.03.4	113	<i>Lightweight Convolutional Neural Network (CNN) and Long Short-Term Memory Network (LSTM) for Dynamic Hand Gesture Recognition</i>
Lubis, Hasby	OL2.09.5	772	<i>Performance of Term Frequency - Inverse Document Frequency and K-Means in Government Service Identification</i>
Lubis, Muharman	OL1.09.10	457	<i>Evaluating Quality of Service: Throughput, Packet Loss, and Delay in Tree Topology with Ryu and Pox Controllers in Software Defined Networks</i>
Lucas, Jerry	OL1.06.1	254	<i>Analyzing the Impact of ChatGPT on Enhancing Academic Skills and Learning Concepts Among University Students in Jakarta</i>
Lucky, Henry	OL1.06.2	259	<i>Polkadot Cryptocurrency Close Price Prediction Using Machine Learning</i>
Lukitosari, Valeriana	OL1.06.7	288	<i>Pricing Strategies Using Design of Experiment in Online and Offline Supply Chain</i>
Lukitosari, Valeriana	OL1.09.4	421	<i>Optimizing Air Cargo Delivery Routes with a Modified Artificial Bee Colony</i>
Lusiastuti, Angela Mariana	OL1.07.8	347	<i>Light Fidelity Internet of Things based for Medical Applications</i>
Lydia, Maya	OL1.09.2	412	<i>Improved Accuracy of Decision Tree with XGBoost Technique in Animal Disease Diagnosis</i>
	OL1.09.3	417	<i>Indonesian Dynamic Sign Language Recognition for Individuals with Sensory Disabilities using LSTM</i>

M

Madyatmadja, Evaristus	OL1.06.1	254	<i>Analyzing the Impact of ChatGPT on Enhancing Academic Skills and Learning Concepts Among University Students in Jakarta</i>
Mahdiyah, Umi	OL1.08.5	378	<i>Performance Analysis of Discrete Wavelet Transformation Method with K-Nearest Neighbor in Eye Disease Identification</i>
Mahmoud, Moamin	OL2.04.4	564	<i>Optimizing Cloud Storage Costs: Introducing the Pre-Evaluation-Based Cost Optimization Mechanism (PECSCO)</i>
Maneetham, Dechrit	OL1.03.1	96	<i>Kinematic and Dynamic Equations for the Design and Simulation of 2DOF PID-Controlled Exoskeleton</i>
Manvi, Tri Eko Putra	OL1.04.6	177	<i>Performance Evaluation of Equivalent Circuit Model Parameter Extraction Methods on Lithium-Ion Battery</i>
	OL2.04.7	582	<i>State of Charge Estimation of Lithium Ion Battery Using Coulomb Counting Method Based on Raspberry Pi</i>
Massie, Gary	OL1.05.9	248	<i>Eye Disease Classification System Based on Fundus Image Using Transfer Learning Convolutional Neural Network Model ResNet50</i>
Maulana, Agus	OS1.01.2	7	<i>Implementation of Distributed Wide Area Monitoring System Server Configuration on Java-Madura-Bali Power System</i>
Maulana, Bayu	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Mayadewi, RA	OL1.03.5	119	<i>Indonesian Sign Language Detection for The Deaf using Convolutional Neural Network Algorithm</i>
	OL1.04.5	171	<i>Nutrient Detection In Complementary Feeding Using Convolutional Neural</i>

Network Algorithm

Mayasari, Fitriyanti	OL1.07.9	353	<i>Enhancement of Voltage Quality through D-STATCOM Implementation in the Electrical Infrastructure of Semen Tonasa</i>
Medikawati, Mita	OL1.07.7	341	<i>The Influence of Perceived Authenticity and EWOM on Price Sensitivity, Perceived Value, Perceived Risk, and Repurchase Intentions in E-commerce Sites</i>
Mohammad, Yusra	OL2.06.5	650	<i>Hybridization of Self Supervised Learning Models for Enhancing Automatic Arabic Speech Recognition</i>
Mohammed, Raya	OL2.09.6	778	<i>VVC Encoded Video Transmission over 5G-based Multiple Access Systems</i>
Mohammed, Samir	OL2.08.7	742	<i>Wastewater Aeration process based Cloud-SCADA/PLC System</i>
Mohammed, Tiba	OL2.08.5	730	<i>An Efficient Hybrid Model for Federated Learning Systems to Deal with Medical Heterogeneous Datasets</i>
Mohammed Hussein, Safa	OL1.06.4	271	<i>Wavelet Entropy and Support Vector Machine multi-class fall detection based on IMU wearable sensors data</i>
Mohd Kanafiah, Siti Nurul Aqmariah	OL1.09.7	439	<i>Comparative Analysis of Image Filtering for Dental Caries Image</i>
Motlak, Hassan	OL2.04.6	576	<i>Modified Positive Output Super Lift Luo Converter Based on Switched Capacitor Technique</i>
	OL2.07.2	672	<i>Design Improved Transimpedance CMOS amplifier for optical Receiver front end</i>
Muhammad, Hasan	OL2.02.5	487	<i>Exploration of Internal Factors Influencing the Success of Digital Projects</i>
Mukti, Iqbal	OL2.02.5	487	<i>Exploration of Internal Factors Influencing the Success of Digital Projects</i>
Muliadi, Jemie	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Munadi, Rendy	OS1.01.4	16	<i>Examining Reliability in Delay Tolerant Networks: A Study of Protocol Behavior</i>
Mundzir, Mundzir	OS1.01.7	33	<i>Artificial Intelligence: Investigating the Impact of Teacher's Awareness, Perception, and Learning Motivation on Learning Evaluation</i>
Musnansyah, Ahmad	OL1.09.9	451	<i>Classification Of Indonesian Rupiah Currency Using Convolutional Neural Network For Visually Impaired Individuals</i>
Mutiara, Belinda	OL1.03.3	107	<i>Enhancing Online Learning Experience: An Ensemble Approach for Classifying Student Adaptivity Level</i>

N

Nababan, Erna	OL1.02.1	45	<i>Reduction of Microarray Data Dimensions to Enhance Performance of Naïve Bayes in Classification</i>
	OL1.09.3	417	<i>Indonesian Dynamic Sign Language Recognition for Individuals with Sensory Disabilities using LSTM</i>
Nagendra, Roshni	OL1.02.8	83	<i>Multi-Organ 3D Reconstruction and Virtual Reality Visualization Using Graph-Based Segmentation</i>
Nair, Amrutha	OL2.05.1	587	<i>Advancing Neuro-Oncological Diagnostics: A Comparative Analysis of Machine and Deep Learning Models for Brain Tumor Classification</i>
Nararto, Emily	OL1.04.4	165	<i>Opinion Classification on MSME Social Media Comments using Support Vector Machine and Random Forest Models</i>
Nasaruddin,	OL1.07.5	329	<i>Performance Analysis of IoT Message Queuing Telemetry Transport</i>

Nasaruddin			<i>Implementation in Smart Home Systems</i>
Naser, Roaa	OL2.06.4	644	<i>A Developed Safety Distance Model to Predict the Vehicles Traffic Flow</i>
Nasrawi, Dhamyaa	OL1.02.6	72	<i>Extracting Gender Textual Nuances Using Text Similarity for Gender Classification Improvement</i>
	OL2.02.7	499	<i>Generation Method of Dynamic Coverless Arabic Text Information Hiding Using First-Order Markov Chain</i>
Nasrul, Nasrul	OL2.05.3	599	<i>Application of MobileNet Architecture for Pneumonia Disease Classification Based on Lung X-Ray Images</i>
Nasution, Benny	OL1.09.2	412	<i>Improved Accuracy of Decision Tree with XGBoost Technique in Animal Disease Diagnosis</i>
Nasution, Mahyuddin	OL2.09.5	772	<i>Performance of Term Frequency - Inverse Document Frequency and K-Means in Government Service Identification</i>
Natali, Yus	OL2.03.6	534	<i>Design of Bidirectional TWDM-PON Network for High-Speed Internet Access in Industrial Zones</i>
Nguyen, Phat	OL2.08.2	714	<i>Proposing a Support System to Identify Stroke Patients Using RetinaFace and Resnet50 Model</i>
	OL2.08.3	720	<i>Smart Stick Detecting Obstacles Early Using Random Forest Algorithm</i>
	OL2.08.4	725	<i>Designing of System for Monitoring and Forecasting Air Environment Using LSTM Model</i>
Nguyen Ha, Anh	OL2.08.4	725	<i>Designing of System for Monitoring and Forecasting Air Environment Using LSTM Model</i>
Nguyen Hoang Tu, Nhi	OL2.08.2	714	<i>Proposing a Support System to Identify Stroke Patients Using RetinaFace and Resnet50 Model</i>
Nguyen Minh, Bac	OL2.08.3	720	<i>Smart Stick Detecting Obstacles Early Using Random Forest Algorithm</i>
Nguyen Minh, Quang	OL2.08.4	725	<i>Designing of System for Monitoring and Forecasting Air Environment Using LSTM Model</i>
Nguyen Vu Gia, Hien	OL2.08.4	725	<i>Designing of System for Monitoring and Forecasting Air Environment Using LSTM Model</i>
Nilatika, Aminurachma	OL1.08.6	384	<i>Early Diagnosis of Diabetic Retinopathy through Optimization of Convolutional Neural Network Hyperparameters using Genetic Algorithm</i>
Nirad, Dwi Welly Sukma	OL1.04.2	154	<i>Monitoring Railway Journeys at Unauthorized Crossings in Padang City using Geographic Information System (GIS)</i>
Noto, Giri	OL2.06.1	628	<i>Optimization of MLP-Regressor for Predicting Student's Cumulative Grade Point Average (GPA)</i>
Novita, Hessy	OL1.07.8	347	<i>Light Fidelity Internet of Things based for Medical Applications</i>
Nugroho, Anto Satriyo	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Nur 'Aini, Masayu Alya	OL1.09.7	439	<i>Comparative Analysis of Image Filtering for Dental Caries Image</i>
Nurbayani, Siti	OL1.04.5	171	<i>Nutrient Detection In Complementary Feeding Using Convolutional Neural Network Algorithm</i>
Nursanthika, Rika	OL1.03.7	131	<i>Classification System of Breast Cancer using Machine Learning on Hu Moment Invariants and GLCM Features</i>
Nurwati, Tri	OL2.05.7	622	<i>Active Gate Driver with RC Snubber and Proportional-Integral (PI) Controller for</i>

O

Othman, Siti Marhainis	OL1.07.3	317	<i>Enhanced Denoising of Cervical Pre-cancerous Cell Images through Advanced Color Filtering</i>
Owda, Amani	OL2.03.1	505	<i>Solar Power Generation Forecasting Based on Machine Learning Techniques</i>
	OL2.03.2	511	<i>Detection of DDoS Attack on Software-Defined Networking Controller Using Convolutional Neural Networks</i>
	OL2.03.5	528	<i>Optimal Decision Support System Model for Breast Cancer Diagnosis</i>
	OL2.04.1	546	<i>Multi-Channel Fusion Model for Data Logs Analysis and Anomaly Detection in Data Centers</i>
Owda, Majdi	OL2.03.1	505	<i>Solar Power Generation Forecasting Based on Machine Learning Techniques</i>
	OL2.03.2	511	<i>Detection of DDoS Attack on Software-Defined Networking Controller Using Convolutional Neural Networks</i>
	OL2.03.5	528	<i>Optimal Decision Support System Model for Breast Cancer Diagnosis</i>
	OL2.04.1	546	<i>Multi-Channel Fusion Model for Data Logs Analysis and Anomaly Detection in Data Centers</i>

P

P, Likitha	OL1.02.8	83	<i>Multi-Organ 3D Reconstruction and Virtual Reality Visualization Using Graph-Based Segmentation</i>
Pacaon, Mark Reden	OL1.05.5	225	<i>Modified Recommender Algorithm based on Technique for Order of Preference by Similarity to Ideal Solution (TOPSIS) Methodology with Entropy Weighting Method (EWM)</i>
Palupi, Shinta	OS1.01.6	27	<i>Enhancing Computational Strategies to Decode ChatGPT's Influence on the Critical Thinking Abilities of University Students</i>
Pamungkas, Danar	OL1.08.5	378	<i>Performance Analysis of Discrete Wavelet Transformation Method with K-Nearest Neighbor in Eye Disease Identification</i>
Panduwiyasa, Haryasena	OL1.07.1	305	<i>Investigating Generation Z's Technostress During Fintech Adoption: Security and Customer Service with Theory of Planned Behavior in Indonesia</i>
	OL1.07.2	311	<i>Gen Z's Embrace of Fintech: A Study on Customer Support and Security as Technostress Factors in e-Wallet Use in Indonesia</i>
Patel, Manav	OL1.02.2	50	<i>Hybrid Golden Jackal-Sea Lion and Sea Horse Optimization Algorithm for Improved Keystroke Dynamics User Authentication</i>
Penangsang, Ontoseno	OL2.07.4	684	<i>Transient Stability and Power Flow Evaluation on On-Grid Diesel and WHRPG with PV Study Case</i>
Perdana, Adidtya	OL2.04.5	570	<i>Automatic Text Review Summarization of Digital Library System Application using TextRank Algorithm and TF-IDF</i>
Permana, Julian	OL1.04.6	177	<i>Performance Evaluation of Equivalent Circuit Model Parameter Extraction Methods on Lithium-Ion Battery</i>
	OL2.04.7	582	<i>State of Charge Estimation of Lithium Ion Battery Using Coulomb Counting Method Based on Raspberry Pi</i>
Pham Viet, Thanh	OL2.08.3	720	<i>Smart Stick Detecting Obstacles Early Using Random Forest Algorithm</i>
	OL2.08.4	725	<i>Designing of System for Monitoring and Forecasting Air Environment Using LSTM Model</i>
Pinem, Josua	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet</i>

Geovani			<i>Pre-trained Model</i>
Pitogo, Vicente	OL1.08.8	396	<i>Performance Analysis of Caraga State University's Network Infrastructure: A Software-Defined Networking Approach</i>
Poyai, Mana	OL1.08.1	358	<i>LabVIEW Integrated with Python Machine Learning for DC Motor Drive</i>
Pradipta, Doni	OL2.05.7	622	<i>Active Gate Driver with RC Snubber and Proportional-Integral (PI) Controller for Voltage Balancing of Series Connected SiC MOSFETs</i>
Pradito, Baskoro	OL1.06.6	282	<i>Classification for Human Resource Talent Management Using Support Vector Machine Model</i>
Prahasto, Toni	OL1.02.7	77	<i>Hybrid Model Of Unified Theory of Acceptance and Use of Technology (UTAUT), HOT, And Contextual Variables For Analyzing Farmers' Behavior Towards Internet Of Things (IoT)-Based Agricultural Technology</i>
Prajitno, Prawito	OL1.04.6	177	<i>Performance Evaluation of Equivalent Circuit Model Parameter Extraction Methods on Lithium-Ion Battery</i>
	OL2.04.7	582	<i>State of Charge Estimation of Lithium Ion Battery Using Coulomb Counting Method Based on Raspberry Pi</i>
Pramesti, Putri Ayu	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Pramono, Sholeh	OL1.08.6	384	<i>Early Diagnosis of Diabetic Retinopathy through Optimization of Convolutional Neural Network Hyperparameters using Genetic Algorithm</i>
Prasetya, Kristo	OL1.09.1	407	<i>Leveraging IndoBert for CyberBullying Classification on Social Media</i>
Prasetyo, Simeon Yuda	OL1.05.3	213	<i>Diabetes Risk Prediction Exploration: Uncovering Patterns and Enhancing Predictive Accuracy through Ensemble Learning</i>
	OL1.05.4	219	<i>Breast Cancer Detection with Multi Layer Perceptron: Unveiling Neuron Unit Dynamics in Dual Hidden Layers</i>
	OL1.05.6	231	<i>Optimizing Rice Variety Recognition Through Transfer Learning with Pretrained ResNet Models</i>
Pribadi, Agung	OS1.01.6	27	<i>Enhancing Computational Strategies to Decode ChatGPT's Influence on the Critical Thinking Abilities of University Students</i>
Puji Widodo, Aris	OL2.03.4	523	<i>Use of an Expert System to Diagnose and Provide Solutions for Pests and Diseases in Hydroponic Mustard Plants Using Certainty Factor and Forward Chaining Methods</i>
Purwanto, Yudha	OL1.05.1	201	<i>Dark Web Content Exploration using Network Analysis based on Data Crawling</i>
Puspita, Sartika	OL1.09.7	439	<i>Comparative Analysis of Image Filtering for Dental Caries Image</i>
Putra, Anggi	OL1.07.4	323	<i>Forensic Investigation of User Privacy Violation by Android Malware with Hybrid Analysis</i>
Putra, Gilang	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Putra, I Gede	OL2.06.1	628	<i>Optimization of MLP-Regressor for Predicting Student's Cumulative Grade Point Average (GPA)</i>
Putra, Rizky	OL2.08.1	708	<i>Random Forest With Adaptive Synthetic Sampling- Nominal Continuous and Cost Sensitive Learning on Imbalanced Binary Classification</i>
Putri, Adinda Novita Prima	OL1.07.2	311	<i>Gen Z's Embrace of Fintech: A Study on Customer Support and Security as Technostress Factors in e-Wallet Use in Indonesia</i>

R

R Sharika, T	OL2.05.1	587	<i>Advancing Neuro-Oncological Diagnostics: A Comparative Analysis of Machine</i>
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			<i>and Deep Learning Models for Brain Tumor Classification</i>
Rabee, Sarah	OL1.03.2	101	<i>Integrating blockchain with IoT-edge-cloud network for tracking offloaded task</i>
Rachmawati, Ika	OL1.05.4	219	<i>Breast Cancer Detection with Multi Layer Perceptron: Unveiling Neuron Unit Dynamics in Dual Hidden Layers</i>
Radhi, Ahmed	OL2.07.7	702	<i>Improve the Quad copter Stability by Using An Adaptive Fuzzy Inference Neural Network (AFINN)</i>
Rahardjo, Evelyn	OL1.04.3	159	<i>Viral Melodies: Exploring the Factors Influencing Music Virality in TikTok Engagement</i>
Raharjo, Suwanto	OL1.04.9	195	<i>Multi-Label Classification using BERT for Cyberbullying Detection</i>
Rahayu, Santi	OL2.08.1	708	<i>Random Forest With Adaptive Synthetic Sampling- Nominal Continuous and Cost Sensitive Learning on Imbalanced Binary Classification</i>
Rahmadwati, Rahmadwati	OL1.08.6	384	<i>Early Diagnosis of Diabetic Retinopathy through Optimization of Convolutional Neural Network Hyperparameters using Genetic Algorithm</i>
Rahmaniar, Thalita	OL2.05.6	616	<i>Texture Analysis of Scalogram Image from Alcoholic EEG Signals using CNN</i>
Rahmatullah, Rizky	OL1.07.8	347	<i>Light Fidelity Internet of Things based for Medical Applications</i>
Rahmawati, Maryza	OL1.07.3	317	<i>Enhanced Denoising of Cervical Pre-cancerous Cell Images through Advanced Color Filtering</i>
Ramadani, Luthfi	OL2.02.5	487	<i>Exploration of Internal Factors Influencing the Success of Digital Projects</i>
Ramadhani, Putri	OL1.02.1	45	<i>Reduction of Microarray Data Dimensions to Enhance Performance of Naïve Bayes in Classification</i>
Ramadhani, Risky	OL1.06.9	299	<i>Topic Modeling Using Latent Dirichlet Allocation Method Based On Child Anecdotal Record Data</i>
Ramli, Kalamullah	OS1.01.1	1	<i>A technique utilizing Machine Learning and Convolutional Neural Networks (CNN) for the identification of SQL Injection Attacks</i>
Rasool, Samer	OL2.04.4	564	<i>Optimizing Cloud Storage Costs: Introducing the Pre-Evaluation-Based Cost Optimization Mechanism (PECSCO)</i>
Rayhan, Berlian	OL2.03.6	534	<i>Design of Bidirectional TWDM-PON Network for High-Speed Internet Access in Industrial Zones</i>
Repalle, Shanmukha	OL1.02.8	83	<i>Multi-Organ 3D Reconstruction and Virtual Reality Visualization Using Graph-Based Segmentation</i>
Reshma, M	OL2.05.1	587	<i>Advancing Neuro-Oncological Diagnostics: A Comparative Analysis of Machine and Deep Learning Models for Brain Tumor Classification</i>
Rifai, Khoirul	OS1.01.5	22	<i>Comparing Fuzzy Logic Controller (FLC) and Adaptive Neuro-Fuzzy Inference System (ANFIS) for Auto-Cooling System in Generator Rotor Straightening</i>
Risal, Andi Akram Nur	OL2.05.3	599	<i>Application of MobileNet Architecture for Pneumonia Disease Classification Based on Lung X-Ray Images</i>
Rizal, Achmad	OL2.05.6	616	<i>Texture Analysis of Scalogram Image from Alcoholic EEG Signals using CNN</i>
	OL2.07.5	690	<i>Heart Rate Measuring System using Accelerometer And Gyroscope Sensor in Android Smartphone</i>
Rizalihadi, Maimun	OL2.09.3	760	<i>Flood Susceptibility Mapping using GIS Based on Fuzzy AHP Method in Keureuto River Basin, Aceh</i>
Rizki Prasetya,	OL2.02.3	475	<i>Detection of Image Splicing and Copy-Move Forgery Using the Prewitt Operator</i>

Naufal Ikhsan			<i>and CNN Approach</i>
Rochana, Siti	OL1.08.5	378	<i>Performance Analysis of Discrete Wavelet Transformation Method with K-Nearest Neighbor in Eye Disease Identification</i>
Rochimah, Siti	OL1.08.7	390	<i>Software Defect Detection Using Optimized Support Vector Machine Based on Grey Wolf Optimizer with Random Walk</i>

S

Saadah, Hanin	OL2.03.5	528	<i>Optimal Decision Support System Model for Breast Cancer Diagnosis</i>
Saddami, Khairun	OL1.07.5	329	<i>Performance Analysis of IoT Message Queuing Telemetry Transport Implementation in Smart Home Systems</i>
Safarina, Sena	OL1.09.4	421	<i>Optimizing Air Cargo Delivery Routes with a Modified Artificial Bee Colony</i>
Safrina, Nanda	OL1.09.2	412	<i>Improved Accuracy of Decision Tree with XGBoost Technique in Animal Disease Diagnosis</i>
Saha, Utsha	OL2.07.6	696	<i>Confronting the Challenges of Alzheimer's Diagnosis: A Deep Dive into MRI-Based Early Detection Methods</i>
Sahertian, Julian	OL1.06.9	299	<i>Topic Modeling Using Latent Dirichlet Allocation Method Based On Child Anecdotal Record Data</i>
Salam, Soekarman	OL2.09.7	784	<i>Determination the Quality of plain X-Ray Using Fuzzy Logic in View of Voltage, Current and Exposure Time Based on Linear Regression</i>
Salio, José	OL2.05.5	611	<i>Multilingual Named Entity Recognition Model for Location and Time Extraction of Forest Fire</i>
Sanjaya, Hafidz	OL2.05.5	611	<i>Multilingual Named Entity Recognition Model for Location and Time Extraction of Forest Fire</i>
Santoso, Rukun	OL1.09.8	445	<i>Detection Model For Potential Flooding Areas Using K-Means And Local Outlier Factor (LOF)</i>
Santy, Santy	OL1.05.3	213	<i>Diabetes Risk Prediction Exploration: Uncovering Patterns and Enhancing Predictive Accuracy through Ensemble Learning</i>
Saputra, Muhardi	OL1.07.1	305	<i>Investigating Generation Z's Technostress During Fintech Adoption: Security and Customer Service with Theory of Planned Behavior in Indonesia</i>
	OL1.07.2	311	<i>Gen Z's Embrace of Fintech: A Study on Customer Support and Security as Technostress Factors in e-Wallet Use in Indonesia</i>
Saputra, Rizky	OL1.09.1	407	<i>Leveraging IndoBert for CyberBullying Classification on Social Media</i>
Saraee, Mo	OL2.09.4	766	<i>A novel mathematical model for optimizing energy consumption in OLSRv2 routing protocol</i>
Sari, Siska	OL1.04.4	165	<i>Opinion Classification on MSME Social Media Comments using Support Vector Machine and Random Forest Models</i>
	OL1.06.6	282	<i>Classification for Human Resource Talent Management Using Support Vector Machine Model</i>
Sariningrum, Ros	OL1.07.8	347	<i>Light Fidelity Internet of Things based for Medical Applications</i>
Saviera, Amadea	OL1.07.7	341	<i>The Influence of Perceived Authenticity and EWOM on Price Sensitivity, Perceived Value, Perceived Risk, and Repurchase Intentions in E-commerce Sites</i>
Senda, Tito	OL2.05.4	605	<i>Sentiment Analysis Using K-NN Algorithm Through Random Search Cross Validation Approach</i>
Setiawan, Hermawan	OL2.06.1	628	<i>Optimization of MLP-Regressor for Predicting Student's Cumulative Grade Point Average (GPA)</i>
Setiawan, Iwan	OL2.06.2	634	<i>Analysis of Three-Phase Grid Synchronization Algorithms Performance Under</i>

			<i>Harmonic Pollution to Grid Voltage</i>
Setiawan, Karli	OL1.03.3	107	<i>Enhancing Online Learning Experience: An Ensemble Approach for Classifying Student Adaptivity Level</i>
	OL1.04.3	159	<i>Viral Melodies: Exploring the Factors Influencing Music Virality in TikTok Engagement</i>
	OL1.05.2	207	<i>Breast Cancer Image Classification Obtained Through Dynamic Thermography using Deep Learning</i>
Setiawan, M. Nurfalah	OS1.01.6	27	<i>Enhancing Computational Strategies to Decode ChatGPT's Influence on the Critical Thinking Abilities of University Students</i>
Setiawan, Michael Dany	OL1.06.5	276	<i>Transfer Learning using IndoBERT with Long Short-Term Memory Classifier for Detection of Suicide Ideation Themed Indonesian Twitter Posts</i>
Setiawan, Sharon	OL1.04.3	159	<i>Viral Melodies: Exploring the Factors Influencing Music Virality in TikTok Engagement</i>
Setiyaji, Andri	OS1.01.1	1	<i>A technique utilizing Machine Learning and Convolutional Neural Networks (CNN) for the identification of SQL Injection Attacks</i>
Shakir, Dhifaf	OL2.08.6	736	<i>Performance Evaluation of Film Bulk Acoustic wave Resonator with different piezoelectric materials</i>
Shiddiqi, Ary Mazharuddin	OL1.03.9	142	<i>A Deep Feature Extraction for Hate Speech Detection using Fine-Tuned Naive Bayes</i>
Siboro, Dina	OL1.08.4	372	<i>Performance Analysis of KNN and C4.5 Algorithms, with Kappa Measure Evaluation Case Study: Student Graduation Rate at Kemenkes Poltekkes Medan</i>
Singh, Indu	OL1.02.2	50	<i>Hybrid Golden Jackal-Sea Lion and Sea Horse Optimization Algorithm for Improved Keystroke Dynamics User Authentication</i>
Siregar, Baihaqi	OL2.03.7	540	<i>Construction of a Self-balancing Cube with Embedded Reaction Wheel Drive and Preliminary Investigation of Simple Harmonic Motion Patterns</i>
Siregar, Fachri	OL2.06.7	662	<i>Determining The Parameter K of K-Nearest Neighbors (KNN) using Random Grid Search</i>
Siswanto, Muhammad	OL1.08.7	390	<i>Software Defect Detection Using Optimized Support Vector Machine Based on Grey Wolf Optimizer with Random Walk</i>
Sitompul, Opim	OL2.03.7	540	<i>Construction of a Self-balancing Cube with Embedded Reaction Wheel Drive and Preliminary Investigation of Simple Harmonic Motion Patterns</i>
	OL2.05.4	605	<i>Sentiment Analysis Using K-NN Algorithm Through Random Search Cross Validation Approach</i>
Srichaipanya, Wichian	OL1.03.1	96	<i>Kinematic and Dynamic Equations for the Design and Simulation of 2DOF PID-Controlled Exoskeleton</i>
Stefanus, Gardhika	OL1.06.7	288	<i>Pricing Strategies Using Design of Experiment in Online and Offline Supply Chain</i>
Stergioulas, Lampros	OL2.03.1	505	<i>Solar Power Generation Forecasting Based on Machine Learning Techniques</i>
	OL2.03.2	511	<i>Detection of DDoS Attack on Software-Defined Networking Controller Using Convolutional Neural Networks</i>
	OL2.03.5	528	<i>Optimal Decision Support System Model for Breast Cancer Diagnosis</i>
Suakanto, Sinung	OL2.02.5	487	<i>Exploration of Internal Factors Influencing the Success of Digital Projects</i>
Subekti, Aulia Haritsuddin	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>

Karisma Muhammad			
Sugiharni, Gusti Ayu	OL1.05.8	242	<i>The Presence of the JOFF Formula as an Effort to Optimize the DIVAYANA Formula Ranking Results</i>
Sugiharto, Aris	OL1.09.8	445	<i>Detection Model For Potential Flooding Areas Using K-Means And Local Outlier Factor (LOF)</i>
Suharjo, Felix	OL1.06.5	276	<i>Transfer Learning using IndoBERT with Long Short-Term Memory Classifier for Detection of Suicide Ideation Themed Indonesian Twitter Posts</i>
Sujatmiko, Nanang	OS1.01.7	33	<i>Artificial Intelligence: Investigating the Impact of Teacher's Awareness, Perception, and Learning Motivation on Learning Evaluation</i>
Sulistiyanto, Sulistiyanto	OS1.01.6	27	<i>Enhancing Computational Strategies to Decode ChatGPT's Influence on the Critical Thinking Abilities of University Students</i>
Sunaryono, Dwi	OL1.08.7	390	<i>Software Defect Detection Using Optimized Support Vector Machine Based on Grey Wolf Optimizer with Random Walk</i>
Supriyadi, Muhamad	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Suranata, I Wayan Aditya	OL1.04.8	189	<i>IoT Design of Ornamental Fish Aquarium Management Could Monitor Water Conditions</i>
Surjanto, Sentot	OL1.09.4	421	<i>Optimizing Air Cargo Delivery Routes with a Modified Artificial Bee Colony</i>
Suyanto, Suyanto	OL1.08.4	372	<i>Performance Analysis of KNN and C4.5 Algorithms, with Kappa Measure Evaluation Case Study: Student Graduation Rate at Kemenkes Poltekkes Medan</i>
Suyasa, P. Wayan	OL1.05.8	242	<i>The Presence of the JOFF Formula as an Effort to Optimize the DIVAYANA Formula Ranking Results</i>
Suyuti, Ansar	OL1.07.9	353	<i>Enhancement of Voltage Quality through D-STATCOM Implementation in the Electrical Infrastructure of Semen Tonasa</i>
Swanjaya, Daniel	OL1.06.9	299	<i>Topic Modeling Using Latent Dirichlet Allocation Method Based On Child Anecdotal Record Data</i>
Syahchari, Dicky	OL1.06.1	254	<i>Analyzing the Impact of ChatGPT on Enhancing Academic Skills and Learning Concepts Among University Students in Jakarta</i>

T

Tampati, Ihsan	OL2.06.1	628	<i>Optimization of MLP-Regressor for Predicting Student's Cumulative Grade Point Average (GPA)</i>
Taufik Hidayat, Muh	OL1.03.6	125	<i>Enhanced Flood Detection on Highways: A Comparative Study of MobileNet and VGG16 CNN Models Based on CCTV Images</i>
Thathsarani, Nethmi	OL1.02.9	90	<i>A Comprehensive Software Complexity Metric Based on Cyclomatic Complexity</i>
Timadius, Ethan	OL1.05.2	207	<i>Breast Cancer Image Classification Obtained Through Dynamic Thermography using Deep Learning</i>
Tiquio, Darwin	OL2.07.3	678	<i>Pipeline Leak Classification using Machine Learning Ensemble Methods and Hyperparameter Tuning</i>
Toshwal, Manish	OL1.02.2	50	<i>Hybrid Golden Jackal-Sea Lion and Sea Horse Optimization Algorithm for Improved Keystroke Dynamics User Authentication</i>
Tran, Manh Hoang	OL2.08.3	720	<i>Smart Stick Detecting Obstacles Early Using Random Forest Algorithm</i>
Tran Dinh Nhat,	OL2.08.4	725	<i>Designing of System for Monitoring and Forecasting Air Environment Using</i>

Thang			<i>LSTM Model</i>
Tran Van, Tinh	OL2.08.3	720	<i>Smart Stick Detecting Obstacles Early Using Random Forest Algorithm</i>
	OL2.08.4	725	<i>Designing of System for Monitoring and Forecasting Air Environment Using LSTM Model</i>
Tresna, Muhammad Agung	OL1.07.5	329	<i>Performance Analysis of IoT Message Queuing Telemetry Transport Implementation in Smart Home Systems</i>
Triandini, Evi	OL1.03.1	96	<i>Kinematic and Dynamic Equations for the Design and Simulation of 2DOF PID-Controlled Exoskeleton</i>

U

Uman Putra, Dimas	OL2.07.4	684	<i>Transient Stability and Power Flow Evaluation on On-Grid Diesel and WHRPG with PV Study Case</i>
Utami, Ema	OL1.04.9	195	<i>Multi-Label Classification using BERT for Cyberbullying Detection</i>
Utomo, Denny Trias	OS1.01.6	27	<i>Enhancing Computational Strategies to Decode ChatGPT's Influence on the Critical Thinking Abilities of University Students</i>
Utomo, R	OS1.01.5	22	<i>Comparing Fuzzy Logic Controller (FLC) and Adaptive Neuro-Fuzzy Inference System (ANFIS) for Auto-Cooling System in Generator Rotor Straightening</i>

V

Vadreas, Andrew Kurniawan	OL1.04.2	154	<i>Monitoring Railway Journeys at Unauthorized Crossings in Padang City using Geographic Information System (GIS)</i>
Vidy, Vidy	OS1.01.7	33	<i>Artificial Intelligence: Investigating the Impact of Teacher's Awareness, Perception, and Learning Motivation on Learning Evaluation</i>

W

Wage, Sutarman	OL2.06.7	662	<i>Determining The Parameter K of K-Nearest Neighbors (KNN) using Random Grid Search</i>
Wahyu Ramadhan, Reza	OL1.03.9	142	<i>A Deep Feature Extraction for Hate Speech Detection using Fine-Tuned Naive Bayes</i>
Wahyuniar, Lilia	OL1.08.5	378	<i>Performance Analysis of Discrete Wavelet Transformation Method with K-Nearest Neighbor in Eye Disease Identification</i>
Waluyo, Danang	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Wanti Wulan Sari, Nariza	OS1.01.6	27	<i>Enhancing Computational Strategies to Decode ChatGPT's Influence on the Critical Thinking Abilities of University Students</i>
Wardhani, Laksmi	OL1.09.4	421	<i>Optimizing Air Cargo Delivery Routes with a Modified Artificial Bee Colony</i>
Wibowo, Ferry Wahyu	OS1.01.8	39	<i>Optimization of the Unmanned Aerial Vehicle Route Based on Chimpanzee Leader Election Optimization</i>
Wibowo, Mukti	OL1.04.7	183	<i>Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model</i>
Wibowo, Prasetyo	OL1.09.6	433	<i>A Comparative Analysis of Logistic Regression and Decision Trees for Mortality Risk Prediction using Laboratory Data</i>
Widodo, Danang	OL1.08.5	378	<i>Performance Analysis of Discrete Wavelet Transformation Method with K-Nearest Neighbor in Eye Disease Identification</i>
Wiguna, I Kadek	OL1.04.8	189	<i>IoT Design of Ornamental Fish Aquarium Management Could Monitor Water</i>

Arta			<i>Conditions</i>
Wihayati, Wihayati	OS1.01.8	39	<i>Optimization of the Unmanned Aerial Vehicle Route Based on Chimpanzee Leader Election Optimization</i>
Wijaya, Rifki	OL2.07.5	690	<i>Heart Rate Measuring System using Accelerometer And Gyroscope Sensor in Android Smartphone</i>
Wijayanto, Ahmad	OL1.09.8	445	<i>Detection Model For Potential Flooding Areas Using K-Means And Local Outlier Factor (LOF)</i>
Wijayanto, Inung	OL2.05.6	616	<i>Texture Analysis of Scalogram Image from Alcoholic EEG Signals using CNN</i>
Wijayanto, Pikir	OL1.03.5	119	<i>Indonesian Sign Language Detection for The Deaf using Convolutional Neural Network Algorithm</i>
	OL1.04.5	171	<i>Nutrient Detection In Complementary Feeding Using Convolutional Neural Network Algorithm</i>
Williamsyah, Baginda	OL2.07.5	690	<i>Heart Rate Measuring System using Accelerometer And Gyroscope Sensor in Android Smartphone</i>
Wirawan, Muhammad	OL1.09.10	457	<i>Evaluating Quality of Service: Throughput, Packet Loss, and Delay in Tree Topology with Ryu and Pox Controllers in Software Defined Networks</i>
Wongso, Reyner	OL1.05.2	207	<i>Breast Cancer Image Classification Obtained Through Dynamic Thermography using Deep Learning</i>
Wulandari, Ajeng	OL1.05.4	219	<i>Breast Cancer Detection with Multi Layer Perceptron: Unveiling Neuron Unit Dynamics in Dual Hidden Layers</i>

Y

Yahya, Muhammad	OL1.03.6	125	<i>Enhanced Flood Detection on Highways: A Comparative Study of MobileNet and VGG16 CNN Models Based on CCTV Images</i>
Yangyu, Fan	OL1.06.4	271	<i>Wavelet Entropy and Support Vector Machine multi-class fall detection based on IMU wearable sensors data</i>
Younis Altememi, Hiba	OL2.06.5	650	<i>Hybridization of Self Supervised Learning Models for Enhancing Automatic Arabic Speech Recognition</i>
Yovita, Leanna	OS1.01.4	16	<i>Examining Reliability in Delay Tolerant Networks: A Study of Protocol Behavior</i>
	OL1.04.1	148	<i>Optimizing Self-Learning Forwarding Strategies in Vehicular Named Data Network through Protocol Simplification</i>
Yuana, Kumara	OL2.05.5	611	<i>Multilingual Named Entity Recognition Model for Location and Time Extraction of Forest Fire</i>
Yunanda, Rezki	OL1.05.3	213	<i>Diabetes Risk Prediction Exploration: Uncovering Patterns and Enhancing Predictive Accuracy through Ensemble Learning</i>
Yunelfi, Putri	OL1.05.1	201	<i>Dark Web Content Exploration using Network Analysis based on Data Crawling</i>
Yuniarti, Anny	OL2.04.3	558	<i>Object Detection in Low-Light Conditions: A Comparison using YOLOv5 and YOLOv8</i>
Yuniarty, Yuniarty	OL1.07.7	341	<i>The Influence of Perceived Authenticity and EWOM on Price Sensitivity, Perceived Value, Perceived Risk, and Repurchase Intentions in E-commerce Sites</i>
Yunita, Reni	OL1.09.3	417	<i>Indonesian Dynamic Sign Language Recognition for Individuals with Sensory Disabilities using LSTM</i>

Z

Ziani, Said	OL2.05.6	616	<i>Texture Analysis of Scalogram Image from Alcoholic EEG Signals using CNN</i>
	OL2.07.5	690	<i>Heart Rate Measuring System using Accelerometer And Gyroscope Sensor in</i>

Android Smartphone

Ziyati, Houssaine	OL2.09.2	754	<i>A New Model for Securing Personal Sensitive Information Storage in Multi-Cloud</i>
Zulkarnain, Riski	OS1.01.6	27	<i>Enhancing Computational Strategies to Decode ChatGPT's Influence on the Critical Thinking Abilities of University Students</i>

ABCDEFGHIJKLMN OPQRSTU VW

A

ABCDEFGHIJKLMN OPQRSTU VW

- A CNN- based Improved Walrus Optimization Algorithm to Detect Driver Drowsiness*
- A Comparative Analysis of Logistic Regression and Decision Trees for Mortality Risk Prediction using Laboratory Data*
- A Comprehensive Software Complexity Metric Based on Cyclomatic Complexity*
- A Deep Feature Extraction for Hate Speech Detection using Fine-Tuned Naive Bayes*
- A Developed Safety Distance Model to Predict the Vehicles Traffic Flow*
- A New Model for Securing Personal Sensitive Information Storage in Multi-Cloud*
- A novel mathematical model for optimizing energy consumption in OLSRv2 routing protocol*
- A technique utilizing Machine Learning and Convolutional Neural Networks (CNN) for the identification of SQL Injection Attacks*
- Active Gate Driver with RC Snubber and Proportional-Integral (PI) Controller for Voltage Balancing of Series Connected SiC MOSFETs*
- Adoption of Blockchain Technology for Digital Heritage to Improve Heritage Security*
- Advancing Neuro-Oncological Diagnostics: A Comparative Analysis of Machine and Deep Learning Models for Brain Tumor Classification*
- An Efficient Hybrid Model for Federated Learning Systems to Deal with Medical Heterogeneous Datasets*
- Analysis and Modeling of Electroencephalography Bio Signals based on Motor Imagery for Rehabilitation*
- Analysis of Three-Phase Grid Synchronization Algorithms Performance Under Harmonic Pollution to Grid Voltage*
- Analyzing the Impact of ChatGPT on Enhancing Academic Skills and Learning Concepts Among University Students in Jakarta*
- Application of MobileNet Architecture for Pneumonia Disease Classification Based on Lung X-Ray Images*
- Area Grouping Based on Inflation During Covid-19 Using Minimum Message Length*
- Artificial Intelligence: Investigating the Impact of Teacher's Awareness, Perception, and Learning Motivation on Learning Evaluation*
- Automatic Text Review Summarization of Digital Library System Application using TextRank Algorithm and TF-IDF*

B

ABCDEFGHIJKLMN OPQRSTU VW

- Breast Cancer Detection with Multi Layer Perceptron: Unveiling Neuron Unit Dynamics in Dual Hidden Layers*
- Breast Cancer Image Classification Obtained Through Dynamic Thermography using Deep Learning*

Breast Masses in Dynamic Contrast-Enhanced Magnetic Resonance Imaging Classification Based on Combining Deep Learning and Local Binary Pattern Features

C **A B C D E F G H I K L M N O P R S T U V W**

Classification for Human Resource Talent Management Using Support Vector Machine Model

Classification Of Indonesian Rupiah Currency Using Convolutional Neural Network For Visually Impaired Individuals

Classification System of Breast Cancer using Machine Learning on Hu Moment Invariants and GLCM Features

Clustering Algorithms to Handle IoT Stream of Data

Comparative Analysis of Image Filtering for Dental Caries Image

Comparing Fuzzy Logic Controller (FLC) and Adaptive Neuro-Fuzzy Inference System (ANFIS) for Auto-Cooling System in Generator Rotor Straightening

Confronting the Challenges of Alzheimer's Diagnosis: A Deep Dive into MRI-Based Early Detection Methods

Construction of a Self-balancing Cube with Embedded Reaction Wheel Drive and Preliminary Investigation of Simple Harmonic Motion Patterns

D **A B C D E F G H I K L M N O P R S T U V W**

Dark Web Content Exploration using Network Analysis based on Data Crawling

DC Fast-Charging for Electric Vehicle with LiFePO4 Battery based on Fuzzy Logic System

Design and Simulation of a Secured Enterprise Network Architecture for All Departments at East Africa University (EAU), Somalia

Design Improved Transimpedance CMOS amplifier for optical Receiver front end

Design of Bidirectional TWDM-PON Network for High-Speed Internet Access in Industrial Zones

Designing of System for Monitoring and Forecasting Air Environment Using LSTM Model

Detection Model For Potential Flooding Areas Using K-Means And Local Outlier Factor (LOF)

Detection of DDoS Attack on Software-Defined Networking Controller Using Convolutional Neural Networks

Detection of Image Splicing and Copy-Move Forgery Using the Prewitt Operator and CNN Approach

Determination the Quality of plain X-Ray Using Fuzzy Logic in View of Voltage, Current and Exposure Time Based on Linear Regression

Determining The Parameter K of K-Nearest Neighbors (KNN) using Random Grid Search

Diabetes Risk Prediction Exploration: Uncovering Patterns and Enhancing Predictive Accuracy through Ensemble Learning

E **A B C D E F G H I K L M N O P R S T U V W**

Early Diagnosis of Diabetic Retinopathy through Optimization of Convolutional Neural Network Hyperparameters using Genetic Algorithm

Enhanced Denoising of Cervical Pre-cancerous Cell Images through Advanced Color Filtering

Enhanced Flood Detection on Highways: A Comparative Study of MobileNet and VGG16 CNN Models Based on CCTV Images

Enhancement of Voltage Quality through D-STATCOM Implementation in the Electrical Infrastructure of Semen Tonasa

Enhancing Computational Strategies to Decode ChatGPT's Influence on the Critical Thinking Abilities of University Students

Enhancing Online Learning Experience: An Ensemble Approach for Classifying Student Adaptivity Level

Enhancing Reliability in Wireless Sensor Networks through Cluster-based Optimization

Evaluating Quality of Service: Throughput, Packet Loss, and Delay in Tree Topology with Ryu and Pox Controllers in Software Defined Networks

Evaluating the Effects of Sensors Clustering on Wireless Sensor Networks Performance

Examining Reliability in Delay Tolerant Networks: A Study of Protocol Behavior

Exploration of Internal Factors Influencing the Success of Digital Projects

Extracting Gender Textual Nuances Using Text Similarity for Gender Classification Improvement

Eye Disease Classification System Based on Fundus Image Using Transfer Learning Convolutional Neural Network Model ResNet50

F

ABCDEFGHIJKLMN OPQRSTUVW

Flood Susceptibility Mapping using GIS Based on Fuzzy AHP Method in Keureuto River Basin, Aceh

Forensic Investigation of User Privacy Violation by Android Malware with Hybrid Analysis

Fungi Image Segmentation using Efficient U-Net Architecture with ImageNet Pre-trained Model

G

ABCDEFGHIJKLMN OPQRSTUVW

Gen Z's Embrace of Fintech: A Study on Customer Support and Security as Technostress Factors in e-Wallet Use in Indonesia

Generation Method of Dynamic Coverless Arabic Text Information Hiding Using First-Order Markov Chain

H

ABCDEFGHIJKLMN OPQRSTUVW

Heart Rate Measuring System using Accelerometer And Gyroscope Sensor in Android Smartphone

Hybrid Golden Jackal-Sea Lion and Sea Horse Optimization Algorithm for Improved Keystroke Dynamics User Authentication

Hybrid Model Of Unified Theory of Acceptance and Use of Technology (UTAUT), HOT, And Contextual Variables For Analyzing Farmers' Behavior Towards Internet Of Things (IoT)-Based Agricultural Technology

Hybridization of Self Supervised Learning Models for Enhancing Automatic Arabic Speech Recognition

I**ABCDEFGHIJKLMN OPQRSTU VW**

Implementation of Distributed Wide Area Monitoring System Server Configuration on Java-Madura-Bali Power System

Implementation of the EfficientNet Model for Identification of Wild Edible Plants

Implementation P-Wave Detection in a Seismic Waveform Using PhaseNet

Improve the Quad copter Stability by Using An Adaptive Fuzzy Inference Neural Network (AFINN)

Improved Accuracy of Decision Tree with XGBoost Technique in Animal Disease Diagnosis

Indonesian Dynamic Sign Language Recognition for Individuals with Sensory Disabilities using LSTM

Indonesian Sign Language Detection for The Deaf using Convolutional Neural Network Algorithm

Integrating blockchain with IoT-edge-cloud network for tracking offloaded task

Investigating Generation Z's Technostress During Fintech Adoption: Security and Customer Service with Theory of Planned Behavior in Indonesia

IoT Design of Ornamental Fish Aquarium Management Could Monitor Water Conditions

K**ABCDEFGHIJKLMN OPQRSTU VW**

Kinematic and Dynamic Equations for the Design and Simulation of 2DOF PID-Controlled Exoskeleton

L**ABCDEFGHIJKLMN OPQRSTU VW**

LabVIEW Integrated with Python Machine Learning for DC Motor Drive

Leveraging IndoBert for CyberBullying Classification on Social Media

Light Fidelity Internet of Things based for Medical Applications

Lightweight Convolutional Neural Network (CNN) and Long Short-Term Memory Network (LSTM) for Dynamic Hand Gesture Recognition

Localizing Copy-Move Manipulations in Digital Images Using U-Net Architecture with Various Backbone Models

Long Short-Term Memory Utilization for Non-Invertible Transformation Face Biometric Recognition System

Low-Cost Blind Spot Detection System Based on Lite Object Detection Algorithm and Limited Resources Hardware

M**ABCDEFGHIJKLMN OPQRSTU VW**

Maximum Power Point Tracking (MPPT) using Differential Evolution Algorithm on the SEPIC Converter for Solar Panels under Partially Shaded Conditions

Model Development in Recognizing Affect through Facial Expressions of Students' Engagement in Synchronous Class

Modified Positive Output Super Lift Luo Converter Based on Switched Capacitor Technique

Modified Recommender Algorithm based on Technique for Order of Preference by Similarity to Ideal Solution (TOPSIS) Methodology with Entropy Weighting Method (EWM)

Monitoring Railway Journeys at Unauthorized Crossings in Padang City using Geographic Information System (GIS)

Multi-Channel Fusion Model for Data Logs Analysis and Anomaly Detection in Data Centers

Multi-Label Classification using BERT for Cyberbullying Detection

Multi-Organ 3D Reconstruction and Virtual Reality Visualization Using Graph-Based Segmentation

Multilingual Named Entity Recognition Model for Location and Time Extraction of Forest Fire

N **A B C D E F G H I K L M N O P R S T U V W**

Nutrient Detection In Complementary Feeding Using Convolutional Neural Network Algorithm

O **A B C D E F G H I K L M N O P R S T U V W**

Object Detection in Low-Light Conditions: A Comparison using YOLOv5 and YOLOv8

OCTm: Custom Deep Learning Model for Diagnosing Retinal Diseases

Opinion Classification on MSME Social Media Comments using Support Vector Machine and Random Forest Models

Optimal Decision Support System Model for Breast Cancer Diagnosis

Optimization of MLP-Regressor for Predicting Student's Cumulative Grade Point Average (GPA)

Optimization of the Unmanned Aerial Vehicle Route Based on Chimpanzee Leader Election Optimization

Optimizing Air Cargo Delivery Routes with a Modified Artificial Bee Colony

Optimizing Cloud Storage Costs: Introducing the Pre-Evaluation-Based Cost Optimization Mechanism (PECSCO)

Optimizing Face Recognition Accuracy with HOG Features and SVM Classifier: A Study on ORL and Yale Databases

Optimizing Rice Variety Recognition Through Transfer Learning with Pretrained ResNet Models

Optimizing Self-Learning Forwarding Strategies in Vehicular Named Data Network through Protocol Simplification

P **A B C D E F G H I K L M N O P R S T U V W**

Performance Analysis of Caraga State University's Network Infrastructure: A Software-Defined Networking Approach

Performance Analysis of Discrete Wavelet Transformation Method with K-Nearest Neighbor in Eye Disease Identification

Performance Analysis of Heart Disease Prediction using Kernels in Support Vector Machine Model

Performance Analysis of IoT Message Queuing Telemetry Transport Implementation in Smart Home Systems

Performance Analysis of KNN and C4.5 Algorithms, with Kappa Measure Evaluation Case Study: Student Graduation Rate at Kemenkes Poltekkes Medan

Performance Evaluation of Equivalent Circuit Model Parameter Extraction Methods on Lithium-Ion Battery

Performance Evaluation of Film Bulk Acoustic wave Resonator with different piezoelectric materials

Performance Improvement of Apriori Algorithm with Transaction Reduction and Hash Based Approach

Performance of Term Frequency - Inverse Document Frequency and K-Means in Government Service Identification

Pipeline Leak Classification using Machine Learning Ensemble Methods and Hyperparameter Tuning

Polkadot Cryptocurrency Close Price Prediction Using Machine Learning

Predicting the Severity of Parkinson's Disease Based on Voice Analysis Using Deep Learning

Pricing Strategies Using Design of Experiment in Online and Offline Supply Chain

Proposing a Support System to Identify Stroke Patients Using RetinaFace and Resnet50 Model

R **A B C D E F G H I K L M N O P R S T U V W**

Random Forest With Adaptive Synthetic Sampling- Nominal Continuous and Cost Sensitive Learning on Imbalanced Binary Classification

Reduction of Microarray Data Dimensions to Enhance Performance of Naïve Bayes in Classification

Regression Modeling for Predicting House Prices in Java Island

S **A B C D E F G H I K L M N O P R S T U V W**

Sentiment Analysis Using K-NN Algorithm Through Random Search Cross Validation Approach

Skin Melanoma diagnoses using machine learning and ABCD rule

Smart Stick Detecting Obstacles Early Using Random Forest Algorithm

Software Defect Detection Using Optimized Support Vector Machine Based on Grey Wolf Optimizer with Random Walk

Solar Power Generation Forecasting Based on Machine Learning Techniques

State of Charge Estimation of Lithium Ion Battery Using Coulomb Counting Method Based on Raspberry Pi

T **A B C D E F G H I K L M N O P R S T U V W**

Texture Analysis of Scalogram Image from Alcoholic EEG Signals using CNN

The Influence of Perceived Authenticity and EWOM on Price Sensitivity, Perceived Value, Perceived Risk, and Repurchase Intentions in E-commerce Sites

The Presence of the JOFF Formula as an Effort to Optimize the DIVAYANA Formula Ranking Results

Topic Modeling Using Latent Dirichlet Allocation Method Based On Child Anecdotal Record Data

Transfer Learning using IndoBERT with Long Short-Term Memory Classifier for Detection of Suicide Ideation Themed

Transient Stability and Power Flow Evaluation on On-Grid Diesel and WHRPG with PV Study Case

U **A B C D E F G H I K L M N O P R S T U V W**

Use of an Expert System to Diagnose and Provide Solutions for Pests and Diseases in Hydroponic Mustard Plants Using Certainty Factor and Forward Chaining Methods

V **A B C D E F G H I K L M N O P R S T U V W**

Viral Melodies: Exploring the Factors Influencing Music Virality in TikTok Engagement

VVC Encoded Video Transmission over 5G-based Multiple Access Systems

W **A B C D E F G H I K L M N O P R S T U V W**

Wastewater Aeration process based Cloud-SCADA/PLC System

Wavelet Entropy and Support Vector Machine multi-class fall detection based on IMU wearable sensors data

LabVIEW Integrated with Python Machine Learning for DC Motor Drive

1st Mana Poyai

Department of Mechatronics
Engineering, Faculty of Technical
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Abstract— This study presents a new technique that integrates LabVIEW and Python to enhance the control of DC motor drives through the utilization of machine learning methods. The objective of our research is to leverage LabVIEW's graphical programming interface in combination with the Scikit-learn Python package to train a Polynomial Regression model. The goal is to forecast Pulse Width Modulation (PWM) values at desired Rotations per Minute (RPM) of a DC motor. The accuracy and reliability of the trained model are evaluated using performance assessment metrics such as the R-squared (R^2) coefficient of determination and the Root Mean Square Error (RMSE). The R^2 score assesses the precision of the model's fit, whereas the RMSE quantifies the model's predictive capability by comparing observed and predicted data. This research also includes a comparison between the machine learning technique for DC motor drive and conventional PID control. The findings illustrate the successful integration of LabVIEW and Python in managing DC motor drives, achieving low overshooting and faster attainment of the set RPM point compared to classical PID control. This emphasizes machine learning's capacity to enhance control strategies; the application of Polynomial Regression yields promising results, demonstrating its effectiveness in predicting PWM and RPM values with an R^2 value ranging from 96% to 98% and RMSE within 19.

Keywords—Labview, Python, Scikit-learn, Polynomial Linear Regression, DC motor Drive, EasyEda, Machine Learning, RMSE, R^2 , PID

I. INTRODUCTION

The incorporation of various technologies has played a crucial role in enhancing the capabilities of engineering systems in recent years. The combination of hardware and software, along with the utilization of machine learning techniques, has created opportunities to improve the effectiveness and capability of different applications. Our project aims to integrate LabVIEW [1] and Python [2] to effectively drive and control DC motors using an intelligent machine learning framework. DC motors are essential components in a wide range of industrial applications, including robotics and automation systems [3]. Our work intends to leverage the benefits of LabVIEW, a versatile graphical programming environment, and Python, a sophisticated language extensively used in data science and machine learning [4], to create a control system based on a machine learning approach. The control system employs machine learning techniques to fine-tune and verify its performance using statistical tools such as R^2 for machine learning optimization, and RMSE for comparing predictions with actual outcomes. Additionally, the performance of the machine learning approach is compared with the conventional PID approach.

II. LITERATURE REVIEW

A. Machine Learning Techniques

Machine learning has progressed as a groundbreaking field, offering powerful tools to depict complex relationships

inside data. It's a branch of artificial intelligence (AI), allows systems to autonomously learn and refine their performance based on experience, eliminating the need for human intervention. This technology enhances the predictive capabilities of software applications without the necessity for explicit programming. Fundamentally, machine learning focuses on creating algorithms that analyze input data and make predictions using statistical methods. In recent years, machine learning has become highly popular, with its algorithms being utilized in diverse areas such as object detection, pattern recognition, text interpretation, and various research disciplines. The main aim of machine learning is to teach computers to leverage data to address specific problems efficiently [5]

In recent years, Machine Learning (ML) algorithms have been increasingly implemented, though some solutions may simply replace one problem with another. Common types of machine learning include supervised learning, unsupervised learning, and reinforcement learning [6].

Supervised learning involves using a dataset comprised of pre-labeled target data input variables (training data) [7]. This method generates a mapping function to associate inputs with the desired outputs based on these input variables. The model parameters are adjusted until it reaches a satisfactory level of accuracy with the training data. This type of learning allows for predictions based on a known dataset (training dataset), which includes input variables (X) and output/response variables (Y). These variables are essential for developing a model that predicts the value of the response variable (Y) for new, unseen data. In supervised learning, an algorithm is designed to learn the mapping function from the input variables (X) to the output/response variable (Y). The mapping function can be expressed as:

$$Y = f(X) \quad (1)$$

Unsupervised learning utilizes only training data without associated outcome data, meaning the data is not pre-classified. This approach identifies existing patterns or clusters within datasets without the need for supervision. The model autonomously discovers information to produce output, primarily dealing with unlabeled data. One of the most common methods in unsupervised learning is cluster analysis, which is used to identify structures or patterns within a pool of unclassified data [8].

Reinforcement learning involves conditioning a machine to take actions based on specific decisions, resulting in rewards or feedback. The machine is programmed to draw from past experiences to identify the most beneficial actions. This method enables the machine to take appropriate actions in given situations to maximize rewards. Learning occurs through interaction with the environment by agents or learners, who receive rewards for correct actions and penalties for incorrect ones. The agent learns without human intervention by aiming to maximize rewards and minimize penalties. This system of

rewards and punishments effectively trains the algorithms [9].

B. Algorithm of Machine Learning

Decision tree algorithms are primarily utilized for classification problems. They divide attributes into two or more classes based on their values. Each tree consists of nodes and branches, where each node represents an attribute of the group, and each branch corresponds to a specific value of that attribute [10].

Artificial neural networks model themselves after the configuration of biological neurons and operate using a supervised approach to machine learning. They consist of artificial neurons interconnected with weighted connections between units. These networks are recognized for their capability in parallel distributed computing [11].

Data Clustering Algorithms partition objects into different groups or clusters based on similarities among items within each subset. It is an unsupervised learning method commonly referred to as clustering or hierarchical and network partitioning techniques [12].

Regression algorithms make predictions by modeling the relationship between variables using an error measure, predicting continuously varying values. This statistical tool helps identify the relationship between dependent and independent variables and is used to model a target value that relies entirely on independent predictors. Regression analysis is employed to find correlations between two variables, though it cannot determine cause-and-effect relationships. Unlike classification algorithms, which categorize output variables, regression focuses on predicting continuous outcomes [13].

Polynomial regression [14] is a type of regression algorithm which has versatile technique that is particularly valuable for assessing the relationship between data, especially when implemented using the Scikit-learn framework. This approach is highly significant in numerous disciplines [15].

C. Polynomial Regression Fundamentals

Polynomial regression, an extension of linear regression, is adept at capturing intricate nonlinear relationships. The literature extensively covers its fundamental principles, showcasing its capability to model data with higher degrees of complexity [16]. The general form of the polynomial regression equation is expressed as a polynomial function of the independent variable, allowing researchers to flexibly adapt models to the shape of the data.

D. Scikit-learn a Robust Toolkit for Polynomial Regression

Scikit-learn, a widely used machine learning library in Python, provides a comprehensive set of tools for implementing polynomial regression models. Researchers have embraced Scikit-learn for its efficient implementation and integration capabilities, enabling the seamless deployment of polynomial regression in diverse applications [17].

E. Pulse Width Modulation (PWM) for DC Motor Drives

Pulse Width Modulation (PWM) is a vital technology extensively used in the realm of DC motor drives to control the velocity and orientation of direct current (DC) motors [18]. This technology is crucial for achieving accurate control over motor performance, enabling efficient and dynamic modifications in a wide range of applications, including robotics and industrial automation. Pulse Width Modulation (PWM) functions by swiftly alternating a signal between an active state and an inactive one at a consistent frequency. The

duty cycle is defined as the ratio of the duration in which the signal is in the "on" state (high voltage) to the overall period of the signal. Pulse Width Modulation (PWM) is a technique that allows for precise control of the average power output to a DC motor by adjusting the duty cycle. Pulse Width Modulation (PWM) enables speed control by adjusting the proportion of time the signal is on compared to the total time of the signal [19]. As the duty cycle increases, the motor experiences a greater average voltage, leading to an increase in speed. On the other hand, a decreased duty cycle results in a decrease in the average voltage and a reduction in the motor speed. This system enables seamless and uninterrupted speed regulation in DC motor drives.

III. RESEARCH METHODOLOGY

A. Hardware Design

The web-based software EasyEDA [20] was employed to create a schematic and PCB, integrating components such as a controller (ESP8266), opto-coupler isolator, IGBT drive, power regulator, and various discrete elements. This board is designed to drive the DC motor and record RPM speed for machine learning data collection. The schematic of this board is illustrated in Fig. 1 (a), utilizing the ESP8266 controller embedded with C code firmware. It functions as the bridge channel interfacing through the USB port between the LabVIEW-Python-based PC software, the DC motor drive, and the encoder reader. The board utilizes the IGBT as the switching drive for the DC motor and an opto-coupler to isolate the microcontroller drive signal from the electromagnetic induction generated by the DC motor. Voltage regulators are employed to regulate the power supply from the DC motor to match with the supply of the ESP8266 microcontroller, opto-coupler, and other components. The functionality of this PCB includes an RPM reading feature through the encoder, facilitating the measurement of the DC motor speed for data collection in the machine learning training module. The PCB shown in Fig.1 (b) is generated from this schematic using the same EasyEDA software, with the 3D view shown in Fig. 1 (c). The assembled PCB, featuring components for a complete PCBA for the DC motor drive with data collection for machine learning, is depicted in Fig. 1 (d).

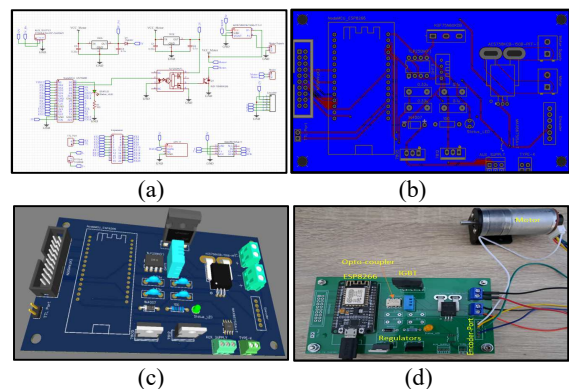


Fig. 1 (a) Schematic of DC Motor Drive, (b) PCB layout of DC Motor Drive, (c) PCB (3D) of DC Motor Drive, (d) PCBA of DC Motor Drive

B. Software System Design

LabVIEW is primarily used as the graphical user interface (GUI) for this system, sending PWM signals to the ESP8266 controller to control the IGBT, thereby turning the DC motor on and off. Additionally, LabVIEW is employed to read the RPM speed of the DC motor through the encoder. The interfacing between the DC motor drive board and the PC is achieved through the USB port. The dataset of PWM and RPM values is recorded in a text file for further processing in

Python's text-based coding software. This Python software is designed to invoke the Scikit-learn library's train module, establishing the relationship between PWM (%) and RPM, with the R-Squared value calculation for the model's predictive accuracy. Then, after the LabVIEW software is triggered by the user to predict the PWM (%) value needed to be sent to the DC motor drive board for achieving the desired RPM, LabVIEW will call the Python to predict value. This function predicts the PWM(%) value required for the specified RPM using the trained model previously executed. In addition, this LabVIEW-Python integrated software also includes a test mode to collect the data for evaluating the trained model using the Root-mean-square deviation (RMSE) value. This value represents the difference in error between the trained model and the real values generated from the predict function. The overview flow diagram of this software system is shown as the Fig. 2.

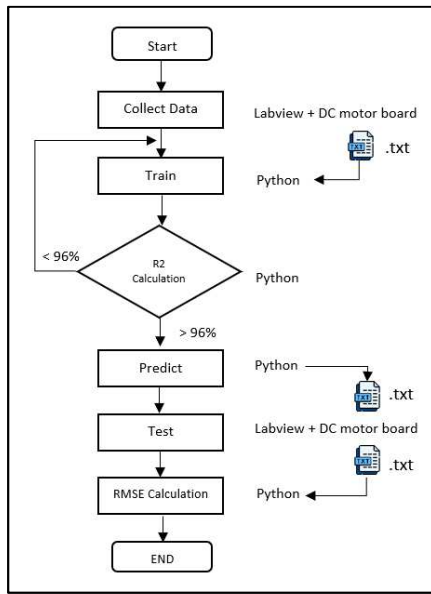
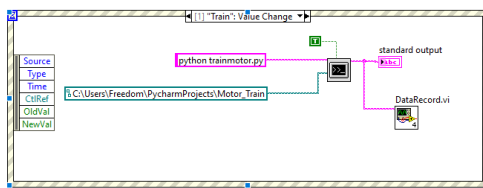
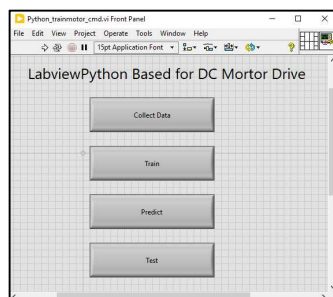


Fig. 2 Software Flow Diagram

The interface between LabVIEW and Python is established through the CMD tool as shown in Fig. 3 (a) and the user interface is shown as Fig. 3 (b), which calls the Python script and facilitates the interchange of data with a text-based file.



(a)



(b)

Fig. 3 (a) Labview Call Python Script
(b) Labview User Interface

C. Polynomial Regression

The train model is used the polynomial method to find the relation between the input and output as the equation below.

$$Y = \beta_0 + \beta_1 X + \beta_2 X^2 + \dots + \beta_n X^n \quad (2)$$

Where Y is the predicted output, X is the input variable and $\beta_0, \beta_1, \dots, \beta_n$ are the coefficients.

D. RMSE Calculation for Model Evaluation

The Root Mean Square Error (RMSE) is used to objectively evaluate the accuracy of machine learning models by comparing their predictions to the actual values. The equation for Root Mean Square Error (RMSE) is provided as follows.

$$RMSE = \sqrt{\frac{1}{N} \sum_{i=1}^N (Y_{actual,i} - Y_{predict,i})^2} \quad (3)$$

Where N is the number of observation, $Y_{actual,i}$ is the actual value, $Y_{predict,i}$ is predict value.

IV. RESULTS AND DISCUSSIONS

A. Machine Learning DC Motor Train and Drive

The LabVIEW-based software is executed to send the PWM value as a percentage to the ESP8266, which drives the IGBT in PWM mode to generate power for the DC motor. It also records the RPM value of the DC motor sent back from the encoder along with the PWM (%) value applied to the DC motor. The X-Y graph illustrating the relationship between the PWM (%) and RPM values, plotted by LabVIEW, is shown in Fig. 4. This graph demonstrates that the PWM (%) and RPM values exhibit unique characteristics under different conditions. For this experiment, two models of DC motors are used, 25GA371 (12VDC, 1000 rpm) and GA25370 (6VDC, 1360 rpm), under two conditions: no load and with load. The systems used are shown in Fig. 5.

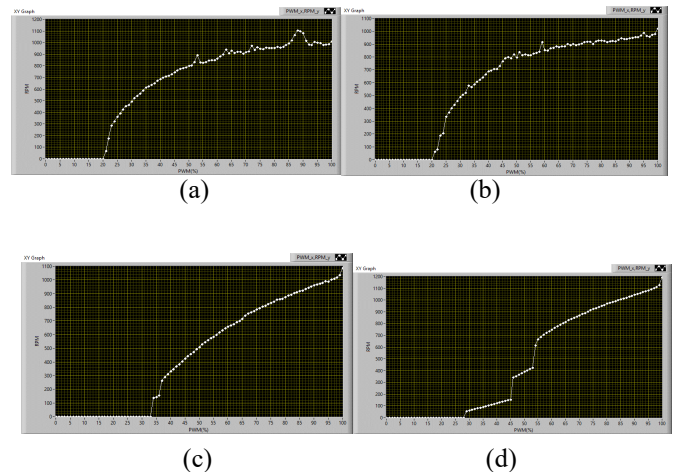


Fig. 4 The X-PWM(%), Y-RPM graph plotted by LabVIEW shows the relationship between the PWM(%) and the RPM values read back from the encoder : (a) 25GA371 DC Motor without load, (b) 25GA371 DC Motor with load, (c) GA25370 DC Motor without load, (d) GA25370 DC Motor with load



Fig. 5 (a) 25GA371 DC Motor without load, (b) 25GA371 DC Motor with load, (c) GA25370 DC Motor without load, (d) GA25370 DC Motor with load

Then, after recording the PWM (%) and RPM values of the DC motor, the Python code is used to train the model with a polynomial degree from 1 to 4 from the Scikit-learn library. The fitted model is plotted as shown in Fig. 6 to 9, along with the calculation of the R^2 value. Which, it seems that a polynomial of degree 4 fits well, as indicated by the high R^2 score [21] at around 96 to 98%. And, the summary of R^2 is shown in the Table I.

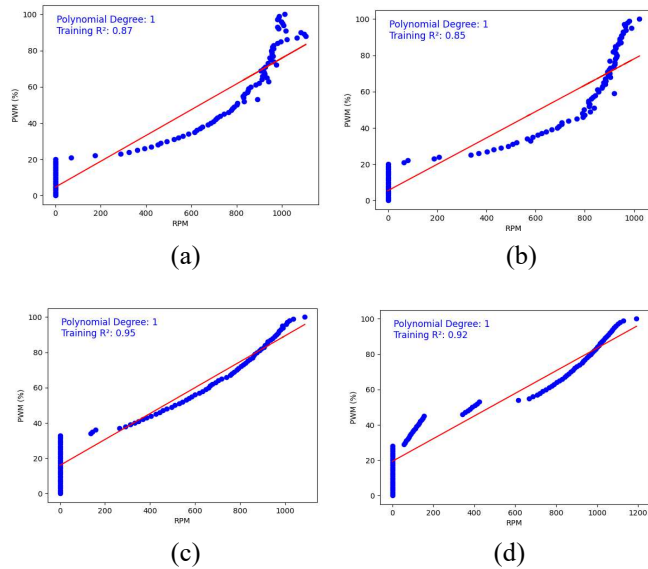


Fig.6 Polynomial plot degree 1 with trend line between RPM and PWM (%), (a) 25GA371 no load, (b) 25GA371 with load, (c) GA25-370 no load, (d) GA25-370 with load

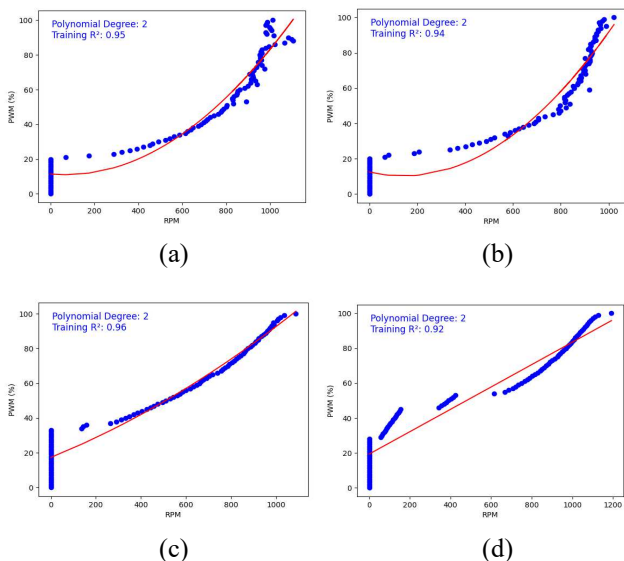


Fig.7 Polynomial plot degree 2 with trend line between RPM and PWM (%), (a) 25GA371 no load, (b) 25GA371 with load, (c) GA25-370 no load, (d) GA25-370 with load

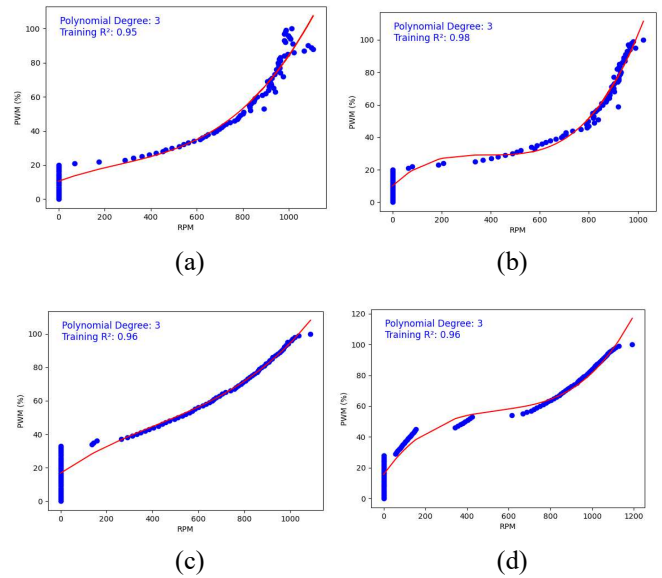


Fig.8 Polynomial plot degree 3 with trend line between RPM and PWM (%), (a) 25GA371 no load, (b) 25GA371 with load, (c) GA25-370 no load, (d) GA25-370 with load

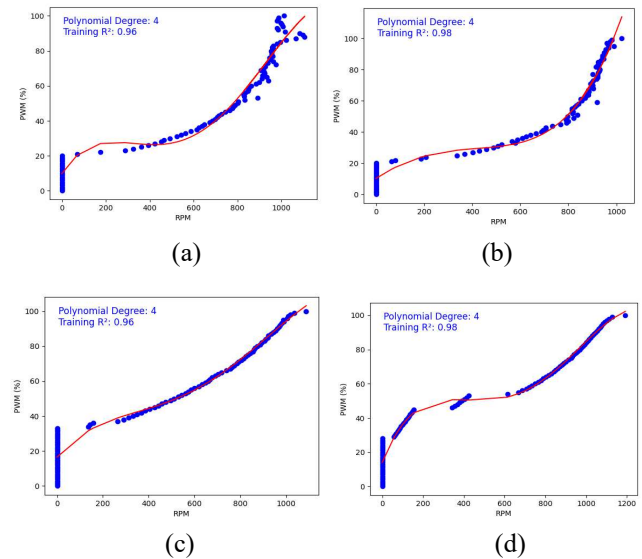


Fig.9 Polynomial plot degree 4 with trend line between RPM and PWM (%), (a) 25GA371 no load, (b) 25GA371 with load, (c) GA25-370 no load, (d) GA25-370 with load

TABLE I. R^2 SUMMARY OF POLYNOMIAL DEGREE 1 TO 4

System	Condition	Polynomial Degree			
		1	2	3	4
25GA371	No load	87%	95%	95%	96%
25GA371	No load	85%	94%	98%	98%
GA25-370	With load	95%	96%	96%	96%
GA25-370	With load	92%	92%	96%	98%

And, after completing the training, the test command from LabVIEW is executed to compare the predicted values with the actual values and observe the error, which is shown as Table II to Table V and the Root-mean-square error (RMSE) [22] value is calculated.

TABLE II. RMSE CALCULATION BETWEEN DESIRE RPM VS. ACTUAL RPM 25GA371 NO LOAD

Desire RPM	PWM (%) Predict	Actual RPM			Average	SD	Diff
		1	2	3			
400	36.85	430	435	441	435	5	35
500	40.78	489	492	494	492	3	-8
600	45.18	593	594	595	594	1	-6
700	50.38	683	683	686	684	2	-16
800	56.62	780	780	781	780	1	-20
900	64.09	893	894	896	894	1	-6
RMSE							18

TABLE III. RMSE CALCULATION BETWEEN DESIRE RPM VS. ACTUAL RPM 25GA371 WITH LOAD

Desire RPM	PWM (%) Predict	Actual RPM			Average	SD	Diff
		1	2	3			
400	29.24	390	406	400	399	8	-1
500	30.54	501	513	495	503	9	3
600	33.21	600	611	600	604	6	4
700	39.30	710	719	705	711	7	11
800	51.28	801	798	795	798	3	-2
900	71.98	920	929	950	933	16	33
RMSE							14

TABLE IV. RMSE CALCULATION BETWEEN DESIRE RPM VS. ACTUAL RPM GA25-370 NO LOAD

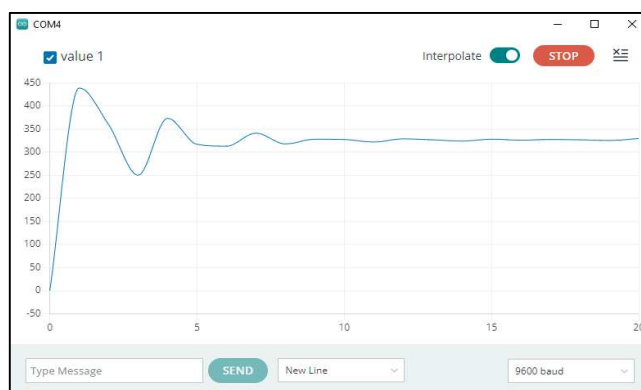
Desire RPM	PWM (%) Predict	Actual RPM			Average	SD	Diff
		1	2	3			
400	44.38	397	392	403	397	6	-3
500	48.92	501	491	509	501	9	1
600	54.90	601	600	598	600	2	0
700	62.72	717	707	707	710	6	10
800	72.32	795	793	797	795	2	-5
900	83.17	921	897	899	906	14	6
RMSE							5

TABLE V. RMSE CALCULATION BETWEEN DESIRE RPM VS. ACTUAL RPM GA25-370 WITH LOAD

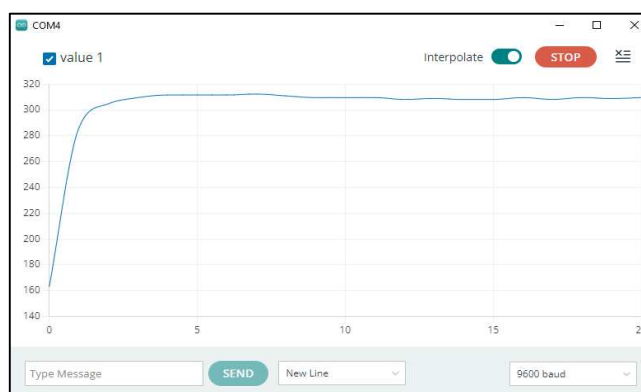
Desire RPM	PWM (%) Predict	Actual RPM			Average	SD	Diff
		1	2	3			
400	50.59	450	416	414	427	20	27
500	50.40	473	473	501	482	16	-18
600	51.78	560	610	599	590	26	-10
700	55.93	674	712	679	688	21	-12
800	63.24	769	802	767	779	20	-21
900	73.26	929	915	922	922	7	22
RMSE							19

B. Machine Learning DC Motor Drive Comparing with Conventional PID Control

In the present study, the DC motor drive system, which incorporates the machine learning concepts discussed in the previous experiment from the earlier section, is meticulously compared with a traditional Proportional-Integral-Derivative (PID) control approach [24]. This comparison is conducted under identical conditions, specifically using the 25GA371 motor under no load. The performance evaluation involves capturing the revolutions per minute (RPM) of the motor over a specified time interval, immediately after the command is issued from the PC to achieve a particular RPM. The resulting data, as illustrated in Fig. 12, reveals that the motor drive employing the machine learning method exhibits a significantly lower overshoot in RPM compared to the conventional PID control. Furthermore, the machine learning-based drive achieves the desired RPM in a noticeably shorter duration. This underscores the enhanced efficiency and responsiveness of the machine learning approach over the conventional PID method in controlling the DC motor drive.



(a)



(b)

Fig. 12 Graph of RPM speed on y-axis and time (sec) on x-axis (a) Conventional PID control for DC motor drive (b) Machine Learning control for DC motor drive

V. CONCLUSION

This study successfully demonstrated the combination of LabVIEW and Python to enhance the capabilities of DC motor drive control. Using the Scikit-learn Python package, we employed polynomial regression as a machine learning technique [23] to predict the PWM (Pulse Width Modulation) percentage command required to achieve the desired speed (RPM) of a DC motor. This approach was compared with conventional PID control, which typically has higher overshoot and requires more time to reach the target RPM value. The conventional method also involves complex fine-tuning of P, I, and D values to reduce overshoot and quickly reach the RPM set point. The machine learning concept introduced in this paper addresses these issues. The smooth interface between LabVIEW and Python enabled rapid data transmission and model training, signifying a significant advancement in control system design. Polynomial regression yielded positive results in predicting the PWM % value. The accuracy of the model was evaluated by comparing the observed and predicted values, utilizing the Root Mean Square Error (RMSE). The attained RMSE is within 19 serves as a benchmark for assessing the predictive capabilities of our integrated system. This study establishes a solid foundation for the partnership between LabVIEW and Python in the realm of machine learning-driven control systems.

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