

# INTERNATIONAL CONFERENCE



The Second International Conference on  
Engineering and Technology Development

# 2<sup>nd</sup> ICETD 2013

27, 28, 29 August 2013, Bandar Lampung, Indonesia



**PROCEEDINGS**



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Hosted by :

Faculty of Engineering and Faculty of Computer Science,  
Bandar Lampung University (UBL), Indonesia

# 2<sup>nd</sup> ICETD 2013

THE SECOND INTERNATIONAL CONFERENCE  
ON ENGINEERING AND TECHNOLOGY DEVELOPMENT

28 -30 January 2013  
Bandar Lampung University (UBL)  
Lampung, Indonesia

## PROCEEDINGS

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## PREFACE

The Activities of the International Conference is in line and very appropriate with the vision and mission of Bandar Lampung University (UBL) to promote training and education as well as research in these areas.

On behalf of the Second International Conference on Engineering and Technology Development ( 2<sup>nd</sup> ICETD 2013) organizing committee, we are very pleased with the very good response especially from the keynote speaker and from the participans. It is noteworthy to point out that about 80 technical papers were received for this conference.

The participants of the conference come from many well known universities, among others : University Kebangsaan Malaysia – Malaysia, APTIKOM – Indonesia, Institut Teknologi sepuluh November – Indonesia, Surya Institute – Indonesia, International Islamic University – Malaysia, STMIK Mitra Lampung – lampung, Bandung Institut of Technology – Bandung, Lecture of The Malahayati University, B2TP – BPPT Researcher – lampung, Starch Technology Center – Lampung, Universitas Islam Indonesia – Indonesia, Politeknik Negeri Malang – Malang, University of Kitakyushu – Japan, Gadjah Mada University – Indonesia, Universitas Malahayati – Lampung, Lampung University – lampung, Starch Technology Center – Lampung, Universitas Riau – Riau, Hasanuddin University – Indonesia, Diponegoro University – Indonesia, King Abdulaziz University – Saudi Arabia, Parahyangan Catholic University – Indonesia , National Taiwan University– Taiwan, Surakarta Christian University – Indonesia, Sugijapranata Catholic University – Indonesia, Semarang University – Indonesia, University of Brawijaya – Indonesia, PPKIA Tarakanita Rahmawati – Indonesia, Kyushu University, Fukuoka – Japan, Science and Technology Beijing – China, Institut Teknologi Sepuluh Nopember – Surabaya, Researcher of Starch Technology Center, Universitas Muhammadiyah Metro – Metro, National University of Malaysia – Malaysia.

I would like to express my deepest gratitude to the International Advisory Board members, sponsor and also to all keynote speakers and all participants. I am also gratefull to all organizing committee and all of the reviewers who contribute to the high standard of the conference. Also I would like to express my deepest gratitude to the Rector of Bandar Lampung University (UBL) who give us endless support to these activities, so that the conference can be administrated on time

Bandar Lampung, 29 August 2013-08-26

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## Table Of Content

Organizing Committee .....	i
Table Of Content.....	v
Keynote Speaker	
1. Recent Advances in Biofuel Cell and Emerging Hybrid System <b>Abdul Aziz Ahmad and Raihan Othman</b> .....	1
2. Waste Utilization Study Tailing Gold Mine in Way Linggo-Lampung, as Fine Aggregate Materials for Producing Mortar Materials based on concept of Green Technology <b>Lilies Widodojoko &amp; Susilawati</b> .....	8
3. Infrastructure Health Monitoring System (SHM) Development, a Necessity for Maintance and Investigation <b>Prof. Dr. Priyo Suprobo, Faimun, Arie Febry</b> .....	17
4. Four Phases Quality Function Deployment (Qfd) By Considering Kano Concept, Time And Manufacturing Cost <b>Prof. Dr. Moses L Singgih, Dyah L. Trenggonowati, Putu D. Karningsih</b> ....	22



Speaker

1. Comparative Analysis for The Multi Period Degree Minimum Spanning Tree Problem  
**Wamiliana, Amanto, and Mustofa Usman**..... 39
2. Choosing The Right Software In Supporting The Successful of Enterprise ERP Implementation  
**Yodhie Yuniarthe, Idris Asmuni**..... 44
3. Climate Adaptive Technology In Maintaining Vernacularism Of Urban Kampong Case study: Kampung Adat (Indiginous) Mahmud, Bandung District, West Java  
**Marcus Gartiwa**..... 50
4. The Prospect Of Diesohol In Facing Fossil Fuel Crissis  
**M.C. Tri Atmodjo**..... 63
5. The Potential Of Agriculture And Forestry Biomass Wastes As Source Of Bioenergy  
**Hardoyo**..... 66
6. The Importance of Education Facility as Sustainable Urban Generation Tool  
**Fritz Akhmad Nuzir, Haris Murwadi and Bart Julien Dewancker** ..... 71
7. The implementation of Secton Method for Solving Systems of Non Linear Equations  
**Nur Rokhman** ..... 80
8. Quality Control Analysis Into Decrease The Level Defects On Coffee Product  
**Heri Wibowo, Sulastri and Emy Khikmawati** ..... 85
9. Public Transpotion Crisis In Bandar Lampung  
**Ida Bagus Ilham Malik** ..... 89
10. Geospatial Analysis of Land Use Change in Way Kuripan Watershed, Bandar Lampung City  
**Candra Hakim Van Rafi'1., Dyah Indriana Kusumastuti2., Dwi Jokowinarno**..... 99
11. Material Utilization Technology Of Agriculture And Forestry Waste  
**Hardoyo**..... 105
12. The Supply Chain System Of Cassava On The Tapioca Industry  
**Hardoyo**..... 108
13. Glass Technology In Natural Light Glasses On Aperture Element In The Architecture World  
**Muhammad Rija & MT Pedia Aldy** ..... 113

14. An Eksperimental Permeable Asphalt Pavement Using Local Material Domato Stone On Quality Of Porous Asphalt  
**Firdaus Chairuddin, Wihardi Tjaronge, Muhammad Ramli, Johannes Patanduk** ..... 117
15. Coordination Of Architectural Concepts And Construction Systems  
**Eddy Hermanto.** ..... 129
16. Seismic Assessment of RC Building Using Pushover Analysis  
**Riza Ainul Hakim.**..... 136
17. Viscosity and Liquidity Index Relation for Elucidating Mudflow Behavior  
**Budijanto Widjaja and Shannon Hsien-Heng Lee.**..... 143
18. The Use of Pozzolanic Material for Improving Quality of Strontium Liquid Waste Cementation in Saline Environment during Nuclear Waste Immobilization Process  
**Muhammad Yusuf, HayuTyasUtami, Tri SulistiyoHariNugroho, SusetyoHarioPutero** ..... 148
19. Geospatial Analysis Of Land Use And Land Cover Changes For Discharge At Way Kualagaruntang Watershed In Bandar Lampung  
**Fieni Yuniarti, Dyah Indriana K, Dwi Joko Winarno.**..... 153
20. Wifi Network Design For High Performance  
**Heru Nurwarsito, KasyfulAmron,BektiWidyaningsih** ..... 161
21. Studi on The Efficiency Using Nature Materials in The Structural Elements of Reinforced Concrete Beam  
**Yasser, Herman Parung, M. Wihardi Tjaronge, Rudy Djamaluddin.**..... 167
22. The Research Of Slow Release Nitrogen Fertilizer Applied In Sugarcane (Saccharum Officinarum) For Green Energy Bioethanol  
**M.C. Tri Atmodjo, Agus Eko T. Nurul Rusdi, Sigit Setiadi, and Rina.**..... 179
23. Energy Utilization Technology Of Agriculture And Forestry Waste  
**Hardoyo.**..... 185
24. Implementation Of Fuzzy Inference System With Tsukamoto Method For Study Programme Selection  
**Fenty Ariani and Robby Yuli Endra.** ..... 189
25. The Analysis of Video Conference With ITU Standarization (International Telecommunication Union) That Joining in Inherent At Bandar Lampung University  
**Maria Shusanti F, Happy Reksa** ..... 201

26. The E-internal audit iso 9001:2008 based on accreditation form assessment matrix in study program for effectiveness of monitoring accreditation <b>Marzuki, Maria Shusanti F.</b> .....	207
27. The Developing Of e-Consultations For Effectiveness of Mentoring Academy <b>Ahmad Cucus, Endang K</b> .....	214
28. The Evaluation of information system performance in higher education case study with EUCS model at bandar lampung university <b>Reni Nursyanti, Erlangga.</b> .....	221
29. The Analysis Of History Collection System Based On AndroidSmartphone With Qr Code Using Qr CodeCase Study: Museum Lampung <b>Usman Rizal, Wiwin Susanty, Sutrisno.</b> .....	230
30. Application of Complaint Handling by Approach Model of ISO 10002 : 2004 to Increase Complaint Services <b>Agus Sukoco and Yuthsi Aprilinda.</b> .....	235
31. Towards Indonesian Cloud Campus <b>Taqwan Thamrin, Iing Lukman, Dina Ika Wahyuningsih</b> .....	252
32. Bridging Router to ADSL Modem for Stability Network Connection <b>Arnes Yuli Vandika and Ruri Koesliandana.</b> .....	257
33. The Effect of Use Styrofoam for Flexural Characteristics of Reinforced Concrete Beams <b>Yasser , Herman Parung, M. Wihardi Tjaronge, Rudy Djamaluddin</b> .....	261
34. The Estimation Of Bioethanol Yield From Some Cassava Variety <b>M.C. Tri Atmodjo</b> .....	273
35. Effect of Superficial Velocity of Pressure Difference on The Separation of Oil And Water by Using The T-Pipe Junctionl <b>Kms. Ridhuan and Indarto.</b> .....	277
36. The use of CRM for Customer Management at Cellular Telecommunications Industry <b>Ayu Kartika Puspa.</b> .....	293
37. Indonesian Puslit (Centre Of IT Solution) Website Analysis Using Webqual For Measuring Website Quality <b>Maria Shusanti Febrianti and Nurhayati.</b> .....	297
38. The E-internal audit iso 9001:2008 based on accreditation form assessment matrix in study program for effectiveness of monitoring accreditation <b>Marzuki, Maria Shusanti F.</b> .....	307

39. Enhancing Quality Software Through CMMI-ISO 9001:2008 and ISO 9126 <b>Agus Sukoco</b> .....	320
40. Value Analysis Of Passenger Car Equivalent Motorcycle (Case Study Kartini Road Bandar Lampung) <b>Juniardi, Aflah Efendi</b> .....	337
41. Alternative Analysis Of Flood Control Downstream Of Way Sekampung River <b>Sugito, Maulana Febramsyah.</b> .....	347
42. Analysis Of Fitness Facilities And Effective Use Of Crossing Road <b>Juniardi, Edi Haryanto.</b> .....	353
43. Study On Regional Development Work Environment Panjang Port Lands In Support Bandar Lampung City As A Service And Trade <b>Ir. A. Karim Iksan, MT, Yohn Ferry.</b> .....	359
44. Analytical And Experimental Study Bamboo Beam Concrete <b>Hery Riyanto, Sugito, Juli</b> .....	370
45. Comparative Analysis Of Load Factor Method Static And Dynamic Method (Case Study Akdp Bus Route Rajabasa - Bakauheni) <b>A. Ikhsan Karim, MT., Ahmad Zulkily.</b> .....	378
46. Optimization Utilization Of Water Resources dam Batutegei Using Method Of Linear Program <b>Aprizal, Hery Fitriyansyah</b> .....	386
47. Characteristics Generation Traffic Patterns And Movement In Residential Area (Case Study Way Kandis Residential Bandar Lampung) <b>Fery Hendi Jaya, Juniardi,</b> .....	392
48. Use Study On Slight Beam Reinforced Concrete Floor Plate in Lieu Of Secondary Beam <b>Hery Riyanto, Sugito, Lilies Widodjoko, Sjamsu Iskandar</b> .....	399
49. Observation Of The Effect Of Static Magnetic Field 0.1 Mt On A-Amylase Activity In Legume Germination <b>Rochmah Agustrina, Tundjung T. Handayani, and Sumardi.</b> .....	405
50. Effectiveness Analysis Of Applications Netsupport School 10 Based Iso / Iec 9126-4 Metrics Effectiveness <b>Ahmad Cucus, Nelcy Novelia</b> .....	413
51. Comparative Performance Analysis Of Banking For Implementing Internet Banking <b>Reza Kurniawan</b> .....	418

## The implementation of Secton Method for Solving Systems of Non Linear Equations

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**Abstract**—Newton method is a famous method for solving non linear equations numerically. This method is also suitable for solving systems of non linear equations. However, this method has a limitation because it requires the derivative of the non linear function which constructing the systems. The need of derivation some times lead to a problem. Secton method is a combination of Newton method and Secant method. Secton method omit the need of derivation of function. The performance of Secton method is almost same with Newton method. In this paper, Secton method is used to solve a non linear systems of equation. The experiments showed that Secton method could work well for solving non linear systems of equations.

**Keywords**-component; Newton method; secant method; non linear equation

2

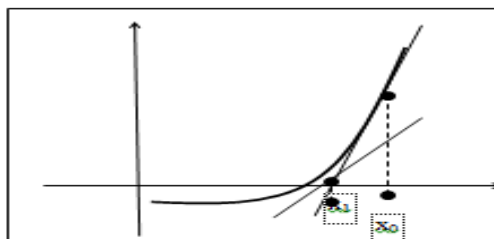


Figure 1. Newton method

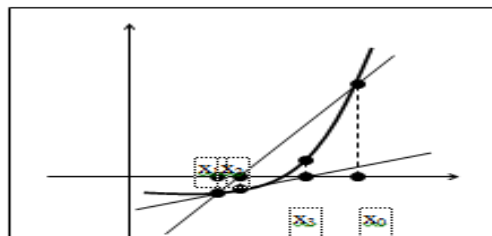


Figure 2. Secant method

## 1 Introduction

The solution of an equation  $f(x) = 0$  is an intersection point between the graph of  $y = f(x)$  and the X axis. Assuming the initial value of the solution is  $x_0$ , iteratively the solution could be found by using Eq. 1 as illustrated in Figure 1 which is known as Newton method [1].

$$x_{n+1} = x_n - \frac{f(x_n)}{f'(x_n)}$$

The use of Newton method creates another problem. The derivation of some function is difficult. Secant Method solve this problem by using an approximation of the derivative value ( $f'(x_n)$ ), that is the slope of a line connecting two points on the function. Secant method need two initial points. It is shown in Figure 2, by using two initial points  $x_0$  and  $x_1$  the solution could be found using Eq. 2 [1].

$$x_{n+1} = x_n - f(x_n) \frac{x_n - x_{n-1}}{f(x_n) - f(x_{n-1})}$$

## 2 SECTON METHOD

Numerical solution is found by iterating an initial value which moves to approximate the solution. The iteration process is stopped when the iteration reach the error tolerance ( $\varepsilon$ ), otherwise no solution can be found.

Secton method is developed by using  $\varepsilon$  in the determination of derivative value of the function to be solved. A derivative of a function  $f(x)$  is calculated using [3]:

$$f'(x) = \lim_{h \rightarrow 0} \frac{f(x+h) - f(x)}{h}$$

If  $\varepsilon$  is very small, then derivative value of  $f(x)$  at  $x = x_n$  is

$$f'(x_n) = \frac{f(x_n + \varepsilon) - f(x_n)}{\varepsilon}$$

Applying (4) into (1) gives Secton method:

$$x_{n+1} = x_n - f(x_n) \frac{\varepsilon}{f(x_n + \varepsilon) - f(x_n)}$$

The performance of Secton method for solving an unstable function, namely Wilkinson polynomial

$$w(x) = \prod_{i=1}^{20} (x - i)$$

has been discussed [4].

The complete solution of the Wilkinson polynomial by using Secton method can be seen in Table I. All the root of the Wilkinson polynomial can be found.

## 3 NEWTON METHOD FOR SOLVING SYSTEM OF NON LINEAR EQUATIONS

Consider the following system of non linear system

$$\begin{aligned} f(x, y) &= 0 \\ g(x, y) &= 0 \end{aligned} \tag{7}$$

The graph of  $z = f(x, y)$  is a surface in xyz-space. The solution of  $f(x, y) = 0$  lie on the intersection of the xy-plane and the graph of  $z = f(x, y)$ . The intersection is called "zero curve" of  $f(x, y)$ . The solution of  $g(x, y) = 0$  lie on the zero curve of  $g(x, y)$  [1].

Let  $(x_0, y_0)$  be an initial guess for a solution for the system (7). The approximation is constructed by using a tangent plane at  $(x_0, y_0, f(x_0, y_0))$ , namely  $z = p(x, y)$  having

$$\begin{aligned}
 p(x, y) &\equiv f(x_0, y_0) \\
 &+ (x - x_0)f_x(x_0, y_0) + \\
 &(y - y_0)g_y(x_0, y_0)
 \end{aligned}
 \tag{8}$$

$$\begin{aligned}
 f_x(x, y) &= \frac{\partial f(x, y)}{\partial x} \\
 f_y(x, y) &= \frac{\partial f(x, y)}{\partial y}
 \end{aligned}$$

The above construction can be applied to the surface  $z = g(x, y)$ .

$$\begin{aligned}
 q(x, y) &\equiv g(x_0, y_0) \\
 &+ (x - x_0)g_x(x_0, y_0) + \\
 &(y - y_0)g_y(x_0, y_0)
 \end{aligned}
 \tag{9}$$

$$\begin{aligned}
 g_x(x, y) &= \frac{\partial g(x, y)}{\partial x} \\
 g_y(x, y) &= \frac{\partial g(x, y)}{\partial y}
 \end{aligned}$$

The solution of the system is the intersection of the zero curve. Let  $(x - x_0) = \delta x$  and  $(y - y_0) = \delta y$ .

Solving the following equation

$$\begin{aligned}
 f(x_0, y_0) + \delta_x f_x(x_0, y_0) + \\
 \delta_y f_y(x_0, y_0) = 0
 \end{aligned}
 \tag{10}$$

$$\begin{aligned}
 g(x_0, y_0) + \delta_x g_x(x_0, y_0) + \\
 \delta_y g_y(x_0, y_0) = 0
 \end{aligned}$$

will get  $\delta_x$  and  $\delta_y$ . The next guess will be [1] $x_1 = x_0 + \delta_x$

$$y_1 = y_0 + \delta_y$$

This kind of solution is a generalization of Newton Method [1]. By using this step the  $n+1$ th guess can be determined, namely

$$x_{n+1} = x_n + \delta_x$$

$$y_{n+1} = y_n + \delta_y$$

where  $\delta_x$  and  $\delta_y$  is obtained from the solution of

$$\begin{aligned}
 f(x_n, y_n) + \delta_x f_x(x_n, y_n) + \\
 \delta_y f_y(x_n, y_n) = 0
 \end{aligned}
 \tag{11}$$

$$\begin{aligned}
 g(x_n, y_n) + \delta_x g_x(x_n, y_n) + \\
 \delta_y g_y(x_n, y_n) = 0
 \end{aligned}$$

#### 4 THE IMPLEMENTATION OF SECTON METHOD

Secton method is used to calculate  $f_x(x, y)$ ,  $f_y(x, y)$ ,  $g_x(x, y)$  and  $g_y(x, y)$ , without any process of derivation. Here is the formulae :

$$f_x(x, y) = \frac{f(x + \varepsilon, y) - f(x, y)}{\varepsilon}$$

$$f_y(x, y) = \frac{f(x, y + \varepsilon) - f(x, y)}{\varepsilon}$$

$$g_x(x, y) = \frac{g(x + \varepsilon, y) - g(x, y)}{\varepsilon}$$

$$g_y(x, y) = \frac{g(x, y + \varepsilon) - g(x, y)}{\varepsilon}$$

The general form of the solution can be constructed. Suppose there is a system of  $n$  nonlinear equations [1].

$$\begin{aligned}
 F_1(x_1, \dots, x_n) &= 0 \\
 &\vdots \\
 F_n(x_1, \dots, x_n) &= 0
 \end{aligned}
 \tag{12}$$

Define

$$x = \begin{bmatrix} x_1 \\ \vdots \\ x_n \end{bmatrix}$$

$$F(x) = \begin{bmatrix} F_1(x_1, \dots, x_n) \\ \vdots \\ F_n(x_1, \dots, x_n) \end{bmatrix}$$

$$F'(x) = \begin{bmatrix} \frac{\partial F_1}{\partial x_1} & \dots & \frac{\partial F_1}{\partial x_n} \\ \vdots & \vdots & \vdots \\ \frac{\partial F_n}{\partial x_1} & \dots & \frac{\partial F_n}{\partial x_n} \end{bmatrix}$$

By implementing Section method,  $F'(x)$  can be replaced with

$$F'(x) = \left[ \frac{\partial F_i}{\partial x_j} \right], \quad i = 1 \dots n, j = 1 \dots n$$

Where

$$\frac{\partial F_i}{\partial x_j} = \frac{F_i(x_1, \dots, x_j + \varepsilon, \dots, x_n)}{\varepsilon}$$

### 5 TESTING

The implementation of Section method for solving system of non linear equations is tested to solve

$$x^2 + 4y^2 - 9 = 0$$

$$18y - 14x^2 + 45 = 0$$

The solutions of this system are (1.203167, -1.374081), (-1.203167, -1.374081), 2.1372167,

1.052652) and (-2.1372167, 1.052652).

Table II shows the iteration of (10,10) as an initial guess. Various initial guesses and its corresponding solutions are showed in Table III.

### 6 CONCLUSION

The implementation of Secant method can a find solution of system of nonlinear equations without any process of derivation of the functions composing the system..

TABLE I THE COMPLETE SOLUTION OF WILKINSON POLYNOMIAL BY USING SECTON METHOD

X0	Solution	iteration	X0	solution	iteration	X0	solution	iteration
-1.25	1.0000	12	6.75	7.0000	3	14.75	15.0000	5
-0.75	1.0000	11	7.25	7.0000	4	15.25	15.0000	4
-0.25	1.0000	9	7.75	8.0000	4	15.75	16.0000	5
0.25	1.0000	8	8.25	8.0000	4	16.25	16.0000	4
0.75	1.0000	5	8.75	9.0000	4	16.75	17.0000	5
1.25	20.0000	16	9.25	9.0000	3	17.25	17.0000	4
1.75	2.0000	5	9.75	10.0000	4	17.75	18.0000	5
2.25	1.0000	4	10.25	10.0000	4	18.25	18.0000	4
2.75	3.0000	4	10.75	11.0000	4	18.75	20.0000	5
3.25	3.0000	5	11.25	11.0000	4	19.25	19.0000	4
3.75	4.0000	4	11.75	12.0000	3	19.75	1.0000	18
4.25	4.0000	5	12.25	12.0000	4	20.25	20.0000	5
4.75	5.0000	4	12.75	13.0000	4	20.75	20.0000	8
5.25	5.0000	5	13.25	13.0000	4	21.25	20.0000	8
5.75	6.0000	3	13.75	14.0000	4	21.75	20.0000	11
6.25	6.0000	5	14.25	14.0000	3	22.25	20.0000	12

THE COMPLETE SOLUTION OF WILKINSON POLYNOMIAL BY USING SECTON METHOD



(E=0.0001)

No	initial points		solutions	
	x	y	x	y
1	10	10	2.13721 7	1.05265 2
2	-10	10	- 2.13721 7	1.05265 2
3	10	-10	1.20316 7	- 1.37408 1
4	-10	-10	- 1.20316 7	- 1.37408 1

TABLE I. ITERATION OF AN INITIAL POINT BY USING SECTON METHOD ON A SYSTEM OF NONLINEAR EQUATION (E=0.0001)

iteration	x	y
0	1	-1
1	1.1467	-1.4678
2	1.1882	-1.3994
3	1.2015	-1.3763
4	1.2030	-1.3743
5	1.2032	-1.3741
6	1.2032	-1.3741
7	1.2032	-1.3741
8	1.2032	-1.3741
9	1.2032	-1.3741
10	1.2032	-1.3741

TABLE II. VARIOUS INITIAL POINTS AND ITS SOLUTIONS OF SYSTEM OF NON LINEAR EQUATIONS (E=1X 10<sup>-15</sup>)

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