

**NOVEL APPROACH FOR REDUCING
CHATTERING EFFECTS IN SLIDING MODE
CONTROL SYSTEM**

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TABLE OF CONTENTS

	Page
DECLARATION OF THESIS	i
ACKNOWLEDGEMENTS	ii
TABLE OF CONTENTS	iii
LIST OF TABLES	vii
LIST OF FIGURES	viii
LIST OF ABBREVIATIONS	xiii
LIST OF SYMBOLS	xvi
ABSTRAK (MALAY)	xviii
ABSTRACT	xix
CHAPTER 1 INTRODUCTION	
1.1 Background	1
1.2 Problem Statement	3
1.3 Research Objectives	5
1.4 Scope of research	7
1.5 Summary of Contributions	8
1.6 Thesis Outline	9
CHAPTER 2 LITERATURE REVIEW	
2.1 Introduction	11
2.2 Sliding Mode Controller	15

2.2.1	Existing Condition	17
2.2.2	Reaching Condition	18
2.2.3	Sliding Mode Controller Parameters	18
2.3	Classification of Sliding Mode Controller	21
2.3.1	Sliding Mode Controller Based on System Type	21
2.3.1.1	Continuous Time Sliding Mode Controller	22
2.3.1.2	Discrete Time Sliding Mode Controller	22
2.3.1.3	Sample data Sliding Mode controller	23
2.3.2	Sliding Mode Controller Based on Sliding Surface Method	24
2.3.2.1	Conventional Sliding Surface With or Without Model Following	24
2.3.2.2	Dynamic Sliding Surface With or Without Model Following	24
2.4	Chattering in SMC	25
2.4.1	Chattering Due to Parasitic Dynamics	
2.5	Chattering Reduction Methods	27
2.5.1	Boundary Layer Method	28
2.5.1.1	Boundary Layer Sliding Mode Controller	29
2.5.1.1.1	The Saturation Function	29
2.5.1.1.2	The Sigmoid Function Sliding Mode Controller	34
2.5.1.1.3	The Conical Boundary Layer	35
2.5.2	Observer-Based Sliding Mode Control	36
2.5.3	Two-Dimensional Vector Control called Super-Twisting	39
2.5.4	Time-Varying Switching Gain	41
2.6	Summary	42

CHAPTER 3 RESEARCH METHODOLOGY

3.1	Introduction	44
3.2	Basic Sliding Mode Controller Design	45
3.2.1	Controller Design Evaluations	46
3.2.2	SMC Design Parameters Evaluation and Analysis	47
3.2.2.1	System Stability	47
3.3	Observability and Controllability	48
3.3.1	Linear Time-Invariant (LTI) Systems	49
3.4	Software Simulation	50
3.5	Simulation Model Over view	51
3.6	Overview of Proposed Methodologies	51
3.6.1	Sliding Mode with State Feedback Controller	52
3.6.2	Modeling Sliding Mode with State Feedback Controller	52
3.6.2.1	SMSFC System Modelling	63
3.6.2.2	EvaluationScenarios	63
3.6.2.3	Performance metrics	64
3.6.3	Pre-programmed Exponential Sliding Mode Controller	65
3.6.4	Combination of Nonlinear Functions with Sliding Mode Controller	82
3.7	Summary	83

CHAPTER 4 RESULTS AND DISSCUSION

4.1	Introduction	85
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4.2	Performance Analysis of SMSFC	86
4.2.1	External load	93
4.2.2	System with External and internal noise	96
4.2.3	Parameter Variations	97
4.2.4	External load, Noise and Parameter Variations Effect	98
4.2.5	Nonlinear Input Source	101
4.2.6	Comparison of SMSFC and STW with Nonlinear Input Source	101
4.2.7	External load Applied between 1.5 to 4 Seconds	105
4.3	Chattering Analysis	110
4.4	Comparative Analysis of SMSFC with BLSSMC and CSMC	115
4.5	Evaluation and Analysis of SMSFC and BLSSMC with High level-Measurement Noise	119
4.6	Comparison between the SMSFC signal with Exponential Signal	121
4.7	SMSFC Comparative Analysis with Low Pass Filter on SMC	123
4.7.1	Evaluation of SMSFC and BLSSMC in the Robotics System	127
4.8	Performance and Evaluation of Pre-programmed Exponential Sliding Mode Controller	129
4.9	Performance Evaluation of CNFSSMC	134

CHAPTER 5 CONCLUSION AND RECOMMENDATION

5.1	Conclusions	136
5.2	Future Work	140

REFERENCES	142
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LIST OF PUBLICATIONS AND AWARDS	154
--	------------

LIST OF TABLES

No.	Page
4.1 SMSFC System Performance	100
4.2 Comparison of Time Response (SMSFC and STW)	103
4.3 Comparison of Control Signals (SMSFC and STW)	104
4.4 Standard Deviation of Chattering in SMSFC and CSMC	112
4.5 Mean of Chattering for SMSFC and CSMC	114
4.6 Standard Deviation of Chattering in SMSFC, BLSMC and CSMC	117
4.7 Standard Deviation of Chattering for SMSFC, BLSMC, CSMC and LPFSMC	124
4.8 Standard Deviation of Chattering in SMSFC, BLSMC, CSMC LPFSMC with External Noise and Parameter Variations	126
5.1 Summary of the Reduction of the Effect of Chattering Phenomenon in Different Cases (With and Without External Load, Noise, and Changes in the System parameters)	138

LIST OF FIGURES

No.	PAGE
2.1 Samples of SMC Applications	13
2.2 Literature Review Flowchart	14
2.3 Phase Plane Trajectory of Second-Order System	20
2.4 Chattering Phenomenon on Switching Surface (Sliding Phase)	26
2.5 Saturation Function $\text{sat}(\sigma)$	30
2.6 Sliding Surface and Boundary Layer (BL)	31
2.7 Sliding surface and boundary layer	32
2.8 A Nonlinear Switching Curve	33
2.9 Sigmoid Function (Sigmoid (σ))	35
2.10 Sliding Mode Controller with Asymptotic Observer	37
2.11 Sliding Mode with Asymptotic Observer	38
3.1 Graphical User Interface Routh-Hurwitz Criterion	48
3.2 Block Diagram for State-Space System Dynamics	54
3.3 System with m Inputs and n Outputs	57
3.4 Block Diagram of Sliding Mode State Feedback Controller (SMSFC) System	59
3.5 Detail Components for Sliding Mode State Feedback Controller (SMSFC) System	60
3.6 Detail Components of SMSFC Controller System	61
3.7 Sigma Generation for SMSFC System	61

3.8	Flowchart of Sliding Mode Controller with State Feedback Controller (SMSFC) System	62
3.9	Relation between the Sliding Line Slope and Gain Amplitude	67
3.10	Phase Plane of System with Sliding Line Moving from $(\theta_1$ to θ_2)	68
3.11	Effect of Angle Changing of Sliding Line on the Amplitude of Chattering	70
0.1	Switching of Sliding Mode Controller with Different Time Intervals	71
3.13	Relationship between Chattering and Amount of Switching on SMC	72
3.14	Effect of Exponential Gain on Amplitude of Sliding Mode Control Signal	73
	Error! Bookmark not defined.	
3.15	Block Diagram of Pre-programmed Exponential Sliding Mode Controller	73
	Error! Bookmark not defined.	
3.16	Relation between the Input and Fixed Magnitude Gain of PPESMC	74
3.17	Nyquist Plot of Switching Function	75
3.18	Reduction of the Chattering Phenomenon for the Proposed PPESMC Compared to CSMC (a) Control Signal, (b) Sliding Function Signal	77
3.19	Relationship of Sliding Mode Gain and System States with Sliding Surface, M1 and M2 which are the Magnitude of Controller, Z Slope Parameter	77
3.20	Relationship of Exponential Gain of Sliding Mode Controller and System States (x_1, x_2) with Sliding Surface	78
3.21	Overall Schematic of PPESMC	79
3.22	PPESMC Algorithm Flowchart	81
3.23	Block diagram of Combination Nonlinear Functions with Sliding Mode Controller (CNFSMC)	82
4.1	High Chattering in Phase Plane of System Using CSMC with Initial Condition $(x_{o1} = -1.5, x_{o2} = 1.5)$	86
4.2	Signal with High Frequency Switching of CSMC	87
4.3	States Response of System, with High Chattering on the Second State (x_2) , Switches at High (Theoretically Infinite) Frequency of CSMC	88

4.4	Phase Plane of the System Using SMSFC Eliminates the Chattering Phenomenon, with Initial Condition (1.5, -1.5)	89
4.5	Compression of States Response of the System Using SMSFC and CSMC (Reduced the Effect of Chattering in the System Using SMSFC)	90
4.6	Comparison of Control Signals of CSMC and SMSFC	91
4.7	Phase Plane of the Three Different Types of Controllers CL, CSMC and SMSFC with Same Initial Condition	91
4.8	Zooming of the Phase Plane Shows High Chattering in CSMC and Chattering Reduction in SMSFC	92
4.9	Block Diagram of a Position-Control, Armature-Controlled DC Motor (Kanojiya & Meshram, 2012)	93
4.10	System Response Using SMSFC when 120% Load is Applied to the System	94
4.11	System Response Using SMSFC and CSMC when 120% Load is Applied to the System	94
4.12	(a) Control Signal of SMSFC, (b) Phase Plane of SMSFC, (c) Control Signal of CSMC, (d) Phase Plane of CSMC	95
4.13	SMSFC System Responses when $\pm 40\%$ Noise is Applied to the System	96
4.14	System Time Responses Using SMSFC and CSMC Respectively when 30% Parameter Variations Occur	98
4.15	System Time Responses Using SMSFC and CSMC Respectively when 120% External Load, 40% External Noise and 30% Parameter Variations Occur	99
4.16	(a & c) Comparison of System Response using SMSFC and STW with Nonlinear Input, (b & d) Phase Plane of the System using SMSFC and STW	102
4.17	Response of the SMSFC and STW Controllers when Nonlinear Input was Applied	103
4.18	Control Signal of the SMSFC and STW Controllers when Nonlinear Input was Applied	104
4.19	Sliding Equation Signal for both SMSFC and STW when Nonlinear Input was Applied to the System	105
4.20	Phase Plane of the System Using both SMSFC and STW its Clear the Limit Cycle Red color line of STW near Equilibrium point, Blue Color of SMDFC	106
4.21	(a) System responses with 120% load between 1.5 to 4 seconds using SMSFC,	107

(c) System responses with 120 % load between 1.5 to 4 seconds using STW,	
(b) Phase Plane of the System Using SMSFC, (d) Phase Plane of the System Using STW	
4.22 SMSFC Response when 120 % applied load between 1.5 to 4 seconds	107
4.23 STW Responses when 120 % Load Applied Between 1.5 to 4.0 seconds	108
4.24 SMSFC Control Signal when 120% External Load is Applied Between 1.5 and 4.0 Seconds	109
4.25 CSMC Control Signal when 120% External Load is Applied Between 1.5 and 4.0 seconds	109
4.26 Response of Second State of the System ($x_1 = x_2$) for SMSFC and CSMC	111
4.27 SMSFC and CSMC Control Signals	111
4.28 Response of System States (x_1, x_2) for SMSFC and CSMC with Different Initial Conditions ($x_{o1} = \pm 0.5, x_{o2} = \pm 0.5$)	112
4.29 Standard Deviation of Chattering in SMSFC and CSMC with Different Initial Conditions $x_{o1,o2} = \pm 0.5, x_{o1,o2} = \pm 1$ and $x_{o1,o2} = \pm 1.5$	113
4.30 Mean of Chattering for SMSFC and CSMC under Different Initial Conditions $x_{o1,o2} = \pm 0.5, x_{o1,o2} = \pm 1$ and $x_{o1,o2} = \pm 1.5$	114
4.31 Phase Plane Trajectory of the System for SMSFC, BLSMC and CSMC	115
4.32 Response of the Three Sliding Equations $\sigma_{SMSFC}, \sigma_{BLSM}$ and σ_{CSMC}	116
4.33 Standard Deviation of Chattering in SMSFC, BL SMC and CSMC under Different Initial Conditions $x_{o1,o2} = \pm 0.5, x_{o1,o2} = \pm 1$ and $x_{o1,o2} = \pm 1.5$	117
4.34 Chattering-Area of SMSFC, BL SMC and CSMC for Number of Iterations	118
4.35 Control Signal of the Three Controllers (SMSFC, BLSMC and CSMC)	118
4.36 (a) System Response Using BLSMC, (b) Phase Plane Using BLSMC, (c) Control Signal of BLSMC and (d) Error Signal Using BLSMC, when BL Thickness is 0.01	119
4.37 (a) System Response Using BLSMC, (b) Phase Plane Using BLSMC, (c) Control Signal of BLSMC and (d) Error Signal Using BLSMC, when BL Thickness is 0.1	120

4.38 (a) System Response Using SMSFC, (b) Phase Plane Using SMSFC, (c) Control Signal of SMSFC, and (d) Error Signal Using SMSFC with HLMN	120
4.39 (a) System Response with Programmable Input Using Exponential Control Signal, (b) Control Signal and (c) Error signal	122
4.40 (a) System Response, (b) Control Signal and (c) Error Signal with Programmable Input Using SMSFC	123
4.41 Standard Deviation of Chattering for SMSFC, BL SMC, CSMC and Low Pass Filter SMC under Different Initial Conditions	125
4.42 Chattering-Area of SMSFC, LPFSMC, BLSMC and CSMC under Different Initial Conditions	125
4.43 Standard Deviation of Chattering on SMSFC, BLSMC, CSMC and LPFSMC with External Noise and Parameter Variations	126
4.44 Chattering-Area of SMSFC, LPFSMC, BLSMC and CSMC with External Noise and Parameter Variations	127
4.45 The Robotic Phase Plane of Robotics under Different Initial Conditions	128
4.46 Zooming of the Robotic Phase Plane under for SMSFC and BLSMC	128
4.47 a) Time Response, (b) Error Response and (c) Control Signal of Robotics under Different Initial Conditions Using SMSFC and BLSMC	129
4.48 Phase Plane of Unobservable System Using SMSFC can't Read All System States By Sensor	130
4.49 Compression Phase Plane of Unobservable System Using SMSFC and PPESMC	130
4.50 (a) System Response Using PPESMC with Nonlinear Input, (b) Error (c) Signal and Control Signal	131
4.51 (a) System Response using PPESMC, (b) Error Signal and (c) Control Signal with External Load	132
4.52 (a) System Response Zooming Using PPESMC (b) Control Signal (c) Error Signal	133
4.53 (a) System Response Using CNFSMC, (b) Error Signal (c) Control Signal and (d) Parameter Changes	135
4.54 Phase Plane System , Using CNFSMC and STW	135

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LIST OF ABBREVIATIONS

2-DSMC	2 nd order Discrete-Sliding -Mode Control
2-SMC	Second-order Sliding Mode Control
ADSMCS	Adaptive Dynamic Sliding-Mode Control System
AFSMC	Adaptive Fuzzy system Sliding Mode Control
BIBO	Boundary Input Boundary Output
BL	Boundary Layer
BLM	Boundary Layer Method
BLSMC	Boundary Layer Sliding Mode Controller
CBL	Conical Boundary Layer
CL	Closed Loop
CMFSMC	Combination Nonlinear Functions with Sliding Mode Controller
CNC	Computer Numeric Control
CSMC	Conventional Sliding Mode Control
CSS	Conventional Sliding Surface
CTSMC	Continuous time Sliding mode controller
<i>DF</i>	Describing Function
DSMC	Dynamic Sliding Mode Control
DSMC	Dynamic Sliding-Mode Controller
DSP	Digital Signal Processing
DSS	Dynamic Sliding Surface
DTSMC	Discrete Time Sliding Mode controller
EQC	Equivalent-Control
FLC	Fuzzy-Logic-Controller

GUI	Graphical User Interface
H-LMN	High-Level Measurements Noise
HOSMC	High Order Sliding Mode Controller
IFO	Indirect Field-Orientation control
IM	Induction Motor
LPFSMC	Low Pass Filter Sliding Mode Controller
LTI	Linear Time-Invariant
ISS	Input to State Stability
OBM	Observe Method
PID	Integral, Derivative controller
PPESMC	Pre-programmed Exponential Sliding Mode Controller
PPT	Phase Plane Trajectory
RRBFN	Recurrent Radial Basis Function Network
Std	Stander deviation
SDSMC	Sample data Sliding Mode controller
SISO	Single-Input Single-Output
SMC	Sliding Mode Controller
SMCS	Sliding-Mode Controller with a Smooth control law
SMSFC	Sliding Mode with State Feedback Controller
SSE	Steady State Error
STW	Super-Twisting (STW)
TDVC	Two-Dimensional Vector Control
TOC	Time Optimal Controller
TS	Takagi-Sugeno
TS	Taylor Series

TVSG	Time-Varying Switching Gain
UMD	Unmodeled Dynamics
VSCS	Variable Structure Control System
VSS	Variable Structure System

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LIST OF SYMBOLS

\mathbb{R}^m	m -dimensional control vector
θ	Angle of sliding line
ε	Boundary Layer thickens
k	Constant gain
u	Control input or state velocity vectors $u^{-,+}$
w_c	Controllability Gramian
P	Controllability Matrix
β_1, β_2	Controller parameters
w_c	Critical frequency
x_f	Dynamical system around the origin
T	Final time
w	Frequency
$M1, M2$	<u>Gain</u> Components
K	Gain Matrix of State Feedback
t_0	Initial time
B	Input matrix in state space
$r(t)$	Input signal
δ	Magnitude deflection of controller
A	Matrix states of system in state space
w_o	Observability Gramian
C	Output matrix in state space
α	Parameters of Controllability Matrix

ΔT	Period time of switching function
D	Feedforward Matrix
γ	Reduction filter parameter
sat	saturation function
σ	Sliding function
c	Sliding line parameters (slop)
k_1, k_2	State feedback controller parameter
ψ	Switching Components
X	System state
T	Time
M	m -dimensional order
N	n -dimensional order
\mathbb{R}^n	n -dimensional state vector
M_1	Magnitude of switching gain

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**Pendekatan Baru Mengurangkan Kesan Chattering Dalam Sliding Mode Sistem
Kawalan
ABSTRAK**

Alat kawalan mod gelangsar (SMC) ialah sejenis sistem kawalan struktur boleh ubah, yang merupakan alat autoritatif bagi menangani perubahan tak pasti dan gangguan luaran dalam sistem parameter dan sistem tak linear. Walaupun SMC dikaitkan dengan beberapa kelebihan ketara seperti kekukuhan, alat kawalan mod gelangsar konvensional (CSMC) tidak dapat memenuhi kebanyakan keperluan sistem, terutamanya berdekatan titik keseimbangan akibat getaran kuat disebabkan pensuisan berkelajuan tinggi (frekuensi tinggi isyarat kawalan berdekatan garisan gelangsar). Tesis ini tertumpu pada pembangunan alat kawalan baru dan algoritma bagi mengurangkan kesan fenomena getaran dalam usaha mencapai prestasi sistem yang efisien. Ia merangkumi tiga konsep mod gelangsar baru; mod gelangsar dengan pengawal suap balik keadaan (SMSFC), pengawal mod gelangsar eksponen praprogram (PPESMC), dan gabungan fungsi tak linear dengan pengawal mod gelangsar (CNFSMC). Kesemuanya direka berteraskan konsep SMC. SMSFC bertujuan bagi mengurangkan kesan fenomena getaran yang lazim dikaitkan dengan penggunaan CSMC dalam keadaan hingar dan ketakpastian. Ini diperolehi dengan memperhalus amplitud gandaan CSMC dan mencapai keadaan capahan sistem. Pengawal suap balik keadaan akan melaksanakan pemformatan semula dan penggabungan yang lancar dengan CSMC bagi menghasilkan pengawal bersepadu yang dipanggil mod gelangsar dengan pengawal suap balik keadaan (SMSFC), manakala PPESMC bergantung pada nilai isyarat ralat dan menjanakan gandaan eksponen yang berkadar dengan isyarat ralat tersebut. Akhir sekali, kombinasi fungsi tak linear dengan pengawal mod gelangsar (CNFSMC) boleh dibina dengan menggabungkan kaedah SMSFC dan PPESMC. Kaedah ini bergantung kepada dua ciri keadaan eksponen yang berhubungan dan tak linear. Pengawal baru ini terbukti berkesan sebagai strategi kawalan bersepadu yang kukuh dan efektif untuk sistem linear dan tak linear yang tak pasti dan mengalami perubahan parameter, selain berupaya mengurangkan kesan fenomena getaran. Penilaian, perbandingan dan analisis prestasi ketiga-tiga kaedah ini (SMSFC, PPESMC dan CNFSMC) untuk sistem SMC dibentangkan dalam tesis ini, dan prestasi masing-masing dibandingkan dengan mod gelangsar lapisan sempadan super-berputar dan penapis laluan rendah kaedah SMC (STW, BLSCM and LPFSMC) apabila diaplikasikan dalam motor DC dan robotik. Kesimpulan utama yang dapat diperolehi daripada tesis ini menunjukkan bahawa SMSFC yang dibangunkan dan digunakan seperti diterangkan di atas telah menunjukkan kekukuhan sistem, prestasi yang tinggi serta kawalan pengesanan trajektori yang baik dalam keadaan hingar dan ketakpastian sesebuah model. Penilaian dan analisis dijalankan terhadap indeks prestasi yang berbeza dan di bawah keadaan operasi yang berlainan. Keputusan menunjukkan bahawa di bawah beban luaran dan hingar luaran yang berbeza serta perubahan parameter sistem, prestasi SMSFC, PPESMC dan CNFSMC terbukti lebih baik berbanding STW, BLSCM dan LPFSMC dalam pengurangan kesan fenomena getaran, masing-masing sebanyak 95%, 68%, 78% dan 89%.

Novel Approach for Reducing Chattering Effects in Sliding Mode Control System

ABSTRACT

The sliding mode controller (SMC) is a type of variable structure control system (VSCS), which is an authoritative tool for dealing with uncertainty, variations in parameter systems, nonlinear systems and external disturbances. Although significant advantages are associated with SMC such as robustness, the conventional sliding mode controller (CSMC) does not cover most of the requirements of the system, especially near the equilibrium point because of the high chattering which occurs as a result of high-speed switching (high frequencies of control signal near sliding line). This thesis is concerned with developing a novel controller and algorithms to reduce the effect of the chattering phenomenon, in order to achieve an efficient system performance. It includes three novel sliding mode concepts; sliding mode with state feedback controller (SMSFC), pre-programmed exponential sliding mode controller (PPESMC), and combination of nonlinear functions with sliding mode controller (CNFSMC). These are based on the SMC concept. The SMSFC is designed to reduce the effect of the chattering phenomenon that is present with the use of CSMC when noise and uncertainties occur. This is accomplished by refining the gain amplitude of CSMC, obtaining the convergence states properties of the system. The state feedback controller reformat and combines seamlessly with the CSMC to produce an integrated controller called a sliding mode with state feedback controller (SMSFC), whereas PPESMC relies on the value of an error signal and generates an exponential gain which is proportional to the error signal. Finally, a combination of nonlinear functions with sliding mode controller (CNFSMC) can be constructed from a combination of SMSFC and PPESMC. This method depends on two interrelated and nonlinear state-exponential properties. These new controllers have proved to be a robust and effective integrated control strategy for uncertain, varied-parameter, linear, and nonlinear systems, in addition to reducing the effect of the chattering phenomenon. Performance evaluations, comparisons, and analysis for the three methods (SMSFC, PPESMC and CNFSMC) for the SMC system are presented in this thesis, and their performance compared with the super-twisting (STW), boundary layer sliding mode (BLSMC) and low pass filter (LPFSMC) with SMC methods respectively when applied to a DC motor and robotics. The main conclusion drawn in this thesis was that the SMSFC as developed and implemented exhibited robust and high performance and trajectory tracking control given modeling uncertainties and noise. The evaluation and analysis were performed for different performance indexes and under different operational conditions. The results showed that under various external loads, external noise, and variations in system parameters SMSFC, PPESMC, CNFSMC, STW, BLSMC and LPFSMC with respect to reduction of the effect of the chattering phenomenon by 95%, 94%, 97%, 68%, 78% and 89% respectively.

CHAPTER 1

INTRODUCTION

1.1 Background

Controller systems are dominant in everyday life. Scientific progress and the achievement of consistently outstanding advances in the field of analogue and digital controllers, electronic devices in optical and telecom systems, information networks, local and global activities and controller systems' vital role in the development of the use of advanced control have reached a high level in recent years, especially in the areas of industrial applications, robots, military applications, medical applications and space applications (Boiko 2011, Dorf and Bishop 2011). Such crucial developments require that the control systems must be at the same stage of evolution in all applications. System performance in terms of high precision, speed response, non-chattering, no overshoot and zero steady-state error are the most important and basic requirements for control systems.

The traditional control systems that are applied to linear and nonlinear systems may not be appropriate for all desired system requirements, especially in varied-parameter and uncertain systems (Kundur 2001). Uncertain control systems have been successfully tested, however, by using variable structure systems (VSS) with the sliding mode control (SMC) method (Utkin 1977).

Theoretically, SMC provides powerful stability control systems through a high gain with infinite fast switching (Crassidis and Markley 1996). High-gain control designs,

however, suffer from a defective peaking phenomenon. SMC constitutes regular discontinuous control input with infinite switching frequency. This will obviously lead to an undesirable phenomenon called chattering (Huang 2013). This phenomenon has some disadvantages in mechanical and electrical systems such as mechanical wearing and overheating of the electrical components (Piltan, et al. 2011).

The emergence of SMC theory in practical applications gives certain guarantees regarding modelling error and the parameter uncertainties of the system and satisfies most of the demands of these complex systems. Although sliding mode control systems are robust and easy to design and implement (Utkin 1978, Bengiamin and Chan 1982, Utkin, Guldner et al. 1999, Barambones, Garrido et al. 2006, Baburaj and Bandyopadhyay 2012, Ahmed, et al. 2013, Al-Hadithi, et al. 2013), the phenomenon of chattering (which is the implied nature of the control of the discontinuous signal) is a problem; therefore, there is some uncertainty about this approach (Mihoub, et al. 2010, Takhmar, et al. 2012).

The development of the sliding mode control system (SMCS) has addressed the main obstacle posed by the phenomenon by the use of CSMC. Although the implementation of modern SMC has been used to reduce the effect of chattering, most of these methods have weaknesses which emerge in the system output. As a result the harmful chattering that accompanies the conventional sliding mode control has become the focus of a great deal of attention. There are different types of chattering in sliding mode controllers, but

this thesis considers only those that can be analysed and addressed as other types may be either harmless or irremediable.

1.2 Problem Statement

There are several approaches to reduce the phenomenon of chattering: for example, the boundary layer method (BLM), the observe method, two-dimensional vector control, the time-varying switching gain (TVSG), the equivalent-control-dependent gain method, the super-twisting method (STW), etc. (Goh, et al. 2003, Liu, et al. 2005, Cupertino, et al. 2008, Min et al. 2008, Ming, et al. 2010, Zaeri, et al. 2012). These methods have disadvantages such as a reduction in the accuracy of the control system, and may be ineffective in the presence of an external load, high level measurement noise (HLMN), parameter system variation, and uncertain systems. As a result, reducing the phenomenon (chattering) may yield weaknesses in other places. Those methods (STW and BLM) lead, however, to weak control signals because the small control signal value reduces the effect of the chattering phenomenon (Yang, et al. 2008, Ming, et al. 2010, Ferreira, et al. 2011, Loukianov, et al. 2011, Zaltni and Abdelkrim 2011, Zhiyu, Gang et al. 2011, Aghababa and Akbari 2012, Al-Hadithi, et al. 2013, Chena, Yangb et al. 2013). Therefore, the most important of the problem statements associated with the use of SMC is as follows:

A small time constant of the system, finite sampling rate in digital sliding mode controller and fast dynamic, which was neglected in the ideal model, causes the chattering phenomenon in sliding mode controllers (Bartolini, et al. 2000, Dal and Teodorescu 2011).

As is it well known the appropriate gain of a sliding controller may ensure the stability of the system; however, this is accompanied by the emergence of the chattering phenomenon. In addition most controller systems suffer from a loss of stability when exposed to external disturbance, high level measurement noise (HLMN) and external loads and variations in the system parameters (Spong and Vidyasagar 1987).

The majority of the offered solutions decrease the value of the gain in order to reduce the chattering phenomenon but the main problem when the system is close to the equilibrium point is that it is possible to lose stability because of the reduction in the amount of gain value. The decrease of gain value (control signal value) of the sliding mode controller in order to reduce the chattering phenomenon has disadvantages for this procedure (Xu, et al. 2004), which lead the trajectory of system states leave the sliding line (Zhao and Jiang 1998). As a result, the controller approach is largely unable to compensate fully for the disturbance. Traditional SMC still provides the closed-loop system with certain characteristics to reduce the influence of external disturbances; however, it is not absolutely foolproof.

Accordingly, a novel approach is needed for designing a sliding mode with state feedback controller (SMSFC) to overcome the most serious weakness of SMC, the chattering phenomenon. The removal of chattering, however, requires precise selection of the gain value to maintain the properties of the sliding mode controller the use of some features of the system itself (property convergence of states in the stable system) in which the states of the system own the property of convergence.