

Sliding Mode Controller for Electromechanical System with Chattering Attenuation

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Abstract:

Electromechanical systems (EMS) may be considered as devices transforming electrical into mechanical energy. Every system that belongs to the electromechanical class can be decomposed in an electrical (ES) and a mechanical subsystem (MS). The motion control systems can be quite complicated because many different factors have to be considered in the design of electromechanical systems. These factors can be summarized as the nonlinearity, non-smoothness in its model, the uncertainty in system model parameters and non-satisfying matching condition.

In this paper a new sliding mode control design approach for the EMS is proposed without neglecting the inductance in the electrical part or approximating the non-smooth perturbation. The first step in the proposed controller design consists of transforming the ES to a low pass filter (LPF) and then (the second step) designing a sliding mode controller (SMC) to the MS that will reject system model uncertainty and the effect of non-smooth disturbances. With a suitable selected LPF time constant, the SMC which controls the MS is nearly the equivalent control and as a result the chattering is attenuated greater than that in the case of classical SMC which designed by ignoring the electrical subsystem and also with a smaller control effort. The simulation results, of applying the proposed sliding mode control to an electromechanical system, show its superiority compared with classical SMC designed in two effective SMC features beside forcing the state to follow the desired position where chattering amplitude is greatly reduced with a significant reduction in control action value (approximately equal to third the required input voltage with the classical SMC).

Keywords: Electromechanical systems, Sliding mode control, Low pass filter, Chattering attenuation

1. Introduction:

Electromechanical systems may be considered as devices transforming electrical into mechanical energy. They establish a very important class of

industrial components often found in current practical applications defining the ideal link between computer-based drivers and movement generators systems. From the control point of view their structure is quite interesting since they belong to the class of the so-called under actuated systems in the sense that only the electrical part is directly actuated; the mathematical models that represent their dynamical behavior are, in general, nonlinear and, in many cases, the state is not completely available for measurement [1]. The main assumption is that every system that belongs to the electromechanical class can be decomposed into an electrical and a mechanical subsystem which it can be viewed as the *interconnection* of electrical and mechanical lumped elements, respectively. For the *electrical subsystems* these elements are inductances, capacitances and resistances, while for the *mechanical subsystem* are springs, masses and dampers [1].

Motion control is concerned with manipulating power to control the movement of a mechanical system. A large amount of motion control is now performed using electric motors, so that it will be our main focus. Motion control systems can be quite complicated because many different factors have to be considered in the design. The following issues must typically be considered:

- Reduction of the influence of plant disturbances
- Attenuation of the effect of measurement noise
- Variations and uncertainties in plant behavior

It is difficult to find design methods that consider all these factors, especially for the conventional control approaches where control designs involve compromises between conflicting goals. In order to design control systems to get high performance and robustness when controlling such complicated processes, advanced controllers have been introduced.

From control design point of view there are mainly three problems for the application of many control theories which can be summarized as follows:

- 1) The nonlinearity and non-smoothness in its model due to the friction model and the nonlinear spring.

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Table of Contents Chattering Attenuation Of Sliding Mode Controller Using

1. Understanding the eBook Chattering Attenuation Of Sliding Mode Controller Using
 - The Rise of Digital Reading Chattering Attenuation Of Sliding Mode Controller Using
 - Advantages of eBooks Over Traditional Books
2. Identifying Chattering Attenuation Of Sliding Mode Controller Using
 - Exploring Different Genres
 - Considering Fiction vs. Non-Fiction
 - Determining Your Reading Goals
3. Choosing the Right eBook Platform
 - Popular eBook Platforms
 - Features to Look for in an Chattering Attenuation Of Sliding Mode Controller Using
 - User-Friendly Interface
4. Exploring eBook Recommendations from Chattering Attenuation Of Sliding Mode Controller Using
 - Personalized Recommendations
 - Chattering Attenuation Of Sliding Mode Controller Using User Reviews and Ratings
 - Chattering Attenuation Of Sliding Mode Controller Using and Bestseller Lists
5. Accessing Chattering Attenuation Of Sliding Mode Controller Using Free and Paid eBooks
 - Chattering Attenuation Of Sliding Mode Controller Using Public Domain eBooks
 - Chattering Attenuation Of Sliding Mode Controller Using eBook Subscription Services

- Chattering Attenuation Of Sliding Mode Controller Using Budget-Friendly Options
- 6. Navigating Chattering Attenuation Of Sliding Mode Controller Using eBook Formats
 - ePub, PDF, MOBI, and More
 - Chattering Attenuation Of Sliding Mode Controller Using Compatibility with Devices
 - Chattering Attenuation Of Sliding Mode Controller Using Enhanced eBook Features
- 7. Enhancing Your Reading Experience
 - Adjustable Fonts and Text Sizes of Chattering Attenuation Of Sliding Mode Controller Using
 - Highlighting and Note-Taking Chattering Attenuation Of Sliding Mode Controller Using
 - Interactive Elements Chattering Attenuation Of Sliding Mode Controller Using
- 8. Staying Engaged with Chattering Attenuation Of Sliding Mode Controller Using
 - Joining Online Reading Communities
 - Participating in Virtual Book Clubs
 - Following Authors and Publishers Chattering Attenuation Of Sliding Mode Controller Using
- 9. Balancing eBooks and Physical Books Chattering Attenuation Of Sliding Mode Controller Using
 - Benefits of a Digital Library
 - Creating a Diverse Reading Collection Chattering Attenuation Of Sliding Mode Controller Using
- 10. Overcoming Reading Challenges
 - Dealing with Digital Eye Strain
 - Minimizing Distractions
 - Managing Screen Time
- 11. Cultivating a Reading Routine Chattering Attenuation Of Sliding Mode Controller Using
 - Setting Reading Goals Chattering Attenuation Of Sliding Mode Controller Using
 - Carving Out Dedicated Reading Time
- 12. Sourcing Reliable Information of Chattering Attenuation Of Sliding Mode Controller Using
 - Fact-Checking eBook Content of Chattering Attenuation Of Sliding Mode Controller Using
 - Distinguishing Credible Sources
- 13. Promoting Lifelong Learning
 - Utilizing eBooks for Skill Development
 - Exploring Educational eBooks
- 14. Embracing eBook Trends

- Integration of Multimedia Elements
- Interactive and Gamified eBooks

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