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Observer-based model-free adaptive sliding mode predictive control

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ABSTRACT This paper proposes a new observer-based model-free adaptive sliding mode predictive control method (MFASPC) for discrete-time nonlinear systems. This scheme first equates the discrete-time nonlinear system to a linear form using a data-driven compact form dynamic linearization (CFDL) technique, establishes a data model consisting of only the pseudo partial derivatives (PPD), input data and output data, designs adaptive observers to achieve the estimation of the unknown PPD. The controller design part uses integral sliding mode control (SMC) to ensure the system's robustness. In contrast, with its constraint characteristics, the model predictive control (MPC) replaces the traditional switching control of SMC. The closed-loop control quantities are obtained by solving a rolling optimization problem in the finite time domain to provide dynamic optimal control action. The theoretical derivation of the Lyapunov function is used to demonstrate the system's stability. In order to verify the effectiveness of the proposed algorithm, numerical simulations and Photovoltaic power generation system simulation experiments are conducted, respectively, and the results show that the proposed control algorithm has a very reliable tracking capability and control accuracy.

INDEX TERMS Adaptive observer, model free, sliding mode predictive control, rolling optimization, data-driven

I. INTRODUCTION

In recent years, adaptive control techniques for nonlinear systems have attracted a large number of scholars and much effort has been devoted to them [1]–[3]. However, most methods require dynamical or mechanistic analysis of the control system to obtain an accurate mathematical model first, and there are inevitably approximation links throughout the process [4]. In contrast, the ignored unmodeled dynamics part may be a potential factor that makes the closed-loop system unstable and reduces the controller performance.

Model-free adaptive control (MFAC) is a data-driven control method for discrete-time nonlinear systems to improve modeling difficulties [5], and its most important features compared to other data-driven control methods are the equivalent dynamic linearization process and the introduction of virtual parameters (PPD). MFAC uses the input and output data of the system to update the virtual parameters online dynamically, thus establishing an equivalent data model, both the PPD and the data model, which depend merely on the data and are unrelated to the structural information of the system, thus thoroughly characterizing the nonlinear and uncertain features of the system [6]. It has been widely used in the past few years, such as urban traffic control, heading control, zero-sum game control, flexible joint control, etc. [7]–[10].

As the research progresses, to further solve the uncertainty problem of the control system and ensure robust performance in control, some scholars bring the SMC into the MFAC algorithm to carry out the research, which produces the model-free adaptive sliding mode control (MFASC) scheme. Among them, the sliding phase of the SMC law ensures the excellent stability performance of the system, and the arrival phase determines the system's dynamic performance. For example, [11]

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