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A Comparative Experimental Study of Robust Sliding Mode Control Strategies for Underactuated SystemsBy: Din, SU (Din, Sami Ud)^[1]; Khan, Q (Khan, Qudrat)^[2]; Rehman, FU (Rehman, Fazal Ur)^[1]; Akmeliawanti, R (Akmeliawanti, Rini)^[3][View ResearcherID and ORCID](#)

IEEE ACCESS

Volume: 6 Pages: 1927-1939

DOI: 10.1109/ACCESS.2017.2780889

Published: 2018

Document Type: Article

[View Journal Impact](#)**Abstract**

This paper presents a comprehensive comparative study for the tracking control of a class of underactuated nonlinear uncertain systems. A given nonlinear model of the underactuated system is, at first stage, transformed into an input output form and the driving applied control input of the transformed system is then designed via four sliding mode control strategies, i.e., conventional first order sliding mode control, second order sliding mode, fast terminal sliding mode, and integral sliding mode. At second stage, a ball and beam system is considered and the aforementioned four control design strategies are experimentally implemented. A comprehensive comparative study of the simulation and experimental results is then conducted which take into account the tracking performance, i.e., settling time, overshoots, robustness enhancement, chattering reduction, sliding mode convergences, and control efforts.

Keywords**Author Keywords:** Electromechanical system; sliding mode control; Lyapunov method; robust control; nonlinear systems**KeyWords Plus:** PASSIVITY-BASED CONTROL; MECHANICAL SYSTEMS; INVERTED PENDULUM; TRACKING CONTROL; DESIGN; STABILIZATION**Author Information****Reprint Address:** Din, SU (reprint author)

Capital Univ Sci & Technol, Dept Elect Engrn, Islamabad 44000, Pakistan.

Addresses:

[1] Capital Univ Sci & Technol, Dept Elect Engrn, Islamabad 44000, Pakistan

+ [2] COMSATS Inst Informat Technol, Ctr Adv Studies Telecommun, Islamabad 44000, Pakistan

+ [3] Int Islamic Univ, Dept Mech Engrn, Kuala Lumpur 50728, Malaysia

E-mail Addresses: samiuddin@ieee.org**Funding**

Funding Agency	Grant Number
Higher Education Commission, Government of Pakistan	

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IEEE-INST ELECTRICAL ELECTRONICS ENGINEERS INC, 445 HOES LANE, PISCATAWAY, NJ 08855-4141 USA

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