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Control of PEMFC Air-Feed System Using Lyapunov-Based Robust and Adaptive Higher Order Sliding Mode Control

Salah Laghrouche, Mohamed Harmouche, Fayez Shakil Ahmed, and Yacine Chitour

Abstract—In this brief, we present Lyapunov-based robust and adaptive higher order sliding mode (HOSM) controllers for the air-feed system of polymer electrolyte membrane fuel cells, which is a nonlinear single-input, single-output system with bounded uncertainty. The system consists of a motorized compressor, which is driven at its optimal point in order to minimize the internal energy consumption of the system. This brief provides an experimental demonstration of the applicability of the recently developed fixed-gain robust controller and adaptive controller for this problem. Third-order controllers are developed in order to obtain a continuous profile for the input current of the compressor motor. In this regard, a complete adaptive arbitrary HOSM control has been presented for the first time, with Lyapunov-based proof. A performance comparison between the two controllers is presented in the end.

Index Terms—Adaptive control, finite time stabilization, higher order sliding mode (HOSM), Lyapunov analysis, polymer electrolyte membrane fuel cell (PEMFC), robust control.

I. INTRODUCTION

FUEL cells and their auxiliary systems pose challenging control problems, as they are typically nonlinear and difficult to characterize. They require robust or adaptive control methods, as their physical parameters are uncertain, varying with operating conditions and environmental effects. One important control problem in polymer electrolyte membrane fuel cell (PEMFC) systems is the minimization of the power consumed internally by their air-feed systems, in order to maximize the net power output. In particular, a PEMFC needs a sufficient quantity of excess air (oxygen excess) in its cathode in order to respond to load variations and transitions without damaging itself [1]. On the other hand, it has been established that the power consumption of air-feed compressors is the highest among all auxiliary systems of the fuel cell, rising up to 20% of the total PEMFC

power output [1]. Therefore, the air-feed system requires precise control for running the compressor at its optimal operating point, thereby maximizing the net power output of the fuel cell while keeping the oxygen excess ratio high enough for proper operation [2], [3].

Higher order sliding mode control (HOSMC) [4] is a well-established control strategy for uncertain nonlinear systems, as it is insensitive to parametric uncertainty and external disturbance. Unlike classical sliding mode, HOSMC does not suffer from high-frequency chattering because the characteristic discontinuous control [5] acts upon a higher derivative of the sliding variable. If the bounds of parametric uncertainty in the system are known, then fixed-gain HOSM controllers can be designed with relative ease. However, this is usually difficult in practical cases, as the estimation of uncertainty bounds requires rigorous experimentation in worst case conditions. In these cases, adaptive-gain (or simply adaptive) controllers provide a successful means of controlling the system through dynamically adapting gains. However, these controllers ensure practical convergence only, i.e., to a neighborhood of the origin. Many fixed-gain arbitrary robust HOSMC algorithms exist in contemporary literature, prominent examples being [6]–[9]. Huang *et al.* [10] were the first to use dynamic gain adaptation in SMC for the problem of unknown uncertainty bound, following [11] and [12]. Other works in this domain include [13]–[16]. These contributions remain limited to first- and second-order sliding mode. Initial findings on Lyapunov-based robust and (partial) adaptive arbitrary HOSMC were recently presented in [17].

Sliding mode controllers have been studied for PEMFC air-feed system control as well in [18]–[20], and two important examples of second-order SMC (SOSMC) are [21] and [22]. In the former, the oxygen excess ratio is assumed to have a static relationship with the compressor flow rate, and the compressor is controlled using SOSMC. In the latter, the authors have proposed a dual loop Cascade SOSMC controller, which address the compressor speed reference and current control individually. This approach is more practical as both the control loops are robust; however, its implementation requires different loop rates for controllers. Approaching this problem by third-order-sliding-mode-based oxygen excess ratio controllers appears to be a better approach in comparison with both these methods, as third-order extension results in continuous current control of the motocompressor. Adaptive third-order controllers would provide further ease in control design as precise parameters of the otherwise complex system need not be known.

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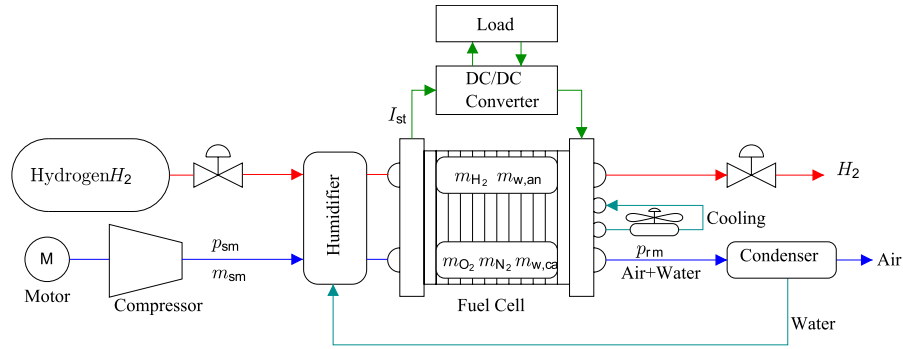


Fig. 1. Fuel cell air-feed system.

In this brief, the robust and adaptive approaches of [17] are extended and applied to the HOSM control of the PEMFC air-feed systems. The objective is to operate the air-feed compressor at its optimal point with respect to the load current, thereby maintaining the required oxygen excess ratio while keeping the power consumption low. There are two major contributions in this brief. First, it is shown that if the bounds of parametric uncertainty are known, then the air-feed control problem can be practically solved with the third-order robust HOSMC controller of [17]. The second main contribution in this brief is the extension of the partial adaptive controller presented in [17] to develop, for the first time, a complete adaptive arbitrary order sliding mode controller. The adaptation dynamics use a saturation function that results in rapid increase as well as rapid decrease of gains when the sliding variable and its derivatives are, respectively, outside and inside of a defined neighborhood of zero. The advantages of this adaptive controller design are its arbitrary order and its fast adaptation rates in both directions. The Lyapunov function defines sufficient conditions for controller parameters in order to ensure convergence to a defined neighborhood. The practical applicability of both the robust and adaptive controllers is demonstrated on a hardware-in-loop (HIL) air-feed test bench, using a real-time physical PEMFC emulator. A comparative analysis of the performances of the robust and adaptive controller is also presented.

This brief is organized as follows. The PEMFC air-feed system is described in Section II. HOSM problem formulation and robust and adaptive control design are discussed in Section III. Their implementation and experimental results are shown in Section IV. Finally, the conclusions are drawn in Section V.

II. PEMFC AIR-FEED SYSTEM

The PEMFC air-feed system (Fig. 1) feeds the fuel cell cathode with air (as the source of oxygen). It consists of a motocompressor and a manifold, in which a certain quantity of air (oxygen excess) is maintained such that the reaction between hydrogen and oxygen is continuous, without any interruption. Maintaining sufficient oxygen excess is critical for the PEMFC, as insufficient air leads to oxygen starvation during load transitions, where a sudden high load imposes a sudden increase in the rate of reaction. The dynamic model of

a fuel cell air-feed system is as follows [22]:

$$\begin{aligned} \dot{x}_1 &= c_1(x_4 - x_1 - x_2 - c_2) \\ &\quad - \frac{c_3 x_1}{c_4 x_1 + c_5 x_2 + c_6} c_{17} \sqrt{x_1 + x_2 + c_2 - c_{11}} - c_7 \zeta \\ \dot{x}_2 &= c_8(x_4 - x_1 - x_2 - c_2) \\ &\quad - \frac{c_3 x_2}{c_4 x_1 + c_5 x_2 + c_6} c_{17} \sqrt{x_1 + x_2 + c_2 - c_{11}} \\ \dot{x}_3 &= -c_9 x_3 - c_{10} \left[\left(\frac{x_4}{c_{11}} \right)^{c_{12}} - 1 \right] + c_{13} u \\ \dot{x}_4 &= c_{14} \left[1 + c_{15} \left[\left(\frac{x_4}{c_{11}} \right)^{c_{12}} - 1 \right] \right] \\ &\quad [W_{cp} - c_{16}(x_4 - x_1 - x_2 - c_2)] \end{aligned} \quad (1)$$

$$u = I_q, \quad \zeta = I_{st}, \quad W_{cp} = c_{21} \omega_{cp}. \quad (2)$$

The physical quantities that form the state vector x are

$$x = [x_1 \ x_2 \ x_3 \ x_4]^T = [p_{O_2} \ p_{N_2} \ \omega_{cp} \ p_{sm}]^T$$

where p_{O_2} and p_{N_2} represent the oxygen partial pressure and the nitrogen partial pressure, respectively. The compressor speed is denoted by ω_{cp} and the supply manifold pressure is denoted by p_{sm} . The control input u is the motor current, whereas the fuel cell stack current ζ is considered as measurable input disturbance. The compressor airflow is denoted by W_{cp} and it is proportional to the compressor speed. The parameters c_i are considered as uncertain constants, decomposed as $c_i = c_{0i} + \delta c_i$, where c_{0i} and δc_i are the nominal value and the uncertainty of c_i , respectively. Complete details and physical significance of these parameters can be found in [22].

A. Control Objective

The control problem in the PEMFC system is to ensure a certain excess amount of air in the cathode while minimizing the energy consumed by the air-feed compressor. The oxygen excess ratio can be written as [22]

$$\lambda_{O_2} = \frac{c_{19}}{c_{20} \zeta} (x_4 - x_1 - x_2 - c_2). \quad (3)$$

The net electrical power is optimized by reducing the consumption of the compressor, i.e., maintaining the oxygen excess ratio λ_{O_2} at its reference optimal value $\lambda_{O_2,ref}$, which is determined as a function of the stack current ζ [22]

$$\begin{aligned} \lambda_{O_2,ref} &= 5 \times 10^{-8} \zeta^3 - 2.87 \times 10^{-5} \zeta^2 + 2.23 \\ &\quad \times 10^{-3} \zeta + 2.5. \end{aligned} \quad (4)$$

158 Our objective is to force λ_{O_2} to follow $\lambda_{O_2,ref}$ in finite
159 time.

160 III. HIGHER ORDER SLIDING MODE CONTROLLERS

161 In this section, we will first recall the preliminary formu-
162 lation of the HOSM control problem and the robust HOSM
163 controller of [17]. Then, based on the initial findings of [17],
164 the complete adaptive HOSM controller will be presented. Let
165 us consider an uncertain nonlinear system

$$166 \begin{cases} \dot{x}(t) = f(x, t) + g(x, t)u \\ y(t) = s(x, t) \end{cases} \quad (5)$$

167 where $x \in \mathbb{R}^n$ is the state vector and $u \in \mathbb{R}$ is the control
168 input. The sliding variable s is a measured smooth output-
169 feedback function and $f(x, t)$ and $g(x, t)$ are uncertain smooth
170 functions. It is assumed that the relative degree r of the
171 system is globally well defined, uniform, and time-invariant,
172 and the associated zero dynamics are asymptotically stable [9].
173 Then, for suitable functions $\tilde{\varphi}(x, t)$ and $\tilde{\gamma}(x, t)$, (5) can be
174 rewritten as

$$175 y^{(r)}(t) = \tilde{\varphi}(x(t), t) + \tilde{\gamma}(x(t), t)u(t). \quad (6)$$

176 The functions $\tilde{\gamma}(x(t), t)$ and $\tilde{\varphi}(x(t), t)$ are assumed to be
177 bounded by positive constants γ_m , γ_M , and $\bar{\varphi}$, such that

$$178 0 < \gamma_m \leq \tilde{\gamma}(x(t), t) \leq \gamma_M, \quad |\tilde{\varphi}(x(t), t)| \leq \bar{\varphi}. \quad (7)$$

179 Defining $s^{(i)} := d^i/dt^i y$, the goal of r th order SMC is to
180 arrive at, and keep the following manifold in finite time:

$$181 s^{(0)}(x, t) = s^{(1)}(x, t) = \dots = s^{(r-1)}(x, t) = 0. \quad (8)$$

182 To be more precise, for $z = [z_1 \ z_2 \ \dots \ z_r]^T := [s \ \dot{s} \ \dots \ s^{(r-1)}]^T$,
183 (8) is equivalent to $z = 0$. It is natural to replace (5) with a
184 more general control system based on (7)

$$185 \begin{aligned} \dot{z}_i &= z_{i+1}, \quad i = 1, \dots, r-1 \\ \dot{z}_r &= \varphi(t) + \gamma(t)u \in I_\varphi + uI_\gamma \end{aligned} \quad (9)$$

187 where the new functions φ and γ are arbitrary measurable
188 functions, bounded such that

$$189 \varphi(t) \in [-\bar{\varphi}, \bar{\varphi}], \quad \gamma(t) \in [\gamma_m, \gamma_M] \quad (10)$$

190 where $\bar{\varphi}$, γ_m , and γ_M are positive constants. This system
191 represents a perturbed integrator chain. The objective of this
192 brief is to design controllers that stabilize (9) to the origin,
193 ideally in finite time. Since these controllers are to be discon-
194 tinuous feedback laws $u = U(z)$, solutions of (9) need to be
195 understood here in Filippov sense [23].

196 A. Robust Higher Order Sliding Mode Controller

197 Let us first recall the robust controller [17], which is
198 designed to (9), assuming that the bounds $\bar{\varphi}$, γ_m , and
199 γ_M are known. This controller has been derived from a
200 class of Lyapunov-based controllers that guarantee finite-
201 time stabilization of pure chain of integrators ($\varphi \equiv 0$
202 and $\gamma \equiv 1$) [24], and satisfy certain additional geometric
203 conditions. Let us consider that the initial states of the system
204 are in a neighborhood of origin, $\hat{U} \subset \mathbb{R}^r$. Then, the main
205 result of [17] is given as follows.

Theorem 1: If there exists a controller $u_0(z)$ that stabilizes
a pure integrator chain in finite time and there exists a C^1
function V_1 defined on the neighborhood $\hat{U} \subset \mathbb{R}^r$, such that:

- 1) $\dot{V}_1 + cV_1^\alpha(z(t)) \leq 0$, if $z(t) \in \hat{U}$;
- 2) $\frac{\partial V_1}{\partial z_r} u_0 \leq 0$;
- 3) $u_0 = 0 \Rightarrow \frac{\partial V_1}{\partial z_r} = 0$.

Then, the following control law establishes HOSM on (9) with
respect to s :

$$u = \frac{1}{\gamma_m} (u_0 + \bar{\varphi} \text{sign}(u_0)). \quad (11)$$

The detailed proof of this theorem can be found in [17].
It can be verified that many controllers, such as those
of [25] and [26], fulfill the conditions demanded in Theorem 2.
For the rest of this brief, we consider Hong's controller [25],
which is defined as follows.

Let $k < 0$ and l_1, \dots, l_r positive real numbers and $|a|^\theta :=$
 $|a|^\theta \text{sign}(a)$, $\forall a \in \mathbb{R}, \theta > 0$. For $z = (z_1, \dots, z_r)$, we define
for $i = 0, \dots, r-1$

$$182 \begin{aligned} p_i &= 1 + (i-1)k \\ v_0 &= 0, \quad v_{i+1} = -l_{i+1} [|z_{i+1}|^{\beta_i} - |v_i|^{\beta_i}]^{\alpha_{i+1}/\beta_i} \end{aligned} \quad (12)$$

where $\alpha_i = p_{i+1}/p_i$, for $i = 1, \dots, r$, and, for $k < 0$ suffi-
ciently small, we have $\beta_0 = p_2$, $(\beta_i + 1)p_{i+1} = \beta_0 + 1 > 0$,
 $i = 1, \dots, r-1$.

182 B. Adaptive Controller

Let us now consider the case where uncertainty bounds
 γ_m , γ_M , and $\bar{\varphi}$ of (9) are unknown. In [17], this problem
was partially solved and a controller was developed which
could function without any explicit knowledge of $\bar{\varphi}$. We now
present a complete arbitrary HOSM controller that can be
designed without the knowledge of bounds of either uncertain
function. Let us first define $\sigma(a)$ as the standard saturation
function, $\sigma(a) = (a/\max(1, |a|))$, $a \in \mathbb{R}$. For $\varepsilon > 0$, $a \in \mathbb{R}$,
we define

$$v_\varepsilon(a) = \frac{1}{2} + \frac{1}{2} \sigma \left(\frac{|a| - \frac{3}{4}\varepsilon}{\frac{1}{4}\varepsilon} \right).$$

We now propose the following controller:

$$u = \hat{\gamma} u_0(z) + \hat{\varphi} \text{sign}(u_0(z)) \quad (13)$$

where u_0 is a homogeneous controller, as defined
in Theorem 1. The adaptive function $\hat{\gamma} = \kappa + \delta|u_0(z)|$
and $\hat{\varphi}(t)$ is defined by the ordinary differential
equation

$$\dot{\hat{\varphi}}(t) = kv_\varepsilon(V_1(z)) - (1 - v_\varepsilon(V_1(z))) [\hat{\varphi}]^\eta$$

with the initial condition $\hat{\varphi}(0) = 0$. The new terms are defined
as $\kappa, \delta > 0$, $\eta \in (0, 1)$, $k > 0$, and V_1 is a homogeneous
Lyapunov function which also satisfies Theorem 1. The
following theorem provides the main result for the adaptive
controller.

Theorem 2: Consider (9) under the feedback control
law (13). Then, $\forall \varepsilon, \exists c' > 0$ and $0 < \alpha' < 1$ such that
the following conditions are satisfied for any initial condition
 $z_0 \in \hat{U}$.

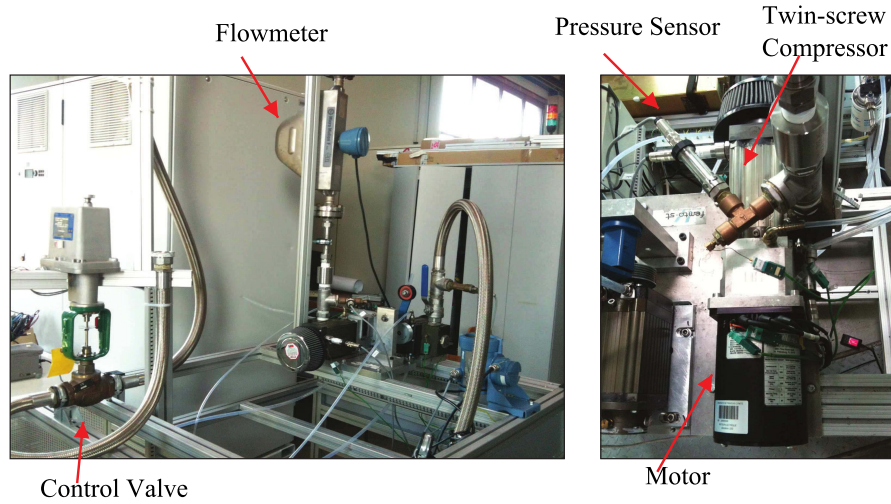


Fig. 2. Test bench.

- AQ:3 250 1) $\liminf_{t \rightarrow \infty} V_1(z(t)) \leq \varepsilon$, $\limsup_{t \rightarrow \infty} V_1(z(t)) \leq \Delta$.
 251 2) $\limsup_{t \rightarrow \infty} |\hat{\phi}| \leq 2\bar{\Phi} + k(\Delta^{1-\alpha}/(c(1-\alpha)))$

252 where

$$253 \quad \bar{\Phi} := \frac{1}{\gamma_m} \left(\bar{\varphi} + \frac{(\kappa\gamma_m - 1)^2}{4\gamma_m\delta} \right)$$

$$254 \quad \Delta := \left(\varepsilon^{1-\alpha'} + \frac{c'(1-\alpha')\gamma_m}{2k} \bar{\Phi}^2 \right)^{\frac{1}{1-\alpha'}}$$

255 *Proof of Theorem 2:* We first demonstrate that the controller
 256 brings the system states from any domain $V_1 > \varepsilon$ to the
 257 domain $V_1 \leq \varepsilon$ in finite time. Then, it is proved that once
 258 z reaches the domain $V_1 \leq \varepsilon$, it stays in the domain $V_1 \leq \Delta$
 259 for all consecutive time instances and $\hat{\phi}$ is upper bounded after
 260 a sufficiently large time.

261 *Lemma 1 [17]:* The function $\hat{\phi}$ is non-negative and is
 262 defined as long as the trajectory of z is defined.

263 Now, let us use contradiction again, to show
 264 $\liminf_{t \rightarrow \infty} V_1(z(t)) \leq \varepsilon$. Supposing that there exists \bar{t}
 265 such that $V_1(t) > \varepsilon$ for every $t \geq \bar{t}$, then according to the
 266 dynamics of $\hat{\phi}$, we get $\dot{\hat{\phi}} = k$ for $t \geq \bar{t}$. This implies that
 267 for $t \geq \bar{t}$, $\hat{\phi}$ is increasing and $\hat{\phi} > \bar{\Phi}$. The derivative of the
 268 Lyapunov function is

$$269 \quad \dot{V}_1 = \frac{\partial V_1}{\partial z_1} z_2 + \dots + \frac{\partial V_1}{\partial z_r} (\gamma[\hat{y}u_0 + \hat{\phi}\text{sign}(u_0)] + \varphi)$$

$$270 \quad = \frac{\partial V_1}{\partial z_1} z_2 + \dots + \frac{\partial V_1}{\partial z_r} u_0 + \frac{\partial V_1}{\partial z_r}$$

$$271 \quad \times (-u_0 + \kappa\gamma u_0 + \gamma\delta|u_0|^2 + \gamma\hat{\phi}\text{sign}(u_0) + \varphi)$$

$$272 \quad \leq -cV_1^\alpha - \left| \frac{\partial V_1}{\partial z_r} \right| \left((\kappa\gamma_m - 1)|u_0| + \gamma_m\delta|u_0|^2 + \gamma_m\hat{\phi} - \bar{\varphi} \right)$$

$$273 \quad \leq -cV_1^\alpha - \gamma_m \left| \frac{\partial V_1}{\partial z_r} \right| (\hat{\phi} - \bar{\Phi}) \leq -cV_1^\alpha \quad (14)$$

274 then, $V_1(z)$ converges to zero in finite time, which contradicts
 275 the hypothesis. The functions u_0 and V_1 are homogeneous,
 276 which according to [27], means that $\exists c', \alpha' > 0 : |\partial V_1/\partial z_r| \leq$
 277 $c'V_1^{\alpha'}$, where $c' = \max_{\{z: V_1(z)=1\}} |\partial V_1/\partial z_r|$, $\alpha' = \kappa_2/\kappa_1$. The
 278 terms κ_2 and κ_1 are the respective degrees of homogeneity
 279 of $\partial V_1/\partial z_r$ and V_1 . We suppose now that $V_1 < \varepsilon$. Let us

estimate the overshoot in the worst case condition with respect
 to uncertainty. For $V_1(z(0)) = \varepsilon$ and $\hat{\phi}(0) = 0$, we get

$$282 \quad \dot{V}_1 \leq -cV_1^\alpha - \gamma_m c' V_1^{\alpha'} (\hat{\phi} - \bar{\Phi}), \quad \dot{\hat{\phi}} = k. \quad (15)$$

283 The overshoot Δ of V_1 holds for $\dot{V}_1 = 0$ at $t = T_M$. We get
 284 $\hat{\phi}(T_M) = \bar{\Phi} - c\Delta^{\alpha-\alpha'}/c'\gamma_m \leq \bar{\Phi}$, and then $T_M \leq \bar{\Phi}/k$.
 285 An upper bound of Δ can be estimated as

$$286 \quad \Delta = \left(\varepsilon^{1-\alpha'} + \frac{c'(1-\alpha')\gamma_m}{2k} \bar{\Phi}^2 \right)^{\frac{1}{1-\alpha'}}$$

287 For an upper bound of $\limsup_{t \rightarrow \infty} \hat{\phi}$, consider the case
 288 $V_1(z(0)) = \varepsilon$ with $\dot{V}_1(z(0)) \geq 0$, in this case we have
 289 $\hat{\phi}(0) < \bar{\Phi}$. For $t = T_M$, i.e., $\dot{V}_1 = 0$, we get $\hat{\phi}(T_M) \leq$
 290 $\bar{\Phi} + \hat{\phi}(0) \leq 2\bar{\Phi}$. $\hat{\phi}$ will increase until time T_f where
 291 $\dot{\hat{\phi}}(T_f) = 0$ and $V_1(z(T_f)) \geq 0$. The worst case is calculated
 292 with respect to the boundary of $\hat{\phi}$, using $\dot{V}_1 \leq -cV_1^\alpha$
 293 and $\dot{\hat{\phi}} = k$. Here, T_f corresponds to $V_1(z(T_f)) = 0$,
 294 i.e., $T_f T_M = (\Delta^{1-\alpha})/(c(1-\alpha))$, which implies that
 295 $\hat{\phi}(T_f) \leq \hat{\phi}(T_M) + k(T_f T_M) = 2\bar{\Phi} + k\Delta^{(1-\alpha)}/c(1-\alpha)$. \square

296 *Remark 1:* The second inequality of 1) of Theorem 2 is
 297 equivalent to Levant's concept of real HOSM [28], defined as

$$298 \quad \exists t_1 > 0 : \forall t > t_1, |z_i(t)| \leq \mu_i, \quad i = 1, \dots, r-1$$

299 where μ_i is an arbitrarily small positive number. This is
 300 equivalent to practical stability of z_1, \dots, z_r .

301 IV. DESIGN AND IMPLEMENTATION

302 Let us now turn toward design of the robust and adaptive
 303 controllers presented in Section III, for PEMFC air-feed
 304 system application. As mentioned previously, third-order
 305 controllers will be designed in order to obtain a smooth
 306 current profile. The test bench is described first in order to
 307 present a physical outlook of the system under consideration.
 308 Then, the designed controllers and experimental results are
 309 presented.

310 A. Test Bench Description

311 The experiments have been conducted on a HIL test bench,
 312 presented in Figs. 2 and 3. This bench consists of a twin-
 313 screw compressor air-feed system coupled with a real time

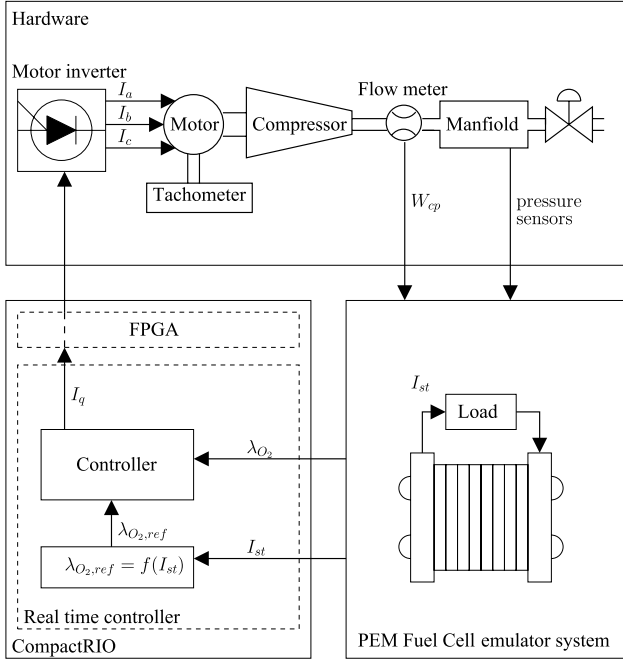


Fig. 3. HIL simulator.

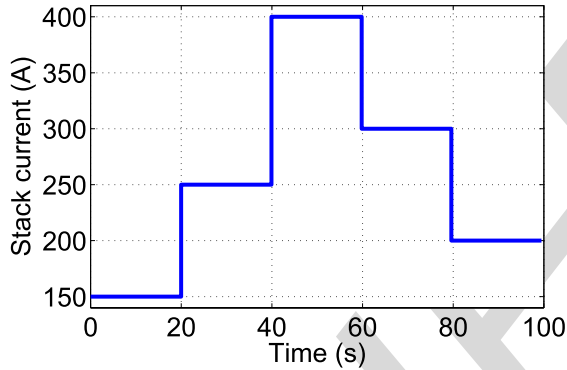


Fig. 4. Stack current (A).

329 33-kW fuel cell emulator. The twin-screw compressor is driven
 330 by a permanent magnet synchronous motor (PMSM). The
 331 three-phase currents of PMSM are calculated from dq
 332 coordinates and supplied by an inverter. The control input I_q
 333 is generated by the proposed controllers installed in a real-time
 334 controller and fed to the inverter. The measured compressor
 335 airflow W_{cp} is fed to the real-time fuel cell emulation system.
 336 The PEMFC emulator receives the flow rate W_{cp} , in order
 337 to generate the states x_1 , x_2 , x_4 , and λ_{O_2} (see Section II
 338 for physical description of the states). Its physical parameters
 339 can be varied to emulate the effect of external operating
 340 conditions on the fuel cell. The output load is simulated as
 341 variable stack current steps between 150 and 400 A, in steps.
 342 The load profile used in the tests for this brief is shown
 343 in Fig. 4.

329 B. Controller Design and Experimental Results

330 Let us consider (1) and the equations of λ_{O_2} and $\lambda_{O_2,ref}$,
 331 i.e., (3) and (4). The system parameters are given in [22].
 332 The sliding variable is defined as $z_1 = s = \lambda_{O_2} - \lambda_{O_2,ref}$.

333 In our case, the sliding variable s depends on x_1 , x_2 , and x_4 .
 334 The first and second time derivative of s are

$$\begin{aligned}
 \dot{s} = z_2 &= \frac{\partial}{\partial x_1} s(x_1, x_2, x_4) \cdot \dot{x}_1(x_1, x_2, x_4) & 335 \\
 &+ \frac{\partial}{\partial x_2} s(x_1, x_2, x_4) \cdot \dot{x}_2(x_1, x_2, x_4) & 336 \\
 &+ \frac{\partial}{\partial x_4} s(x_1, x_2, x_4) \cdot \dot{x}_4(x_1, x_2, x_3, x_4) & 337 \\
 \ddot{s} = z_3 &= \frac{\partial}{\partial x_1} \dot{s}(x_1, x_2, x_3, x_4) \cdot \dot{x}_1(x_1, x_2, x_4) & 338 \\
 &+ \frac{\partial}{\partial x_2} \dot{s}(x_1, x_2, x_4) \cdot \dot{x}_2(x_1, x_2, x_4) & 339 \\
 &+ \frac{\partial}{\partial x_3} \dot{s}(x_1, x_2, x_3, x_4) \cdot \dot{x}_3(x_3, x_4, u) & 340 \\
 &+ \frac{\partial}{\partial x_4} \dot{s}(x_1, x_2, x_3, x_4) \cdot \dot{x}_4(x_1, x_2, x_3, x_4). & 341
 \end{aligned}$$

342 The control input u appears for the first time in the second
 343 time derivative of s . To obtain a continuous control u , the
 344 discontinuous control is applied on the higher derivative \dot{u} .
 345 We get

$$s^{(3)} = \dot{z}_3 = \underbrace{\dot{\phi} + \dot{\gamma} u + \gamma v}_{\Phi} \quad 346$$

347 where $v = \dot{u}$, Φ , and γ are uncertain bounded functions that
 348 satisfy

$$\Phi \in [-\bar{\phi}, \bar{\phi}], \quad \gamma \in [\gamma_m, \gamma_M]. \quad 349$$

350 For the PEMFC under consideration, the bounding values
 351 of the parameters were determined as percentage deviations
 352 through precise physical analyses. The numerical values of
 353 the uncertainty limits were obtained as $\bar{\phi} = 0.03$, $\gamma_m = 5$,
 354 and $\gamma_M = 15$.

355 From here, the control objective becomes equivalent to
 356 forcing s , and its first and second time derivatives to
 357 zero in finite time, through $s^{(3)} \in [-\bar{\phi}, \bar{\phi}] + [\gamma_m, \gamma_M]v$.
 358 We first develop a third-order SMC robust controller
 359 using (11) and (12). According to Theorem 1, the controller
 360 takes the following structure:

$$\begin{aligned}
 v_1 &= -l_1 |s|^{\alpha_1} & 361 \\
 v_2 &= -l_2 [|\dot{s}|^{\beta_1} - |v_1|^{\beta_1}]^{\alpha_2/\beta_1} & 362 \\
 v_3 &= -l_3 [|\ddot{s}|^{\beta_2} - |v_2|^{\beta_2}]^{\alpha_3/\beta_2} & 363 \\
 v &= \dot{u} = \frac{1}{\gamma_m} (v_3 + \bar{\phi} \text{sign}(v_3)). & 364
 \end{aligned} \quad (17)$$

365 In this test, the parameters have been tuned to the following
 366 values: $l_1 = 5$, $l_2 = 10$, $l_3 = 40$, $\beta_0 = 0.8$, $\beta_1 = 1.25$,
 367 $\beta_2 = 2$, $\alpha_1 = 4/5$, $\alpha_2 = 3/4$, $\alpha_3 = 2/3$, $\gamma_m = 5$, $\bar{\phi} = 0.03$.

368 The load variations (Fig. 4) result in changes in $\lambda_{O_2,ref}$,
 369 according to (4). The performance of the robust controller
 370 with respect to these changes is shown in Fig. 5. It can
 371 be seen in Fig. 5(a) that λ_{O_2} tracks $\lambda_{O_2,ref}$ successfully
 372 with a response time between 3 and 7 s practically.
 373 The control input (I_q) is shown in Fig. 5(b), it varies
 374 between 0 and 3 A. As the controller establishes third-order
 375 HOSM, the oscillations in I_q are negligible and it has a smooth
 376 profile.

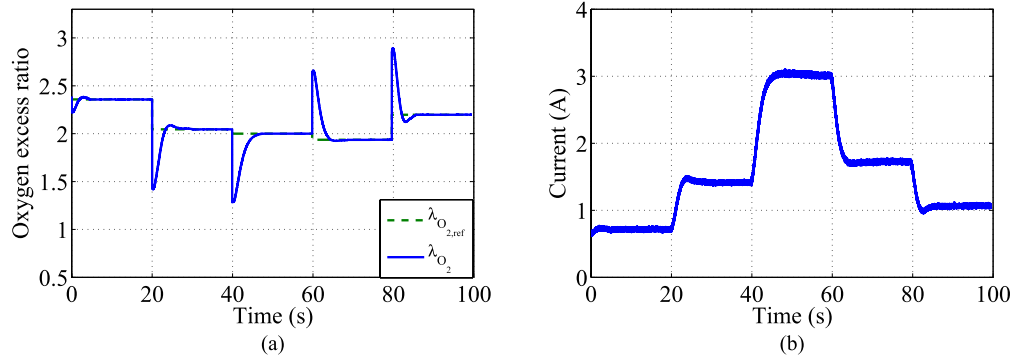


Fig. 5. Robust controller. (a) λ_{O_2} . (b) I_q .

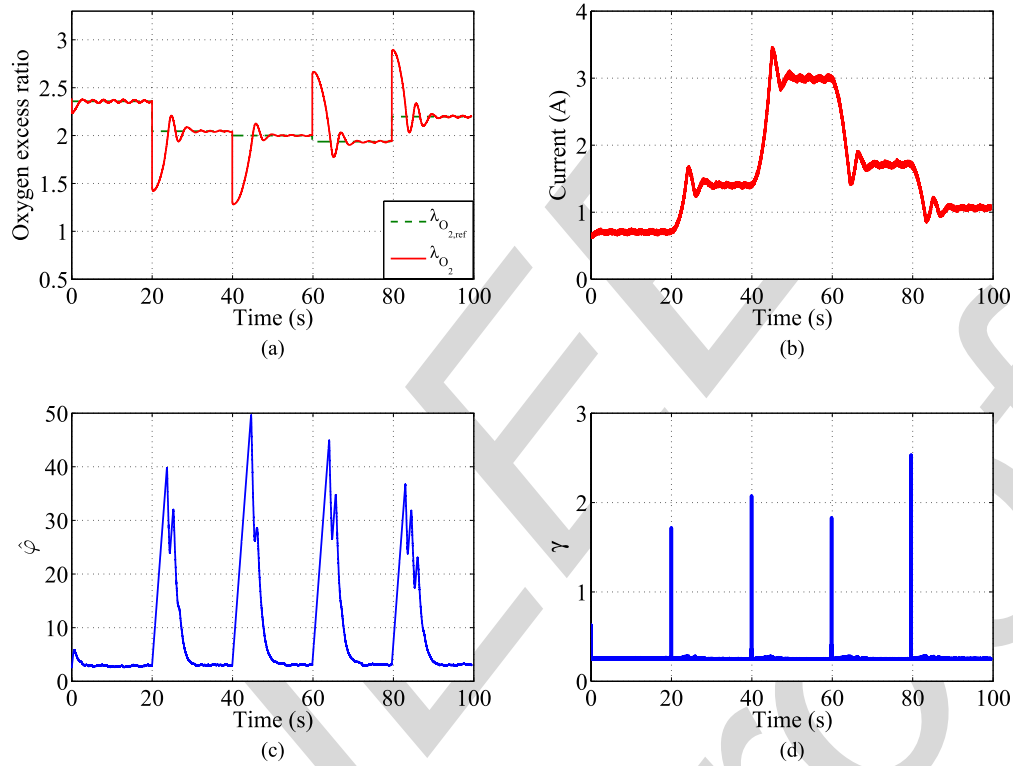


Fig. 6. Adaptive controller. (a) λ_{O_2} . (b) I_q . (c) $\hat{\phi}$. (d) $\hat{\gamma}$.

377 We will now demonstrate the proposed adaptive controller
 378 for the same problem, assuming that we have no knowledge
 379 of the uncertainty bounds. The third-order SMC adaptive
 380 controller is designed using (12) and (13). According
 381 to Theorem 3, the controller has the following structure:

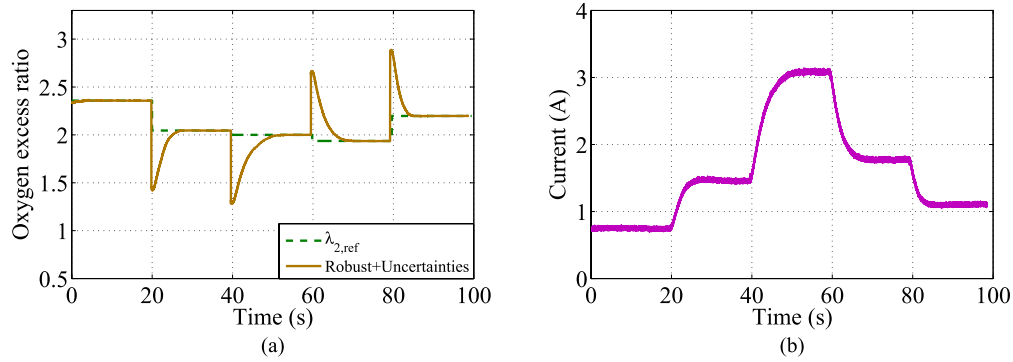
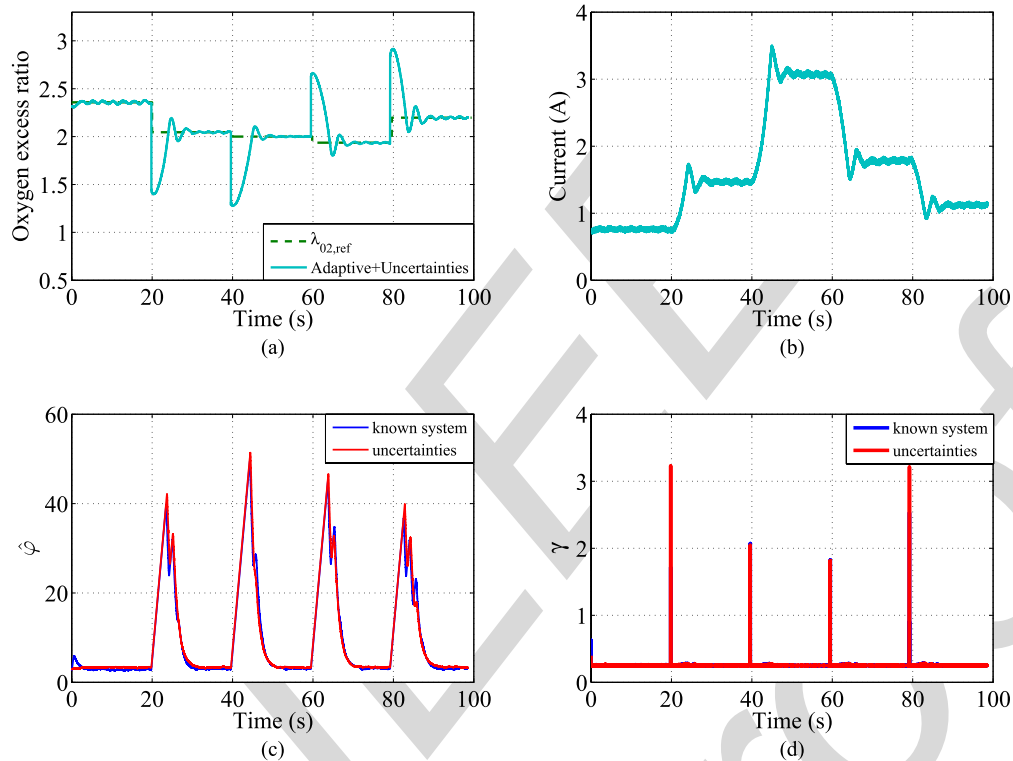
$$v = \dot{u} = \hat{\gamma} v_3 + \hat{\phi} \text{sign}(v_3) \quad (18)$$

383 where v_3 is the same as in (17). The controller
 384 parameters used in adaptive case are as follows: $l_1 = 5$,
 385 $l_2 = 10$, $l_3 = 40$, $\beta_0 = 0.8$, $\beta_1 = 1.25$, $\beta_2 = 2$,
 386 $\alpha_1 = 4/5$, $\alpha_2 = 3/4$, $\alpha_3 = 2/3$, $k = 5$, $\eta = 0.95$,
 387 $\varepsilon = 0.001$, $\kappa = 0.25$, $\delta = 0.001$.

388 The results of the adaptive controller are shown in Fig. 6.
 389 Fig. 6(a) shows that λ_{O_2} converges and remains inside a small
 390 and acceptable neighborhood around the desired value $\lambda_{O_2,ref}$.
 391 The control input, I_q is shown in Fig. 6(b) and the behaviors of
 392 the adaptive parameters $\hat{\phi}$ and $\hat{\gamma}$ are shown in Fig. 6(c) and (d),

respectively. It can be seen that $\hat{\phi}$ increases at each stack
 393 current step, and then decreases rapidly after the convergence
 394 of the tracking error. As ideal sliding mode cannot be achieved
 395 in this case, small oscillations can be seen in $\hat{\gamma}$. In general,
 396 these results show the effectiveness of both the robust and
 397 adaptive controllers for a wide range of stack current variation,
 398 i.e., external perturbation.

399 To demonstrate the robustness of our controllers in dealing
 400 with parametric uncertainty, another series of experiments was
 401 conducted, in which the parameters of the PEMFC emulator
 402 were varied to their extreme values [22]. The designed
 403 controllers were again tested with the same controller
 404 parameters as determined before. The results of the robust
 405 controller in these tests are shown in Fig. 7. The system
 406 response in Fig. 7(a) and the control input in Fig. 7(b)
 407 show that this controller performs as well as in the previous
 408 tests with defined system parameter values. The results of
 409

Fig. 7. Robust controller (parametric shift). (a) λ_{O_2} . (b) I_q .Fig. 8. Adaptive controller (parametric shift). (a) λ_{O_2} . (b) I_q . (c) $\hat{\phi}$. (d) $\hat{\gamma}$.

410 the adaptive controller are shown in Fig. 8. We see again
 411 in Fig. 8(a) a similar behavior of tracking error as compared
 412 with the previous tests. However, the static value of the
 413 quadratic current [Fig. 8(b)] changes in order to accommodate
 414 the emulated parametric drift. The adaptive gains $\hat{\phi}$ and $\hat{\gamma}$
 415 adapt to counteract the uncertainty, ensuring convergence,
 416 as seen in Fig. 8(c) and (d). These tests demonstrate that both
 417 the robust and adaptive controllers are capable of handling
 418 parametric uncertainty, albeit with different mechanisms.

419 V. CONCLUSION

420 In this brief, the control problem of PEMFC air-feed system
 421 was addressed using two arbitrary HOSM controllers associ-
 422 ated with the finite-time stabilization of a perturbed chain of
 423 integrators with bounded uncertainty. The design of the first
 424 controller requires the knowledge of the uncertainty bounds.
 425 The second controller is adaptive and its design does not
 426 require any quantitative knowledge of the uncertainty bounds.

The arbitrary order nature of controllers permitted to extend
 the air-feed system from second to third order, resulting in
 continuous input current profile. The proposed controllers
 showed good performance in simulation and in experiments
 conducted on a PEMFC air-feed test bench.

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