

# Data-Driven Model-Free Adaptive Sliding Mode Control for Multi DC Motor Speed Regulation

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## Abstract

This paper proposes the distributed data-driven model-free adaptive sliding mode control approach to address the consensus problem of nonlinear multi-agent systems. Firstly, the equivalent data model for each agent is constructed using the compact-form dynamic linearization (CFDL) technique. Secondly, by utilizing process information from neighboring agents, the novel sliding surface is employed to ensure the boundedness of distributed measurement error. Subsequently, a distributed model-free adaptive sliding mode controller is developed for accurate consensus tracking. Finally, the effectiveness of the proposed control approach is verified through experiments on multi DC motor system.

## KEYWORDS

Data-driven control, model-free adaptive sliding mode control, nonlinear multi-agent systems, multi DC motor speed control.

## I. INTRODUCTION

Due to the excellent capabilities and coordination efficiency of distributed multi-agent systems (MASs) in various applications such as sensor networks, transportation systems, agriculture monitoring and industrial process systems [1]–[3], MASs have attracted significant attention. Over the past few years, one of the main challenges for collaborative control [4]–[6] is to handle consensus problem. It means that all agents can follow the same trajectory from different initial values. However, traditional model-based control strategies are not suitable for complex systems that are difficult to model accurately.

Despite their effectiveness in certain scenarios, traditional control strategies [10]–[13] heavily depend on precise system models, and the modeling process becomes increasingly challenging as technology grows rapidly. Under such circumstances, it becomes difficult to solve practical problems using the above schemes. In modern industrial environments, vast amounts of process information often containing implicit and complex dynamic behaviors of the system are continuously generated and stored during operation. As a result, there has been a growing interest in alternative control methods that rely on data modeling.

Therefore, how to use this data to achieve system consensus control has become a powerful new topic. The data-driven control [17]–[20] refers to control systems utilizing system I/O data solely. Various data-based approaches have been developed, including model-free adaptive control, iterative learning control, virtual reference feedback tuning [21], PID control [22] and others. Among these, the model-free adaptive control approach [23]–[25] has been proposed, and has a great significance in addressing the aforementioned challenges. The design process relies solely on I/O data of the system, significantly avoiding the reliance on mathematical models. The algorithm has proven effective in practical domains such as motor systems, chemical industries, and machinery, demonstrating the adaptability and usefulness of the algorithm.

Alternatively, sliding mode control [26] has emerged as a highly attractive approach for the control researchers due to the robustness to parameter uncertainties and the capability to ensure fast responses. Currently, the novel sliding mode control method based on I/O data is presented in [27], which eliminates the need for explicit system models. Although considerable progress has been made in controlling nonlinear MASs, the dynamic couplings and complex nonlinear behaviors among agents [14] can be challenging practical implementation.

However, the effectiveness of existing approaches [31]–[34] is limited in highly uncertain environments because they typically rely on input-affine structures with known or partially known dynamics. How to achieve consensus tracking problem utilizing the model-free adaptive sliding mode controller approach for nonlinear MASs remains an open question.

Inspired by the above discussions, this paper proposes a data-driven model-free adaptive sliding mode control scheme. The contributions of this paper are structured as follows:

- 1) This paper establishes the model-free adaptive sliding mode control approach, which enables consensus tracking in nonlinear MASs, even under system uncertainties and unknown dynamics.
- 2) The method utilizes CFDL to construct equivalent data models based purely on input-output data. This allows for the systematic design of controllers for each agent without requiring internal system knowledge, making it highly practical for real-time applications.
- 3) A novel distributed sliding surface is developed using neighboring agent process data. This structure ensures the boundedness of measurement errors and enhances the robustness and convergence of the system through a designed stability mechanism.

The following sections will outline the remaining content of this paper: section II provides preliminaries and problem formulation, Section III presents The main results, Section IV shows simulation results and performance analysis, demonstrating the effectiveness of the proposed method under distinct operating conditions. At the end, conclusions are summarized in Section V.

## II. PRELIMINARIES AND PROBLEM FORMULATION

### A. Directed Graph Theory

The directed graph  $\mathcal{G} = (\mathcal{V}, \mathcal{E}, \mathcal{A})$  is employed to describe the information exchange between agents. Here,  $\mathcal{A} = [a_{ij}] \in \mathbb{R}^{N \times N}$  represents the adjacency matrix,  $\mathcal{V} = \{v_1, v_2, \dots, v_N\}$  is the set of vertices, and  $\mathcal{E} = [(v_j, v_i) | v_i \in \mathcal{V}] \subseteq \mathcal{V} \times \mathcal{V}$  is the set of edges. Moreover,  $\mathcal{N}(i) = \{j \in \mathcal{V} | (i, j) \in \mathcal{E}\}$  denotes the neighbor set of agent  $i$ , where  $a_{ij} \neq 0$ . No self-loop is allowed in this article, which means  $(i, i) \notin \mathcal{E}$  for any  $i \in \mathcal{V}$ ,  $a_{ii} = 0$ . Furthermore, the degree matrix  $K = \text{diag}(k_1, \dots, k_N)$ . If  $k_i > 0$ , agent  $i$  can directly obtain the information from the leader. The Laplacian matrix  $L$  is defined as  $L = (\mathcal{D} - \mathcal{A})$ , here  $\mathcal{D} = \text{diag}(d_1, \dots, d_N)$  and  $d_i = \sum_{j=1}^N a_{ij}$  denotes the in-degree matrix. Moreover, the graph is strongly connected if the path exists between every pair of vertices.

### B. Problem Formulation

Consider the nonlinear multi-agent systems composed of  $N$  agents:

$$y_i(k+1) = f_i(y_i(k), u_i(k)), \quad i = 1, 2, \dots, N \quad (1)$$

where  $u_i(k) \in \mathbb{R}$  and  $y_i(k) \in \mathbb{R}$  represent the system input and output signals of agent  $i$ , respectively.  $f_i(\cdot)$  signifies an unknown nonlinear function.

Assumption 1: The partial derivative of  $f_i(\cdot)$  with respect to  $u_i(k)$  is continuous.

Assumption 2: The system (1) satisfies the generalized Lipschitz condition, meaning that if  $\Delta u_i(k) = u_i(k) - u_i(k-1) \neq 0$  then  $|\Delta y_i(k+1)| \leq b|\Delta u_i(k)|$  holds for any  $k$ , where  $\Delta y_i(k+1) = y_i(k+1) - y_i(k)$ .

Remark 1: The assumptions above are general. Assumption 1 is a general condition for controller design. Assumption 2 implies that the system input rate constrains the system output rate, which is satisfied in many practical systems.

Assumption 3: The communication graph  $\mathcal{G}$  is strongly connected, ensuring that each follower can directly receive information from at least one leader.

Lemma 1 [8]: Consider the nonlinear multi-agent system (1) satisfying above three assumptions. If  $|\Delta u_i(k)| \neq 0$  holds, then the system can be transformed into the CFDL data model as follows:

$$\Delta y_i(k+1) = \phi_i(k) \Delta u_i(k) \quad (2)$$

wherein  $\phi_i(k)$  is called pseudo partial derivative (PPD), satisfying  $|\phi_i(k)| \leq b$ .

The distributed measurement error of  $\xi_i(k)$  for  $N$  agents is established as:

$$\xi_i(k) = \sum_{j \in N_i} a_{ij}(y_j(k) - y_i(k)) + d_i(y_d(k) - y_i(k)) \quad (3)$$

if the agent  $i$  can receive data from the leader, then  $d_i = 1$ ; otherwise,  $d_i = 0$ . Additionally,  $y_d(k)$  represents the reference trajectory.

Remark 2: The CFDL technique requires no prior knowledge about the system dynamic model. Moreover, the dynamic behavior of time-varying PPD may be highly complex and difficult to verify.

### III. MAIN RESULTS

This section is divided in two parts. The first part introduces the model-free adaptive controller design, which is based on the CFDL technique. The second part introduces the sliding mode controller design, which is formulated based on the distributed measurement error. The overall block diagram of the proposed control scheme is shown in Fig. 1, which illustrates the system control process.

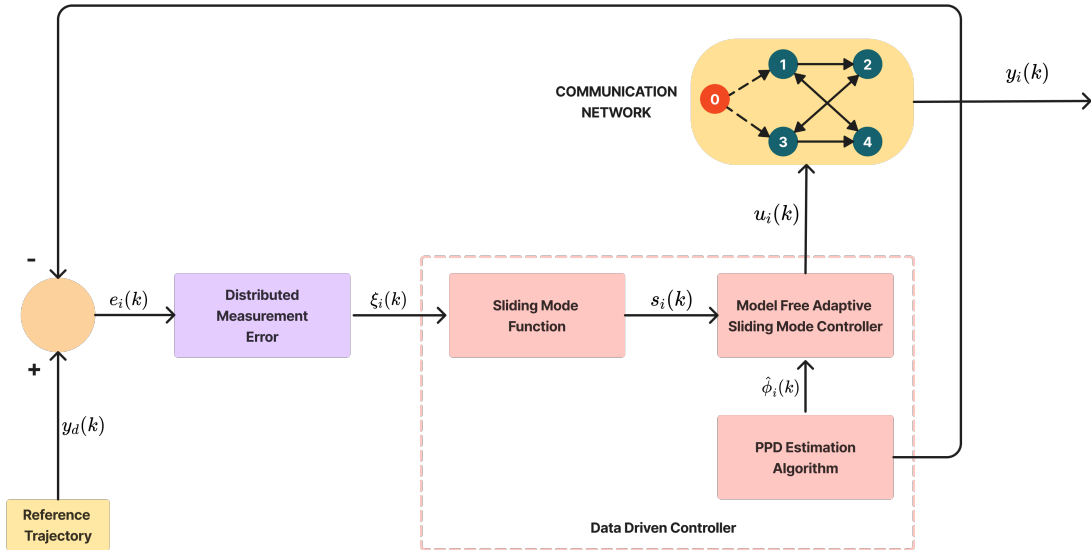


Fig. 1: Block diagram.

#### A. Model-Free Adaptive Controller Design

Consider the following PPD criterion function, for the above consensus tracking objective  $\phi_i(k)$ :

$$J(\phi_i(k)) = |\Delta y_i(k) - \phi_i(k) \Delta u_i(k-1)|^2 + \mu |\phi_i(k) - \hat{\phi}_i(k-1)|^2 \quad (4)$$

By utilizing the optimal condition  $\frac{\partial J(\phi_i(k))}{\partial \phi_i(k)} = 0$ , the updating law with reset algorithm is derived:

$$\hat{\phi}_i(k) = \hat{\phi}_i(k-1) + \frac{\eta \Delta u_i(k-1)}{\mu + \Delta u_i(k-1)^2} (\Delta y_i(k) - \hat{\phi}_i(k-1) \Delta u_i(k-1)) \quad (5)$$

$$\hat{\phi}_i(k) = \hat{\phi}_i(1), \text{ if } |\hat{\phi}_i(k)| \leq \epsilon \text{ or } \text{sign}(\hat{\phi}_i(k)) \neq \text{sign}(\hat{\phi}_i(1)) \quad (6)$$

herein,  $\eta \in (0, 1)$ ,  $\mu > 0$  represents a positive weight factor. Additionally,  $\epsilon$  is a small positive number. Finally,  $\hat{\phi}_i(k)$  signifies the estimated value of  $\phi_i(k)$ .

The following distributed MFAC algorithm is presented:

$$u_{i,\text{MFA}}(k) = u_{i,\text{MFA}}(k-1) + \frac{\rho \hat{\phi}_i(k)}{\lambda + \hat{\phi}_i(k)^2} \xi_i(k) \quad (7)$$

where  $\rho \in (0, 1)$  is a step-size constant, which is added to make (7) general.

### B. Sliding Mode Controller Design

To design the sliding mode controller for the system, the sliding surface function is given by:

$$s_i(k) = \alpha \xi_i(k) - \xi_i(k-1) \quad (8)$$

herein  $\alpha > 1$  represents a positive constant.

Furthermore, from (2) and (3), the formula (3) is updated as

$$\xi_i(k+1) = \xi_i(k) - \left( \sum_{j \in N_i} a_{ij} + d_i \right) \phi_i(k) \Delta u_i(k) + \sum_{j \in N_i} a_{ij} \Delta y_j(k) + d_i \Delta y_d(k+1) \quad (9)$$

wherein  $\Delta y_j(k+1)$  is replaced with  $\Delta y_j(k)$  because the data at the next moment cannot be obtained.

Therefore, considering (8), with the assistance of reaching law  $s_i(k+1) = 0$ , the following equivalent control law can be derived.

$$\Delta u_{i,\text{SM}}^{\text{eq}} = \frac{\omega \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \left( \frac{\xi_i(k) + \sum_{j \in N_i} a_{ij} \Delta y_j(k) + d_i \Delta y_d(k+1)}{\sum_{j \in N_i} a_{ij} + d_i} - \frac{\xi_i(k)}{\alpha \left( \sum_{j \in N_i} a_{ij} + d_i \right)} \right) \quad (10)$$

The controller consists of an equivalent control law and switching control law, which means:

$$u_{i,\text{SM}}(k) = u_{i,\text{SM}}(k-1) + \Delta u_{i,\text{SM}}^M(k) + \Delta u_{i,\text{SM}}^s(k) \quad (11)$$

Additionally, the switching control law  $\Delta u_{i,\text{SM}}^s(k)$  is presented:

$$\Delta u_{i,\text{SM}}^s(k) = \frac{\omega \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \tau_s \text{sign}(s_i(k)) \quad (12)$$

As a consequence, taking into consideration both (10), (11) and (12), the controller is summarized as follows:

$$u_{i,\text{SM}}(k) = u_{i,\text{SM}}(k-1) + \frac{\omega \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \left( \frac{\xi_i(k) + \sum_{j \in N_i} a_{ij} \Delta y_j(k) + d_i \Delta y_d(k+1)}{\sum_{j \in N_i} a_{ij} + d_i} - \frac{\xi_i(k)}{\alpha \left( \sum_{j \in N_i} a_{ij} + d_i \right)} + \tau_s \text{sign}(s_i(k)) \right) \quad (13)$$

Subsequently, the final MFASMC input is:

$$u_i(k) = u_{i,\text{MFA}}(k) + \Gamma_i u_{i,\text{SM}}(k) \quad (14)$$

where the parameter  $\Gamma_i$  is a gain factor.

The main results of the proposed control methodology are presented. The model-free adaptive controller design is introduced, followed by the sliding mode controller design. The stability analysis is provided to ensure the boundedness of the distributed measurement error and the effectiveness of the proposed approach.

### C. Stability Analysis

Theorem 1: For the system (1) satisfying assumptions 1 and 2, using the designed algorithms (5) along with the reset law (6), the sliding surface (8) and controller (13) can ensure the boundedness of  $\hat{\phi}_i(k)$ . Simultaneously, the distributed measurement error remains bounded. This result holds under the condition  $0 < h_0 < h_i(k) < \frac{\omega C_0}{2\sqrt{\sigma}} < 1$ , which guarantees the proper behavior of the function  $h_i(k)$ . The functions used therein are given by:

$$\begin{cases} h_i(k) = \frac{\omega \phi_i(k) \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \\ g_i(k) = (1 - h_i(k)) \left( \sum_{j \in N_i} a_{ij} + d_i \right) \Delta y_d(k+1) - h_i(k) \left( \sum_{j \in N_i} a_{ij} + d_i \right) \tau_s \text{sign}(s_i(k)) \\ |g_i(k)| < g_0 \end{cases}$$

Proof: The proof is divided into two parts.

Part i: Define  $\tilde{\phi}_i(k) = \hat{\phi}_i(k) - \phi_i(k)$ . Using the PPD estimation algorithm (5), the following result is derived:

$$\begin{aligned} \tilde{\phi}_i(k) &= (\hat{\phi}_i(k-1) - \phi_i(k-1)) + \frac{\eta \Delta u_i(k-1)}{\mu + \Delta u_i(k-1)^2} (\phi_i(k-1) \Delta u_i(k-1) \\ &\quad - \hat{\phi}_i(k-1) \Delta u_i(k-1)) - \phi_i(k) + \phi_i(k-1) \\ &= \tilde{\phi}_i(k-1) + \frac{\eta \Delta u_i(k-1)}{\mu + \Delta u_i(k-1)^2} (\phi_i(k-1) \Delta u_i(k-1) \\ &\quad - \hat{\phi}_i(k-1) \Delta u_i(k-1)) - \phi_i(k) + \phi_i(k-1) \\ &= \tilde{\phi}_i(k-1) + \frac{\eta \Delta u_i(k-1)}{\mu + \Delta u_i(k-1)^2} \Delta u_i(k-1) (\phi_i(k-1) - \hat{\phi}_i(k-1)) - \phi_i(k) + \phi_i(k-1) \\ &= \left( 1 - \frac{\eta \Delta u_i(k-1)^2}{\mu + \Delta u_i(k-1)^2} \right) \tilde{\phi}_i(k-1) - \Delta \phi_i(k) \end{aligned} \quad (15)$$

Denote that the term  $\frac{\eta \Delta u_i(k-1)^2}{\mu + \Delta u_i(k-1)^2}$  is monotonically increasing with respect to  $\Delta u_i(k)^2$ , and its minimum value is  $\frac{\eta \epsilon^2}{\mu + \epsilon^2}$ . Therefore, there must be a constant  $q_1$  satisfying the inequalities  $0 < \eta \leq 1$  and  $u_i > 0$

$$0 < \left| 1 - \frac{\eta \Delta u_i(k-1)^2}{\mu + \Delta u_i(k-1)^2} \right| \leq 1 - \frac{\eta \epsilon^2}{\mu + \epsilon^2} = q_1 < 1 \quad (16)$$

Because of  $|\phi_i(k)| < \bar{d}$ , and  $|\Delta \phi_i(k)| < 2\bar{d}$ , the following equation (15) is written as:

$$\begin{aligned} |\tilde{\phi}_i(k)| &\leq q_1 |\tilde{\phi}_i(k-1)| + 2\bar{d} \\ &\leq q_1^2 |\tilde{\phi}_i(k-2)| + 2q_1 \bar{d} + 2\bar{d} \\ &\vdots \\ &\leq q_1^{k-1} |\tilde{\phi}_i(1)| + \frac{2\bar{d}}{1 - q_1} (1 - q_1^{k-1}) \end{aligned} \quad (17)$$

which implies  $\tilde{\phi}_i(k)$  is bounded. Since the boundedness of  $\phi_i(k)$  is guaranteed by Lemma 1.

Part ii: The boundedness of  $\xi_i(k)$ .

By combining (5) with (9), the expression for  $\xi_i(k+1)$  is updated:

$$\begin{aligned} \xi_i(k+1) &= \xi_i(k) + \sum_{j \in N_i} a_{ij} \Delta y_j(k) + d_i \Delta y_d(k+1) - \frac{\omega \phi_i(k) \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \left( 1 - \frac{1}{\alpha} \right) \xi_i(k) \\ &\quad - \frac{\omega \phi_i(k) \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \sum_{j \in N_i} a_{ij} \Delta y_j(k) - \frac{\omega \phi_i(k) \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} d_i \Delta y_d(k+1) + \left( \sum_{j \in N_i} a_{ij} + d_i \right) \tau_s \text{sign}(s_i(k)) \\ &= \left( 1 - \frac{\omega \phi_i(k) \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \left( 1 - \frac{1}{\alpha} \right) \right) \xi_i(k) + \left( \sum_{j \in N_i} a_{ij} \Delta y_j(k) - \frac{\omega \phi_i(k) \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \sum_{j \in N_i} a_{ij} \Delta y_j(k) \right) \end{aligned}$$

$$\begin{aligned}
& + \left( d_i \Delta y_d(k+1) - \frac{\omega \phi_i(k) \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} d_i \Delta y_d(k+1) \right) + \left( \sum_{j \in N_i} a_{ij} + d_i \right) \tau_s \text{sign}(s_i(k)) \\
& = \left( 1 - \frac{\omega \phi_i(k) \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \left( 1 - \frac{1}{\alpha} \right) \right) \xi_i(k) + \left( 1 - \frac{\omega \phi_i(k) \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \right) \left( \sum_{j \in N_i} a_{ij} \Delta y_j(k) \right. \\
& \quad \left. + d_i \Delta y_d(k+1) \right) - \frac{\omega \phi_i(k) \hat{\phi}_i(k)}{\sigma + \hat{\phi}_i(k)^2} \left( \sum_{j \in N_i} a_{ij} + d_i \right) \tau_s \text{sign}(s_i(k))
\end{aligned} \tag{18}$$

Subsequently, take  $0 < h_0 < h_i(k) < \frac{\omega C_0}{2\sqrt{\sigma}} < 1$  into consideration, where  $\phi_i(k) < C_0$  and  $|g_i(k)| < g_0$ , the inequality is obtained by taking the absolute value of each term of (18).

$$\begin{aligned}
|\xi_i(k+1)| & \leq \left| 1 - h_i(k) \left( 1 - \frac{1}{\alpha} \right) \right| |\xi_i(k)| + |g_i(k)| \\
& \leq \left| 1 - h_i(k) \left( 1 - \frac{1}{\alpha} \right) \right| |\xi_i(k)| + g_0(k) \\
& \vdots \\
& \leq 1 - h_0 \left( 1 - \frac{1}{\alpha} \right)^k |\xi_i(k)| + \frac{g_0 (1 - (1 - h_0 (1 - \frac{1}{\alpha}))^2)}{h_0 (1 - \frac{1}{\alpha})}
\end{aligned} \tag{19}$$

Therefore, the following result will be given as

$$\lim_{k \rightarrow \infty} \xi_i(k+1) = \frac{g_0}{h_0 (1 - \frac{1}{\alpha})} = \frac{\alpha g_0}{(\alpha - 1) h_0} \tag{20}$$

In summary, both the parameter estimation  $\hat{\phi}_i(k)$  and the measurement error  $\xi_i(k)$  remain bounded under the proposed adaptive sliding mode control scheme. The condition  $0 < h_0 < h_i(k) < \frac{\omega C_0}{2\sqrt{\sigma}} < 1$  ensures that the adaptive parameters are stable, thereby enabling stability and effectiveness of the distributed controller. This completes the proof.

Remark 3: Distinct from the consensus tracking control schemes used in the existing literature, this paper proposes a model-free adaptive sliding mode control strategy for MASs. For the purpose of attaining the reference trajectory tracking, the CFDL technique is employed alongside a novel sliding surface. Specifically, regardless of the nonlinear and time-varying dynamics of agents, the proposed methodology ensures that distributed measurement error remains bounded, thereby achieving precise speed regulation.

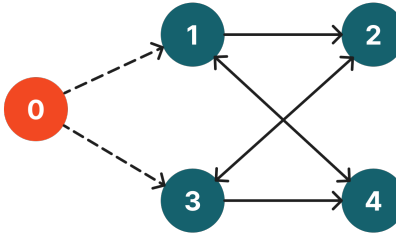


Fig. 2: Communication topology among agents.

#### IV. SIMULATION EXAMPLE

This section describes the usefulness of the provided control approach, which is validated by numerical simulations and physical experiments results.

The motor speed is measured in revolutions per second ( $r/s$ ) based on encoder measurements and the sampling interval  $t$ . The total number of encoder counts per revolution is calculated as  $rT = 4N_e R_r$ , where  $N_e$  is the encoder line count equal to 13,  $R_r$  is the reduction ratio equal to 20 and the factor of 4 accounts for quadrature encoding. The number of rotations,  $N_r$  is determined using  $N_r = \frac{m}{rT}$ , with  $m$  representing the total encoder count. The output data model of each agent is governed by:

$$y_i(k+1) = 0.5y_i(k)u_i(k) + \frac{6m}{rT} - a_i y_i(k)^{p_i} + 0.45, \quad i = 1, 2, 3, 4$$

where the agent-specific parameters are:

$$a_i = \begin{cases} 0.03 & \text{if } i = 1 \\ 0.01 & \text{if } i = 2 \\ 0.02 & \text{if } i = 3 \\ 0.01 & \text{if } i = 4 \end{cases} \quad p_i = \begin{cases} 3 & \text{if } i = 1, 3 \\ 2 & \text{if } i = 2, 4 \end{cases}$$

in this scenario, noting that the four agents have different dynamics, the parameters  $a_i$  and  $p_i$  are set to different values for each agent. In addition, they are given only to generate the I/O data for the MASs.

As illustrated in Fig. 2, the virtual leader is designated as vertex 0. It can be observed that only agents 1 and 3 can receive information from the leader, forming a strongly connected communication graph. The Laplacian matrix of the graph is given as follows:

$$L = \begin{bmatrix} 1 & 0 & 0 & -1 \\ -1 & 2 & -1 & 0 \\ 0 & -1 & 1 & 0 \\ -1 & 0 & -1 & 2 \end{bmatrix}$$

with  $D = \text{diag}(1, 0, 1, 0)$ , the following two different reference trajectories are introduced to demonstrate the effectiveness of the proposed method.

Example 1: In this example, the reference trajectory is time-invariant value signal  $y_d(k) = 0.6$ .

The initial parameters are chosen as  $u_i(1) = 0.01$ ,  $y_i(1) = 0.6$  and  $\hat{\phi}_i(0) = 4$  for all agents in this simulation,  $\Gamma_1 = \Gamma_3 = 0.45$  and  $\Gamma_2 = \Gamma_4 = 0.15$ , with  $\tau_s = 10^{-5}$ ,  $m = 600$ ,  $rT = 1024$ ,  $\eta = 1$ ,  $\mu = 0.005$ , other parameters are given as  $\rho = 7.5$ ,  $\lambda = 350$ ,  $\omega = 10$ ,  $\sigma = 95$ ,  $\alpha = 15$  with  $\epsilon = 10^{-5}$ .

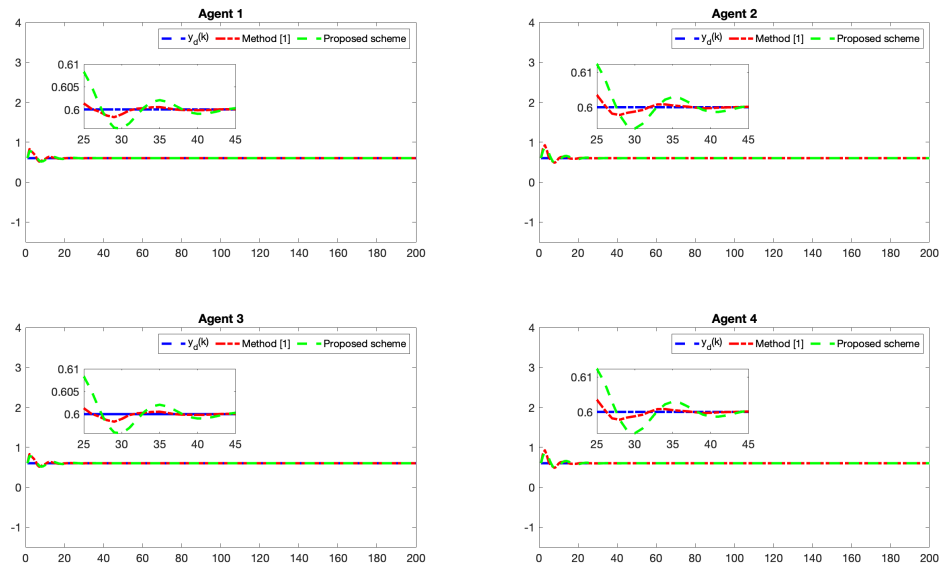


Fig. 3: Tracking performance of all agents under the time-invariant reference trajectory.

Fig. 3 demonstrates the tracking performance of all agents under the proposed control scheme for the case of a time-invariant reference signal. It can be observed that the agents effectively follow the reference trajectory, which is set to a constant value of 0.6, with negligible steady-state error and without overshoot. Moreover, Fig. 4 illustrates the distributed measurement error, which remains bounded within the range of  $[-0.02, 0.02]$ , indicating accuracy of the control strategy. These results confirm that the controller maintains stability.

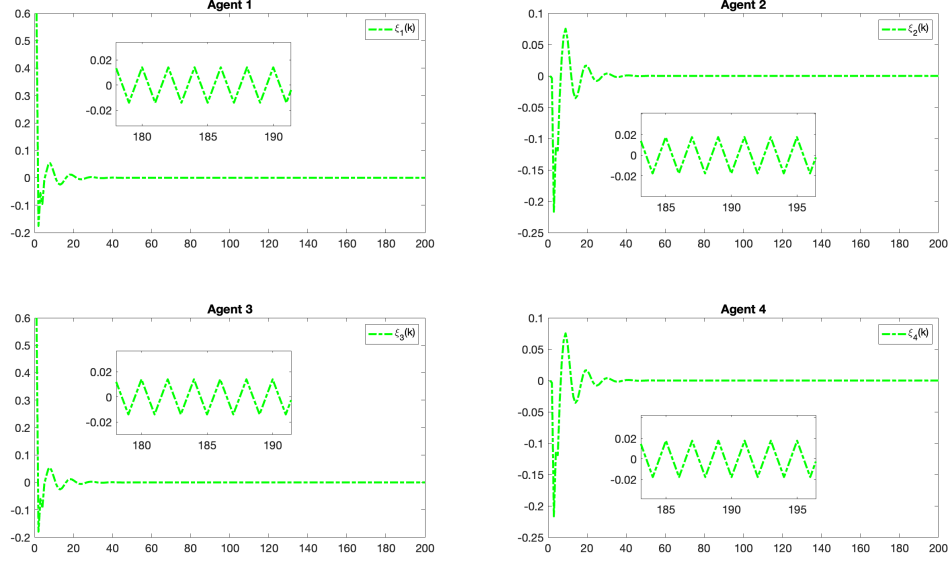


Fig. 4: Distributed measurement error of all agents under the time-invariant reference trajectory.

TABLE I: Mean square error comparison (Example 1)

$MSE_i(k)$	Method [1]	Proposed scheme
Agent 1	$2.1933 \times 10^{-3}$	$2.0628 \times 10^{-3}$
Agent 2	$7.2082 \times 10^{-4}$	$4.7332 \times 10^{-4}$
Agent 3	$2.1976 \times 10^{-3}$	$2.0737 \times 10^{-3}$
Agent 4	$7.2082 \times 10^{-4}$	$4.7332 \times 10^{-4}$
Average	$1.7082 \times 10^{-3}$	$1.2708 \times 10^{-3}$

To quantitatively evaluate the advantages of the developed method, the mean square error(MSE) is calculated for each agent. The MSE values are presented in TABLE I. For each agent, the MSE is calculated according to the formula:

$$MSE_i(k) = \frac{1}{m} \sum_{k=1}^m \xi_i^2(k)$$

where  $m$  denotes the total number of time steps. In comparison to the existing approach [1], the developed strategy demonstrates significant improvement in accuracy, reducing the average MSE across agents by a factor of approximately 1.34. This notable reduction confirms the effectiveness of the proposed technique.



Example 2: The expression for the reference trajectory is:

$$y_d(k) = 0.6 \sin(0.07\pi(k)) + 0.6 \cos(0.04\pi(k)), k \in [0, 200]$$

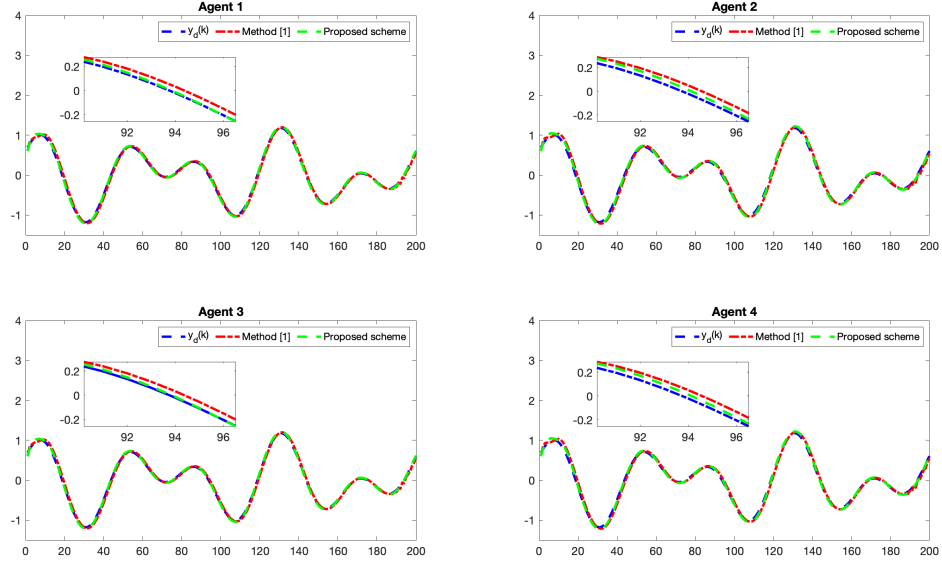


Fig. 5: Tracking performance of all agents under the time-varying reference trajectory.

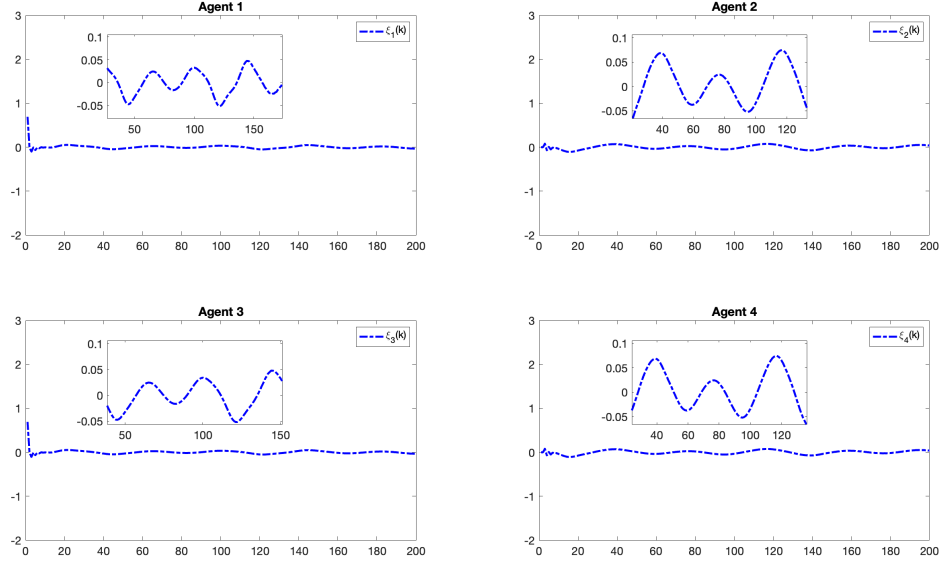


Fig. 6: Distributed measurement error of all agents under the time-varying reference trajectory.

Fig. 5 presents the tracking performance for all agents for the time-varying trajectory. All agents are able to accurately track the time-varying reference trajectory. Additionally, as shown in Fig. 6 the distributed measurement errors among agents are bounded.

For time-varying reference trajectories, the mean squared errors of distributed measurements for two control strategies are detailed in TABLE II. Relative to the conventional approach [1], the proposed scheme reduces in average MSE by approximately 1.24.

TABLE II: Mean square error comparison (Example 2)

$MSE_i(k)$	Method [1]	Proposed scheme
Agent 1	$4.0160 \times 10^{-3}$	$3.0720 \times 10^{-3}$
Agent 2	$2.1004 \times 10^{-3}$	$1.8066 \times 10^{-3}$
Agent 3	$3.9739 \times 10^{-3}$	$3.1168 \times 10^{-3}$
Agent 4	$2.1004 \times 10^{-3}$	$1.8066 \times 10^{-3}$
Average	$3.0477 \times 10^{-3}$	$2.4505 \times 10^{-3}$

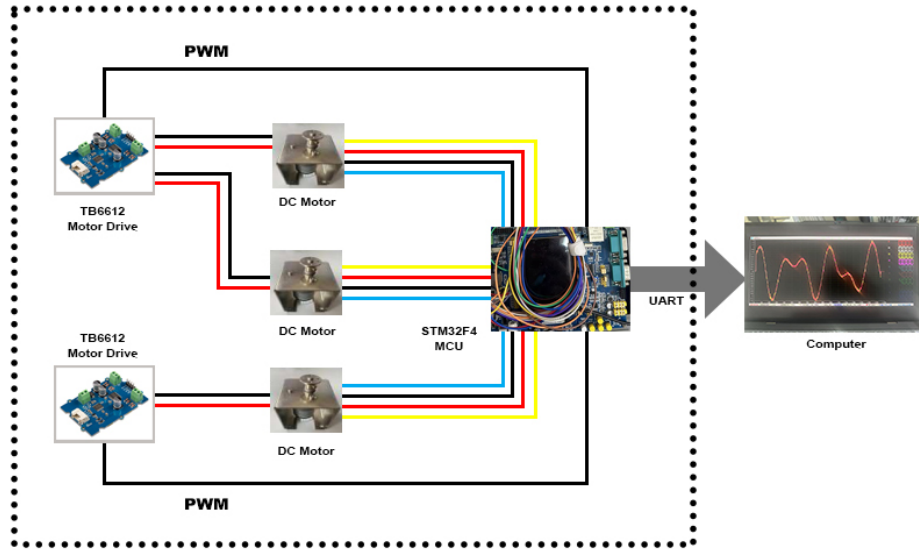


Fig. 7: System connection diagram of multi DC motor consensus tracking control.

To verify the proposed consensus tracking control methodology, the experimental validation is conducted using a multi DC motor system, as illustrated in Fig. 8. The system consists of three DC motors equipped with Hall encoders and reduction gears, an STM32F407 main control chip, two motor drive modules, and an LCD display module. The microcontroller unit (MCU) STM32F407ZGT6 is used for high-resolution pulse width modulation (PWM) output generation to achieve precise motor speed control. The timer module is utilized for this purpose.

In addition, the controller code is written in C language using STM32CubeIDE, while STM32CubeMX is used for pin configuration. The main purpose of the experiment is to ensure that the three motors accurately track the reference trajectory:

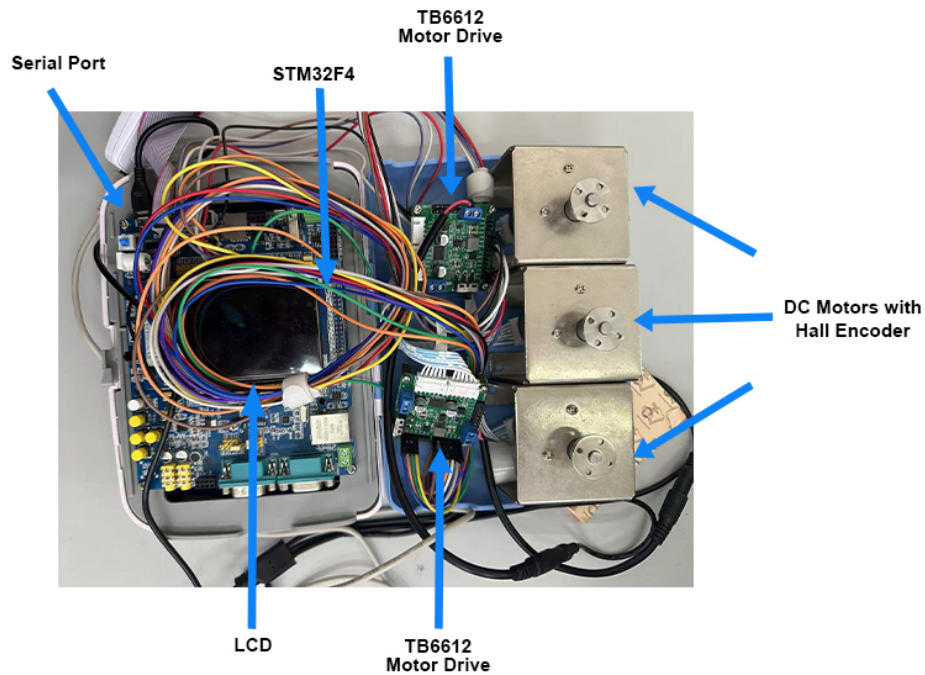


Fig. 8: Multi DC motor system.

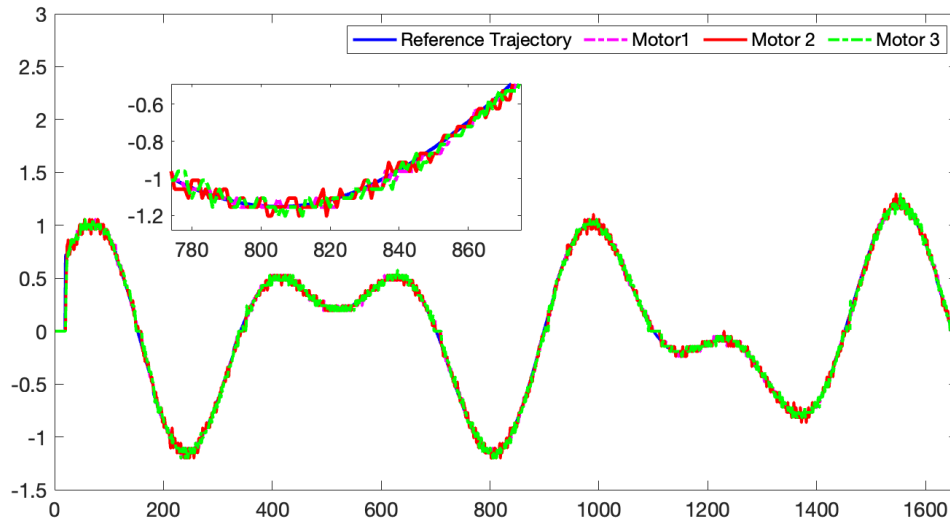


Fig. 9: Tracking performance of 3 DC motors for time-invariable desired trajectory.

Fig. 9 shows the tracking performance of multi DC motor demonstrating the effectiveness of the proposed control method. Overall, the simulation results suggest that the proposed control system is capable of tracking a constant desired trajectory for multiple agents. While initial transient errors may occur, the system eventually reaches a steady-state condition with minimal tracking error. The variations in tracking performance among the agents highlight the potential influence of individual characteristics and external factors.

## V. CONCLUSION

In this study, the model-free adaptive sliding mode control approach is presented to address the consensus problem of MASs. Firstly, the equivalent data model for each agent is obtained using the CFDL method. Secondly, a novel sliding surface is presented to ensure that the distributed measurement error remains bounded. Finally, the effectiveness of the proposed control approach is verified through physical experiments on multi DC motor system.

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