

# Predefined Time Prescribed Performance Backstepping Control for Robotic Manipulators with Input Saturation

Shuli Liu<sup>1,2</sup>, Yi Liu<sup>3\*</sup>, Jingang Liu<sup>3\*</sup>, Yin Yang<sup>1,2\*</sup>

<sup>1</sup>School of Mathematics and Computational Science, Xiangtan University, Street, City, 411105, China.

<sup>2</sup>National Center for Applied Mathematics in Hunan, Street, City, 411105, China.

<sup>3</sup>School of Mechanical Engineering and Mechanics, Xiangtan University, Street, City, 411105, China.

\*Corresponding author(s). E-mail(s):

[liuyi\\_hust@163.com](mailto:liuyi_hust@163.com); [wellbuild@126.com](mailto:wellbuild@126.com); [yangyinxtu@xtu.edu.cn](mailto:yangyinxtu@xtu.edu.cn);

Contributing authors: [shunnee@163.com](mailto:shunnee@163.com);

## 摘要

本文研究了具有未知动力学、有界扰动以及执行器饱和条件下的机器人机械臂轨迹跟踪控制问题，提出了一种立于任何初始状态条件的预定义时间预设性能约束的自适应反步控制方法。针对传统预设性能控制中存在的初值奇异性和误差变换非光滑问题，针对每个通道独立设计了结合多项式性能函数与误差缩放函数的预定义时间误差变换结构，确保系统状态在预定义时间内严格且平滑地满足全局预设性能约束。为处理反步控制及执行器饱和输入引起的计算复杂度爆炸问题，设计了一种预定义时间饱和补偿器，以同时消除命令滤波与输入饱和的不利影响。此外，引入一阶滑模扰动观测器实时估计并补偿系统中未知的有界扰动，利用径向基函数神经网络对系统未建模动态进行辨识和补偿，从而提高了控制系统的鲁棒性和跟踪精度。同时，结合预定义时间理论和自适应动态障碍李雅普诺夫函数，严格证明了闭环系统在预定义时间内的全局稳定性和误差收敛性。数值和实验结果验证了所提出方法的有效性，与现有方法相比，本文方法在响应速度、稳态精度及鲁棒性能方面表现出明显优势。

**Keywords:** Prescribed performance control, predefined-time stability, adaptive dynamic barrier Lyapunov function, backstepping control, input saturation, robotic manipulators' trajectory tracking.

下面是在你原有排版基础上\*\*逐句打磨、修正符号与措辞\*\*后的版本（保留结构与编号；只做必要的更正与增润）。

## 0.1 System description

求  $V_1$  的时间导数为

$$\dot{V}_1 = \sum_{i=1}^n \left[ \frac{\rho_{1,i}^4 z_{1,i}}{(\rho_{1,i}^2 - z_{1,i}^2)^2} \dot{z}_{1,i} - \frac{\rho_{1,i} z_{1,i}^4}{(\rho_{1,i}^2 - z_{1,i}^2)^2} \dot{\rho}_{1,i} \right] \quad (1)$$

记  $P_{j,i} = \frac{\rho_{j,i}^4}{(\rho_{j,i}^2 - z_{j,i}^2)^2} > 0$ ,  $Q_{j,i} = \frac{z_{j,i}^4}{(\rho_{j,i}^2 - z_{j,i}^2)^2} > 0$ ,  $\Phi_{j,i} = \frac{z_{j,i}(\rho_{j,i}^2 - z_{j,i}^2)}{\rho_{j,i}^4} = \frac{z_{j,i}(\rho_{j,i}^2 - z_{j,i}^2)}{P_{j,i}}$ ,  $j \in \{1, 2\}$ ,  $\dot{z}_{1,i} = z_{2,i} - \dot{q}_{d,i} + \alpha_i^f + \zeta_i$ , 将它们代入 BLF 导数后，并根据公式 ( )，得到

$$\dot{V}_1 = \sum_{i=1}^n \left[ P_{1,i} z_{1,i} z_{2,i} + P_{1,i} z_{1,i} (\alpha_i + \zeta_i - \dot{q}_{d,i}) - P_{1,i} z_{1,i} \tilde{\alpha}_i - Q_{1,i} \rho_{1,i} \dot{\rho}_{1,i} \right]$$

Let  $S_{j,i} = \frac{1}{2} \frac{\rho_{j,i}^2 z_{j,i}^2}{\rho_{j,i}^2 - z_{j,i}^2}$ ,  $\Psi(S_{j,i}) = \frac{\pi}{\eta T_p} \left( (S_{j,i})^{1-\eta/2} + n^{-\frac{\eta}{2}} (S_{j,i})^{1+\eta/2} \right)$ , 我们设计

$$\mathcal{K}_{1,i}(z_{j,i}, \rho_{j,i}) = \frac{\rho_{j,i}^2}{2} \frac{\Psi(S_{j,i})}{S_{j,i}} = \frac{\pi \rho_{j,i}^2}{2\eta T_p} \left( (S_{j,i})^{-\eta/2} + n^{-\frac{\eta}{2}} (S_{j,i})^{\eta/2} \right).$$

把它代回, 可设计虚拟控制律为:

$$\alpha_i = \dot{q}_{d,i} - \zeta_i + \frac{z_{1,i}^3}{\rho_{1,i}^3} \dot{\rho}_{1,i} - \mathcal{K}_{1,i}(z_{1,i}, \rho_{1,i}) \Phi_{1,i} - k_{1,i} \rho_{1,i}^2 \Phi_{1,i}, \quad (2)$$

where  $k_1 = \text{diag}\{k_{1,1}, k_{1,i}, \dots, k_{1,n}\} > 0$ ,  $k_{1,i} > 0$ ,

则一步 Lyapunov 导数化简为

$$\dot{V}_1 \leq \sum_{i=1}^n \left[ P_{1,i} z_{1,i} z_{2,i} - \Psi(V_{1,i}) - P_{1,i} z_{1,i} \tilde{\alpha}_i - k_{1,i} \frac{\rho_{1,i}^2 z_{1,i}^2}{\rho_{1,i}^2 - z_{1,i}^2} \right].$$

In the second step, a BLF is used as an energy function for the error dynamics. We choose:

$$V_2 = V_1 + \frac{1}{2} \sum_{i=1}^n \frac{\rho_{2,i}^2 z_{2,i}^2}{\rho_{2,i}^2 - z_{2,i}^2}. \quad (3)$$

Using  $\dot{z}_{2,i} = \dot{x}_{2,i} - \dot{\alpha}_i^f - \dot{\zeta}_i$ , we obtain the time derivative of  $V_2$  is as

$$\begin{aligned} \dot{V}_2 &= V_1 + \sum_{i=1}^n \left[ P_{2,i} z_{2,i} (\dot{x}_{2,i} - \dot{\alpha}_i^f - \dot{\zeta}_i) - Q_{2,i} \rho_{2,i} \dot{\rho}_{2,i} \right] \\ &= \dot{V}_1 + \sum_{i=1}^n \left[ P_{2,i} z_{2,i} \left( f_i(x) + h_i(x, t) + g_i(u_i - \Delta u_i) + d'(t) - \dot{\alpha}_i^f - \delta_i + \mu_2 \zeta_i + g_i \Delta u_i - \frac{z_{2,i}^3}{\rho_{2,i}^3} \dot{\rho}_{2,i} \right) \right] \end{aligned} \quad (4)$$

Let  $Q_2 = \text{col}\{Q_{2,i}\}$ ,  $P_1 = \text{col}\{P_{1,i}\}$ ,  $\Phi_2 = \text{col}\{\Phi_{2,i}\}$ . The control input torque is designed as

$$\begin{aligned} u &= C(q, \dot{q}) x_2 + G(q) \\ &+ M(q) \left[ \dot{\alpha}^f + \delta - \mu_2 \zeta - \frac{P_1}{P_2} z_1 + \frac{z_2^3}{\rho_{2,i}^3} \dot{\rho}_{2,i} - \mathcal{K}_2(z_2, \rho_{2,i}) \Phi_2 - \hat{h}(\chi) - \hat{\omega} - k_s \text{sgn}(z_2) - k_2 \rho_{2,i}^2 \Phi_{2,i} \right] \end{aligned} \quad (5)$$

where  $k_2 = \text{diag}\{k_{2,1}, k_{2,i}, \dots, k_{2,n}\} > 0$ ,  $k_{2,i} > 0$ ,  $k_s > 0$ .

Let  $\chi = \{q, \dot{q}\} \in \mathbb{R}^m$  be the regressor and  $\psi(\chi) \in \mathbb{R}^N$  the normalized basis. Approximate the structured uncertainty by  $\hat{h}_i(\chi) = \hat{\theta}_i^\top \psi_i(\chi)$ , with  $\theta_i \in \mathbb{R}^N$  adapted online by

$$\dot{\hat{\theta}}_i = \varrho_i P_{2,i} z_{2,i} \psi(\chi) - \kappa_i \hat{\theta}_i, \quad \varrho_i, \kappa_i > 0. \quad (6)$$

将结构不确定估计误差和外扰的剩余项定义为  $\omega(x, t) = h(x) - \hat{h}(\chi) + M^{-1}(q)d(t)$ 。为避免直接微分速度, 采用一阶跟踪微分器作为观测器

$$\begin{cases} \dot{\vartheta} = -\omega_d \vartheta + \omega_d x_2, \\ \hat{x}_2 = \omega_d (x_2 - \vartheta), \\ \dot{\hat{\omega}} = -\Lambda_o \hat{\omega} + \Lambda_o (\hat{x}_2 - f(x) - M^{-1}(q) \text{sat}(u) - \hat{h}(\chi)), \end{cases} \quad (7)$$

where  $\Lambda_o = \text{diag}\{\lambda_{o,i}\} > 0$ ,  $\omega_d > 0$ ,  $\vartheta(0) = x_2(0)$ , 设观测误差为  $\tilde{\omega} = \omega - \hat{\omega}$ . 根据公式可得到

$$\dot{V}_2 \leq \sum_{i=1}^n \left( -k_{1,i} \frac{\rho_{1,i}^2 z_{1,i}^2}{\rho_{1,i}^2 - z_{1,i}^2} - \Psi(V_{1,i}) - P_{1,i} z_{1,i} \tilde{\alpha}_i \right) + \sum_{i=1}^n \left( -k_{2,i} \frac{\rho_{2,i}^2 z_{2,i}^2}{\rho_{2,i}^2 - z_{2,i}^2} - \Psi(V_{2,i}) - P_{2,i} z_{2,i} \tilde{\omega}_i \right) - k_s \sum_{i=1}^n P_{2,i} |z_{2,i}| \quad (8)$$

$$\begin{aligned}
\dot{V} &\leq \sum_{i=1}^n \left( -k_{1,i} \frac{\rho_{1,i}^2 z_{1,i}^2}{\rho_{1,i}^2 - z_{1,i}^2} - \Psi(V_{1,i}) - P_{1,i} z_{1,i} \tilde{\alpha}_i \right) + \sum_{i=1}^n \left( -k_{2,i} \frac{\rho_{2,i}^2 z_{2,i}^2}{\rho_{2,i}^2 - z_{2,i}^2} - \Psi(V_{2,i}) - P_{2,i} z_{2,i} \tilde{\omega}_i \right) \\
&\quad - k_s \sum_{i=1}^n P_{2,i} |z_{2,i}| + \tilde{\alpha}^\top \dot{\tilde{\alpha}} + \frac{1}{\gamma_o} \tilde{\omega}^\top \dot{\tilde{\omega}} + \sum_{i=1}^n \frac{1}{\varrho_i} \tilde{\theta}_i^\top \dot{\tilde{\theta}}_i \\
&\leq \sum_{i=1}^n \left( -k_{1,i} \frac{\rho_{1,i}^2 z_{1,i}^2}{\rho_{1,i}^2 - z_{1,i}^2} - \Psi(V_{1,i}) \right) + \sum_{i=1}^n \left( -k_{2,i} \frac{\rho_{2,i}^2 z_{2,i}^2}{\rho_{2,i}^2 - z_{2,i}^2} - \Psi(V_{2,i}) \right) \\
&\quad - P_{2,i} z_{2,i} \tilde{\omega}_i + \frac{1}{\gamma_o} \tilde{\omega}^\top \dot{\tilde{\omega}} - k_s \sum_{i=1}^n P_{2,i} |z_{2,i}| + \tilde{\alpha}^\top \dot{\tilde{\alpha}} - P_{1,i} z_{1,i} \tilde{\alpha}_i + \sum_{i=1}^n \frac{1}{\varrho_i} \tilde{\theta}_i^\top \dot{\tilde{\theta}}_i
\end{aligned} \tag{9}$$

$$\rho_{2,i}^2 - z_{2,i}^2 \leq \rho_{2,i}^2$$

(10)

## Statements and Declarations

### Funding

This work is supported by the National Key Research and Development Program of China (2023YFC3008802), the National Natural Science Foundation of China (52075465), and the Key Products of Hunan Province's Manufacturing Industry "Unveiled and Leading" Project (2023GXGG018), the Project of Scientific Research Fund of the Hunan Provincial Science and Technology Department (2023JJ50021, 2023GK2029, No.2024JC1003, No.2024JJ1008, 2024JJ2051, 2023GK2026), "Algorithmic Research on Mathematical Common Fundamentals" Program for Science and Technology Innovative Research Team in Higher Educational Institutions of Hunan Province of China, the Hunan Provincial Department of Education Excellent Youth Program (23B0162).

### Conflicts of Interest

The authors declare no conflict of interest.

### Author contribution

Shuli Liu: Writing-Original Draft, Methodology, Software, Visualization, Data curation. Yi Liu: Resources, Investigation, Formal analysis, Conceptualization, Writing-Review & Editing. Jingang Liu: Project administration, Validation, Funding acquisition, Writing-Review & Editing. Yin Yang: Supervision, Funding acquisition, Writing-Review & Editing. All authors have reviewed and approved the final version of the manuscript.

### Data Availability

The data that support the findings of this study are available from the corresponding author upon reasonable request.