Global Chaos Synchronization of the Pehlivan Systems by Sliding Mode Control

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***Abstract*—This paper investigates the problem of global chaos synchronization of identical Pehlivan chaotic systems (Pehlivan and Uyaroglu, 2010) by sliding mode control. The stability results derived in this paper for the synchronization of identical Pehlivan systems are established using Lyapunov stability theory. Since the Lyapunov exponents are not required for these calculations, the sliding mode control method is very effective and convenient to achieve global chaos synchronization of the identical Pehlivan chaotic systems. Numerical simulations are shown to illustrate the effectiveness of the synchronization schemes derived in this paper for the identical Pehlivan chaotic systems.**

Keywords- nonlinear control systems; chaos; sliding-mode control; Pehlivan system.

I. INTRODUCTION

Chaotic systems are dynamical systems that are highly sensitive to initial conditions. This sensitivity is popularly known as the *butterfly effect* [1]. Since the seminal work by Pecora and Carroll ([2], 1990), chaos synchronization problem has been studied extensively and intensively in the literature [2-17]. Chaos theory has been applied to a variety of fields such as physical systems [3], chemical systems [4], ecological systems [5], secure communications [6-8] etc.

In the last two decades, various schemes have been successfully applied for chaos synchronization such as PC method [2], OGY method [9], active control method [10-12], adaptive control method [13-14], time-delay feedback method [15], backstepping design method [16], sampled-data feedback synchronization method [17], etc.

In most of the chaos synchronization approaches, the *master-slave* or *drive-response* formalism is used. If a particular chaotic system is called the *master* or *drive* system and another chaotic system is called the *slave* or *response* system, then the goal of the global chaos synchronization is to use the output of the master system to control the slave system so that the states of the slave system track the states of the master system asymptotically. In other words, global chaos synchronization is achieved when the difference of the states of the master and slave systems converge to zero asymptotically with time.

In this paper, we derive new results based on the sliding mode control [18-20] for the global chaos synchronization of identical Pehlivan chaotic systems (Pehlivan and Uyaroglu, 2010). In robust control systems, sliding mode control is often adopted due to its inherent advantages of easy realization, fast response and good transient performance as well as its insensitivity to parameter uncertainties and external disturbances.

This paper has been organized as follows. In Section II, we describe the problem statement and our methodology using sliding mode control. In Section III, we discuss the global chaos synchronization of identical Pehlivan systems ([21], 2010). In Section IV, we summarize the main results obtained in this paper.

II. PROBLEM STATEMENT AND OUR METHODOLOGY USING SLIDING MODE CONTROL

In this section, we describe the problem statement for the global chaos synchronization for identical chaotic systems and our methodology using sliding mode control.

Consider the chaotic system described by

$$\dot{x} = Ax + f(x) \tag{1}$$

where $x \in R^n$ is the state of the system, A is the $n \times n$ matrix of the system parameters and $f : R^n \to R^n$ is the nonlinear part of the system.

We consider the system (1) as the *master* or *drive* system.

As the *slave* or *response* system, we consider the following chaotic system described by the dynamics

$$\dot{y} = Ay + f(y) + u \tag{2}$$

where $y \in R^n$ is the state of the system and $u \in R^m$ is the controller to be designed.

If we define the *synchronization error* as

$$e = y - x, \tag{3}$$

then the error dynamics is obtained as

$$\dot{e} = Ae + \eta(x, y) + u, \tag{4}$$

where

$$\eta(x, y) = f(y) - f(x) \tag{5}$$

The objective of the global chaos synchronization problem is to find a controller u such that

$$\lim_{t\to\infty} \|e(t)\| = 0 \quad \text{for all } e(0) \in R^n.$$

To solve this problem, we first define the control u as

$$u = -\eta(x, y) + Bv \tag{6}$$

where B is a constant gain vector selected such that (A, B) is controllable.

Substituting (5) into (4), the error dynamics simplifies to

$$\dot{e} = Ae + Bv \tag{7}$$

which is a linear time-invariant control system with single input v.

Thus, the original global chaos synchronization problem can be replaced by an equivalent problem of stabilizing the zero solution $e = 0$ of the system (7) by a suitable choice of the sliding mode control. In the sliding mode control, we define the variable

$$s(e) = Ce = c_1 e_1 + c_2 e_2 + \cdots + c_n e_n \tag{8}$$

where $C = \begin{bmatrix} c_1 & c_2 & \cdots & c_n \end{bmatrix}$ is a constant vector to be determined.

In the sliding mode control, we constrain the motion of the system (7) to the sliding manifold defined by

$$S = \left\{ x \in R^n \mid s(e) = 0 \right\}$$

which is required to be invariant under the flow of the error dynamics (7).

When in sliding manifold S, the system (7) satisfies the following conditions:

$$s(e) = 0 \tag{9}$$

which is the defining equation for the manifold S and

$$\dot{s}(e) = 0 \tag{10}$$

which is the necessary condition for the state trajectory $e(t)$ of (7) to stay on the sliding manifold S.

Using (7) and (8), the equation (10) can be rewritten as

$$\dot{s}(e) = C\left[Ae + Bv \right] = 0 \tag{11}$$

Solving (11) for v, we obtain the equivalent control law

$$v_{\text{eq}}(t) = -(CB)^{-1} CA\, e(t) \tag{12}$$

where C is chosen such that $CB \neq 0$.

Substituting (12) into the error dynamics (7), we obtain the closed-loop dynamics as

$$\dot{e} = \left[I - B(CB)^{-1} C \right] Ae \tag{13}$$

The row vector C is selected such that the system matrix of the controlled dynamics $\left[I - B(CB)^{-1} C \right] A$ is Hurwitz, *i.e.* it has all eigenvalues with negative real parts. Then the controlled system (13) is globally asymptotically stable.

To design the sliding mode controller for (7), we apply the constant plus proportional rate reaching law

$$\dot{s} = -q \,\mathrm{sgn}(s) - k\ s \tag{14}$$

where $\mathrm{sgn}(\cdot)$ denotes the sign function and the gains $q > 0,\ \ k > 0$ are determined such that the sliding condition is satisfied and sliding motion will occur.

From equations (11) and (14), we can obtain the control $v(t)$ as

$$v(t) = -(CB)^{-1} \left[C(kI + A)e + q \,\mathrm{sgn}(s) \right] \tag{15}$$

which yields

$$v(t) = \begin{cases} -(CB)^{-1} \left[C(kI + A)e + q \right], & \text{if } s(e) > 0 \\ -(CB)^{-1} \left[C(kI + A)e - q \right], & \text{if } s(e) < 0 \end{cases} \tag{16}$$

Theorem 1. *The master system (1) and the slave system (2) are globally and asymptotically synchronized for all initial conditions* $x(0), y(0) \in R^n$ *by the feedback control law*

$$u(t) = -\eta(x, y) + Bv(t) \tag{17}$$

where $v(t)$ *is defined by (15) and* B *is a column vector such that* (A, B) *is controllable. Also, the sliding mode gains* k, q *are positive.*

Proof. First, we note that substituting (17) and (15) into the error dynamics (4), we obtain the closed-loop error dynamics as

$$\dot{e} = Ae - B(CB)^{-1} \left[C(kI + A)e + q \,\mathrm{sgn}(s) \right] \tag{18}$$

To prove that the error dynamics (18) is globally asymptotically stable, we consider the candidate Lyapunov function defined by the equation

$$V(e) = \frac{1}{2} s^2(e) \tag{19}$$

which is a positive definite function on R^n.

Differentiating V along the trajectories of (18) or the equivalent dynamics (14), we get

$$\dot{V}(e) = s(e)\dot{s}(e) = -ks^2 - q \,\mathrm{sgn}(s) s \tag{20}$$

which is a negative definite function on R^n.

This calculation shows that V is a globally defined, positive definite, Lyapunov function for the error dynamics (18), which has a globally defined, negative definite time derivative $\dot{V}$.

Thus, by Lyapunov stability theory [22], it is immediate that the error dynamics (18) is globally asymptotically stable for all initial conditions $e(0) \in R^n$.

This means that for all initial conditions $e(0) \in R^n$, we have

$$\lim_{t \to \infty} \| e(t) \| = 0$$

Hence, it follows that the master system (1) and the slave system (2) are globally and asymptotically synchronized for all initial conditions $x(0), y(0) \in R^n$.

This completes the proof. ■

III. Global Chaos Synchronization of the Identical Pehlivan Chaotic Systems

A. *Theoretical Results*

In this section, we apply the sliding mode control results derived in Section II for the global chaos synchronization of identical Pehlivan chaotic systems (Pehlivan and Uyaroglu, [21], 2010).

Thus, the master system is described by the Pehlivan dynamics

$$\begin{aligned} \dot{x}_1 &= x_2 - x_1 \\ \dot{x}_2 &= a x_2 - x_1 x_3 \\ \dot{x}_3 &= -b + x_1 x_2 \end{aligned} \tag{21}$$

where x_1, x_2, x_3 are state variables and a, b are positive, constant parameters of the system.

The slave system is also described by the Pehlivan dynamics

$$\begin{aligned} \dot{y}_1 &= y_2 - y_1 + u_1 \\ \dot{y}_2 &= a y_2 - y_1 y_3 + u_2 \\ \dot{y}_3 &= -b + y_1 y_2 + u_3 \end{aligned} \tag{22}$$

where y_1, y_2, y_3 are state variables and u_1, u_2, u_3 are the controllers to be designed.

The Pehlivan systems (21) and (22) are chaotic when

$$a = 0.5 \text{ and } b = 0.5.$$

Fig. 1 illustrates the chaotic portrait of the Pehlivan chaotic system (21).

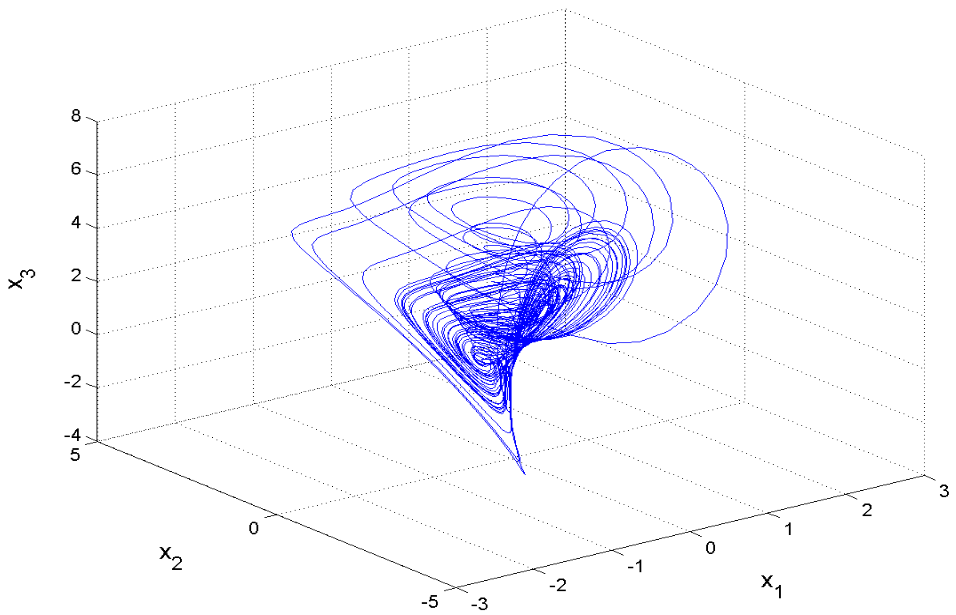

Figure 1. Chaotic Portrait of the Pehlivan Chaotic System

The chaos synchronization error is defined by

$$e_i = y_i - x_i, \ (i = 1, 2, 3) \tag{23}$$

The error dynamics is easily obtained as

$$\begin{aligned} \dot{e}_1 &= e_2 - e_1 + u_1 \\ \dot{e}_2 &= ae_2 - y_1 y_3 + x_1 x_3 + u_2 \\ \dot{e}_3 &= y_1 y_2 - x_1 x_2 + u_3 \end{aligned} \tag{24}$$

We write the error dynamics (24) in the matrix notation as

$$\dot{e} = Ae + \eta(x, y) + u \tag{25}$$

where

$$A = \begin{bmatrix} -1 & 1 & 0 \\ 0 & a & 0 \\ 0 & 0 & 0 \end{bmatrix}, \quad \eta(x, y) = \begin{bmatrix} 0 \\ -y_1 y_3 + x_1 x_3 \\ y_1 y_2 - x_1 x_2 \end{bmatrix} \quad \text{and} \quad u = \begin{bmatrix} u_1 \\ u_2 \\ u_3 \end{bmatrix}. \tag{26}$$

The sliding mode controller design is carried out as detailed in Section II.

First, we set u as

$$u = -\eta(x, y) + Bv \tag{27}$$

where B is chosen such that (A, B) is controllable.

We take B as

$$B = \begin{bmatrix} 1 \\ 1 \\ 1 \end{bmatrix}. \tag{28}$$

In the chaotic case, the parameter values are

$$a = 0.5 \ \text{and} \ b = 0.5.$$

The sliding mode variable is selected as

$$s = Ce = \begin{bmatrix} 1 & 6 & -5 \end{bmatrix} e = e_1 + 6e_2 - 5e_3 \tag{29}$$

which makes the sliding mode state equation asymptotically stable.

We choose the sliding mode gains as $k = 6$ and $q = 0.1.$

We note that a large value of k can cause chattering and an appropriate value of q is chosen to speed up the time taken to reach the sliding manifold as well as to reduce the system chattering.

From Eq. (15), we can obtain $v(t)$ as

$$v(t) = -2.5\ e_1 - 20\ e_2 + 15\ e_3 - 0.05\ \text{sgn}(s) \tag{30}$$

Thus, the required sliding mode controller is obtained as

$$u = -\eta(x, y) + Bv \tag{31}$$

where $\eta(x, y), B$ and $v(t)$ are defined as in the equations (26), (28) and (30).

By Theorem 1, we obtain the following result.

Theorem 2. *The identical Pehlivan chaotic systems (21) and (22) are globally and asymptotically synchronized for all initial conditions with the sliding mode controller* u *defined by (31).* ■

B. Numerical Results

For the numerical simulations, the fourth-order Runge-Kutta method with time-step $h = 10^{-6}$ is used to solve the Liu-Chen four-scroll chaotic systems (21) and (22) with the sliding mode controller u given by (31) using MATLAB.

In the chaotic case, the parameter values are

$$a = 0.5 \text{ and } b = 0.5.$$

The sliding mode gains are chosen as $k = 6$ and $q = 0.1$.

The initial values of the master system (21) are taken as

$$x_1(0) = 10,\ x_2(0) = 6,\ x_3(0) = 8$$

and the initial values of the slave system (22) are taken as

$$y_1(0) = 2,\ y_2(0) = 9,\ y_3(0) = 4.$$

Fig. 2 illustrates the complete synchronization of the identical Pehlivan chaotic systems (21) and (22).

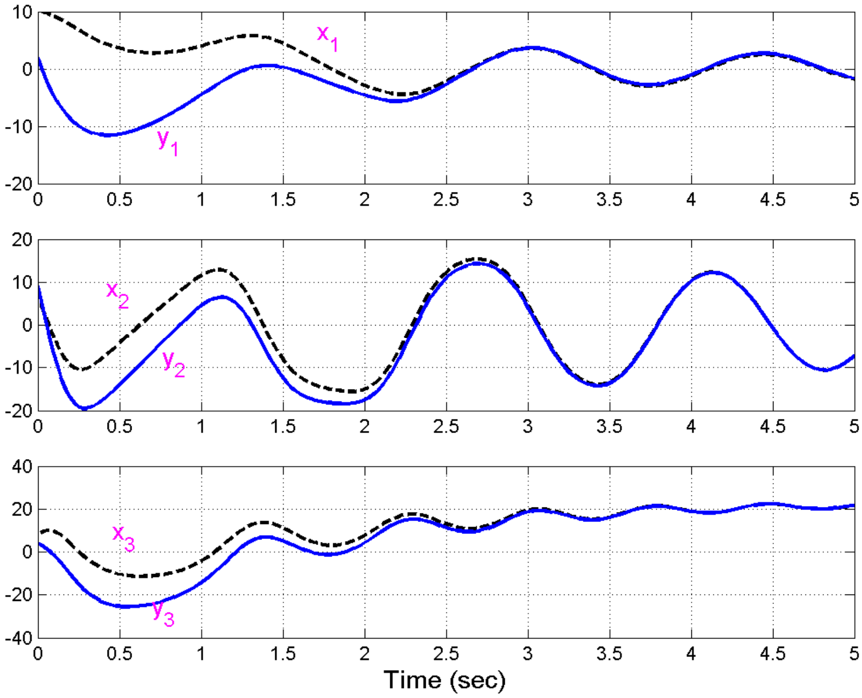

Figure 2. Synchronization of Identical Pehlivan Chaotic Systems

IV. Conclusions

In this paper, we have deployed sliding mode control (SMC) to achieve global chaos synchronization for the identical Pehlivan chaotic systems (Pehlivan and Uyaroglu, 2010). Our synchronization results for the identical Pehlivan chaotic systems have been established using Lyapunov stability theory. Since the Lyapunov exponents are not required for these calculations, the sliding mode control method is very effective and convenient to achieve global chaos synchronization for the identical Pehlivan chaotic systems. Numerical simulations are also shown to illustrate the effectiveness of the synchronization results derived in this paper using sliding mode control for the identical Pehlivan chaotic systems.

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