Contents

Abstract **xi**

1 Introduction **1**
1.1 Invariance 4
1.2 Sliding modes 6
1.2.1 Description of the sliding mode 7
1.2.2 Sliding mode existence necessary condition 8
1.2.3 Equivalent control method 11
1.2.4 A necessary and sufficient condition for existence of Sliding Mode 11
1.2.5 Discontinuous Control Action in Sliding Mode Control. Chattering Problem 12
1.3 Sliding Mode Reference Conditioning 13
1.4 Higher Order Sliding Mode 15
1.4.1 Sliding Mode order 16
1.4.2 Regularity conditions 16
1.4.3 Convergence time 16
1.4.4 Second Order Sliding Mode 17
1.5 SM Continuous approximation and Relative degree 2 . . . 19
1.6 Motivation 19
1.6.1 Coordination and interconnected systems 19
1.6.2 Estimation in Bioprocesses 20
1.6.3 Control theory in synthetic biology 21
1.7 Scope and objectives 21
1.8 Thesis outline 22
1.9 Publications 25

I Coordination of dynamical systems 29

2 Coordinación de sistemas dinámicos 31
2.1 Introducción 32
2.2 Coordinación de sistemas 34
2.2.1 Presentación del problema 34
2.2.2 Intercambio de información entre sistemas 35
2.2.3 Suposiciones y definiciones generales 36
2.3 Invarianza y Acondicionamiento de Referencia por MD . . 37
2.3.1 Invarianza geométrica de conjuntos 38
2.3.2 Acondicionamiento de referencia por MD 41
2.4 Topología global tipo supervisor 44
2.4.1 Esquema propuesto de coordinación 44
2.4.2 Función χ: el mínimo 47
2.5 Topología local distribuida 47
2.6 Simulaciones 51
2.6.1 Topología Global 52
2.6.2 Topología local 54
2.7 Conclusión 58

3 SMRCoord of constrained feedback systems 59
3.1 Introduction 60
3.2 Problem statement 62
3.2.1 Information exchange 63
3.2.2 Constrained systems 64
3.2.3 Assumptions and definitions 64
3.3 Geometric set invariance and sliding mode reference conditioning 64
3.3.1 Geometric set invariance 65
3.3.2 Sliding mode reference conditioning 66
3.4 Reference coordination under local topology 68
3.5 Reference coordination under global topology 71
3.6 Simulation 73
3.6.1 Quadrotors and controllers 75
3.6.2 Information exchange in SMRCoord 75
3.6.3 Simulation results 75
3.7 Conclusion 77

4 UAV reference conditioning for formation control 79
4.1 Introduction 80
4.2 Problem Statement 82
4.3 Formation control 83
4.3.1 Proposed coordination scheme. 83
4.3.2 SMRC analysis and design. 83
4.3.3 Switching frequency and chattering. 85
4.4 Simulation 86
4.4.1 Quadrotors and controllers 86
4.4.2 Virtual leader reference and formation structure . . 86
4.4.3 Simulation results 86
4.5 Conclusion 88

II Bioprocesses and sliding modes estimation 91

5 Specific growth rate estimation in (fed-)batch bioreactors using second-order sliding observers 93
5.1 Introduction 94
5.2 Problem formulation and background material 96
5.2.1 Main assumptions 97
5.2.2 Preliminaries 97
5.3 Second-order sliding mode observer 99
5.4 Simulation results 104
5.5 Experimental results 110
5.6 Conclusions 111

6 Stability preserving maps for finite-time convergence 113
6.1 Introduction 114
6.2 Motivation 116
6.2.1 Super-twisting algorithm 116
6.2.2 Preliminary analysis of the super-twisting algorithm. 117
6.3 Constructive design of the super-twisting algorithm. . . . 119
6.3.1 Case $r(z_1) \equiv 0$ 122
6.3.2 Case $r(z_1) \not\equiv 0$ 123
6.4 Stability analysis 127
6.5 Finite-time convergence 132

6.6 Example 133
6.7 Conclusions 135

7 Second-Order Sliding Mode Observer for Multiple Kinetic Rates Estimation in Bioprocesses 139
7.1 Introduction 140
7.2 Bioprocess model and problem statement 142
7.3 A Second-order Observer of Specific Kinetic Rates 144
7.3.1 Definitions 144
7.3.2 Main result 145
7.4 Experimental results 149
7.4.1 Results 151
7.4.2 Comparison with high gain observers under sensor failure 155
7.5 Conclusions 156

8 Specific Kinetic Rates Regulation in Multi-Substrate Fermentation Processes 159
8.1 Introduction 160
8.2 Problem formulation 161
8.3 Nonlinear PI controller and second order sliding mode observer 163
8.3.1 Nonlinear PI control 164
8.3.2 Multiple rates observer 165
8.4 Simulations 166
8.5 Conclusions 169

III Synthetic genetic circuits design 171

9 Control of protein concentrations in heterogeneous cell populations 173
9.1 Introduction 174
9.2 System description 176
9.2.1 Cell-to-cell communication and feedback controller 176
9.2.2 Mathematical model 177
9.3 Approximation of the intracellular controller 179

9.4 Operation in the linear regime 180
9.5 Control of protein mean and variance 183
9.6 Simulations 184
9.7 Conclusions 188

General discussion **189**

Conclusions of the thesis **191**

Bibliography **199**

Appendices **217**

A Proofs **219**
A.1 Global topology analysis 219
A.2 Local topology analysis 220
A.3 Minimum χ function generalized gradient 223
A.4 Proof of Theorem 9.1 224
A.5 Proof of Theorem 9.2 226

B Algorithms and examples. **229**
B.1 Individual systems dynamics 229