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Xie, Haotian; Novak, Mateja; Wang, Fengxiang; Dragicevic, Tomislav; Rodriguez, Jose; Blaabjerg, Frede; Kennel, Ralph; Heldwein, Marcelo Lobo

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Cooperative Decision-making Approach for Multi-objective Finite Control Set Model Predictive Control without Weighting Parameters

Haotian Xie, *Member, IEEE*, Mateja Novak, *Member, IEEE*,
Fengxiang Wang, *Senior Member, IEEE*, Tomislav Dragicevic, *Senior Member, IEEE*,
José Rodríguez, *Life Fellow, IEEE*, Frede Blaabjerg, *Fellow, IEEE*
Ralph Kennel, *Senior Member, IEEE* and Marcelo Lobo Heldwein, *Senior Member, IEEE*

Abstract—Finite control set model predictive control (FCS-MPC) has gained increasing popularity as an emerging control strategy for electrical drive systems. However, it is still a challenging task to optimize weighting parameters, as multiple objectives are involved in the customized cost function. A cooperative decision-making approach for FCS-MPC is proposed in this article, to solve the optimization problems with manifold control objectives. By splitting the cost function, the optimization problem underlying multi-objective FCS-MPC is separated into a series of decomposed optimization problems. By doing so, the dimension of the decomposed problem is reduced to one. To collect the information for decision-making, an efficient sorting algorithm is applied for each control objective. The theory behind the cooperative decision-making approach is comprehensively analyzed, to validate both the effectiveness and efficiency of the proposed scheme. More specifically, the highlight is the adaptive mechanism on the number of desired candidates, to obtain a decent performance for torque and flux. The candidate which minimizes the switching frequency is selected as the optimal. The proposed scheme is experimentally verified and compared with the existing FCS-MPC without weighting parameters.

Index Terms—Model predictive control, multiple objectives, cooperative decision-making, weighting parameters optimization.

I. INTRODUCTION

FINITE control set model predictive control (FCS-MPC) is enabled to online resolve the optimal solution for constrained quadratic programming (QP) problem, which highlights its increasing presence in the control of power converters and electrical drive systems [1], [2]. Thanks to the

conceptual simplicity in the problem formulation, multiple conflicting disciplines and constraints are flexibly involved in the customized objective function [3], [4]. Regarding the discrete nature of power converters, the control inputs are directly enumerated for objective function minimization in a receding prediction horizon [5]. With the rapid development of digital controllers, FCS-MPC has spread from the process industry with a slow dynamic to a variety of power electronics applications, e.g., induction machine (IM) and permanent magnet synchronous machine (PMSM) drives, multi-level modular converters (MMCs) [6]–[8].

Predictive torque control (FCS-PTC) is one of the most popular schemes in the FCS-MPC family, as torque and stator flux are the optimized performance metrics in the electrical drive systems [9]. Despite that FCS-MPC achieves the attractive features of fast dynamic response, straightforward implementation and the ability to handle multi-objective non-linear control systems, the balance between multiple control objectives is very difficult to be compromised [10], [11]. The technical challenges in the weighting factor optimization are the involvement of more conflicting objectives and increased computational burden. In [12], an empirical weighting value is assigned to each control variable, to indicate the importance of the corresponding tracking error term in the objective function. However, the trial-and-error method is a tedious and time-consuming task without theoretical analysis, which requires a large number of repetitive simulation implementations. To deal with this issue, several artificial intelligence (AI) methods have been studied in the literature. [13], [14] proposes an artificial neural network (ANN) method for the design of parameters in FCS-PTC. However, the combination of weighting parameters optimized by an offline ANN can be hardly adjusted as the step change occurs. In [15], the weighting parameters of FCS-MPC are fine-tuned in real-time on a low-cost hardware platform. However, the scale of ANN becomes larger when multiple criteria are involved in the formulated optimization problem. In [16], an ANN-based MPC with floating weighting factors for the active rectifier is proposed. Four control objectives and a decoupled stability objective are handled in the proposed ANN-based MPC. Although the contributions of multiple objectives are assigned by the aforementioned AI approaches, the effectiveness of ANN is significantly influenced by the training resources.

To avoid the usage of weighting parameters in the multi-objective FCS-MPC, previous references [17], [18] reformulate the objective function by a single-objective term (e.g., flux error term). In [18], a FCS-MPC scheme using flux vector is applied for PMSM drives. However, only the state variables can be unified according to the state-space

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H. Xie is with the Chair of High-Power Converter Systems, Technical University of Munich, Munich 80333, Germany, and also with Quanzhou Institute of Equipment Manufacturing, Haixi Institutes, Chinese Academy of Sciences, Jinjiang, Quanzhou, 362200, China (e-mails: haotian.xie@tum.de).

M. Novak and F. Blaabjerg are with the AAU Energy, Aalborg University, 9220 Aalborg, Denmark (e-mail: nov@et.aau.dk; fbl@et.aau.dk).

F. Wang is with Quanzhou Institute of Equipment Manufacturing, Haixi Institutes, Chinese Academy of Sciences, Jinjiang, Quanzhou, 362200, China, and also with the Chair of High-Power Converter Systems, Technical University of Munich, Munich 80333, Germany (e-mail address: fengxiang.wang@fjirm.ac.cn).

T. Dragicevic is with Center of Electric Power and Energy, Technical University of Denmark, 2800 Kgs. Lyngby, Denmark (e-mail: tomdr@elektro.dtu.dk).

J. Rodríguez is with Faculty of Engineering, Universidad San Sebastián, Santiago 8420524, Chile (e-mail: jose.rodriguezp@uss.cl).

R. Kennel and M. Heldwein are with the Chair of High-Power Converter Systems, Technical University of Munich, Munich 80333, Germany (e-mails: ralph.kennel@tum.de; marcelo.heldwein@tum.de).

model of the control plant. It is not practical to eliminate all the weighting parameters, when additional constraints (e.g., switching frequency) are evaluated in the customized objective function. As can be understood, the switching frequency term is very important to be included in the objective function. A lower switching frequency can improve both the efficiency and power rating of the converters.

Recently, several solutions have been proposed to address the adaptive tuning for weighting parameters. The main concept centers around the decomposition of a high-dimension optimization problem. As can be understood, the weighting parameters are directly eliminated when the FCS-MPC optimization problem is separated into a series of decomposed problems. By doing so, the dimension of the distributed problem is reduced to 1. Optimization effectiveness means the ability to optimize the weighting factors for more conflicting control targets, while efficiency is the cost of increased algorithm complexity for weighting factor optimization. However, how to obtain the optimal solution with improved optimization effectiveness and efficiency is still an open issue. In [19], a ranking approach for multi-objective optimization is proposed to investigate the potential optimal solution. Although the ranking approach is conceptually simple, an additional weighting coefficient for each criterion is required. A quick-sort algorithm is incorporated into the FCS-MPC scheme to tackle more conflicting control targets (e.g., switching frequency) in [20]. The sums of the assigned ranking values are subsequently compared for performance evaluation. However, it is hard to select the optimal for the circumstances that the sums of ranking values are equal for different control inputs. In [21], the torque and flux error terms in the multi-variable FCS-MPC scheme are investigated in a generalized sequential manner. The effectiveness of the proposed method is impaired by the inherent drawback of the hierarchical structure. It is noteworthy that the number of control inputs is significantly narrowed when a certain control objective is optimized. In [22], a fixed switching frequency MPC without weighting factor is presented. The optimal solution is generated by two desired vectors with duty cycles, which are obtained by optimizing the single-objective terms. In [23], an even-handed criterion that results in a lower cross-error is applied for the selection of optimal vector in FCS-MPC. Although the priorities of the control objectives have been carefully assigned, the before-mentioned limitation of the hierarchical optimization structure should be taken into consideration when multiple control targets are involved. In [24], the preselected switching sequences below the constraints are optimized in a concurrent manner. Despite that the proposed method is allowed to deal with multiple control objectives simultaneously, the design of the boundaries for all the criteria is still a cumbersome process. An effective FCS-MPC scheme for PMSM drive without the involvement of weighting parameters is presented in [25]. It should be mentioned that only the torque and flux tracking errors are optimized in the proposed scheme. The proposed scheme becomes more complicated when the switching frequency term is involved in the objective function. Authors in [26] propose a novel boundary-based method for FCS-MPC without weighting factor. The torque boundaries are optimized online to monitor the number of valid vectors. In [27], a multi-objective genetic algorithm is presented for weighting factor optimization of the FCS-MPC schemes. To find the Pareto optimal set, the genetic algorithm entails a high computational burden for online iteration. A high-dimension

weighting parameter problem is optimized in [28]. The multiple cost functions whose hierarchy is determined by the error quantities, but the thresholds still require tuning. Although the abovementioned methods can resolve the optimal solution by collecting information from the decomposed problems, the improvement on both the optimization effectiveness and efficiency is still of great importance.

The motivation of this article is to obtain the optimal solution from the results of a series of decomposed problems, which adaptively modifies the relationship between multiple conflicting objectives for FCS-MPC schemes. By splitting of the objective function, the dimension of optimization problem underlying multi-objective FCS-MPC is reduced to 1. Thus, the issue of weighting parameters optimization is replaced by obtaining the optimal solution from the collected results of the decomposed problems, which are preselected by a fast-sorting algorithm. In the proposed cooperative decision-making approach, the optimization for torque and flux (performance metrics of the control plant) are regarded as the master problems, while minimizing the switching frequency is considered as the subproblem. The candidate vectors are initially generated by an adaptive mechanism between the master problems, which show a high similarity with the collected results. To reduce the algorithm complexity, fewer circumstances are categorized in the subproblem. A proper number of candidate vectors is determined by modifying the number of collected results for the master problems. The candidate vector which minimizes the switching frequency is selected as the optimal solution for the multi-objective FCS-MPC problem. Compared with the state-of-the-art FCS-MPC schemes without weighting parameters, the effectiveness and efficiency of the proposed cooperative decision-making approach are experimentally validated on a 2.2 kW IM testbench. The contributions of the article are summarized as follows.

- 1) The relationship between multiple objectives in the FCS-MPC schemes are fine-tuned by the proposed cooperative decision-making approach. The cumbersome process of weighting parameters design is eliminated by separating FCS-MPC into a series of decomposed problems. By doing so, the design and implementation of FCS-MPC is significantly improved without the need for tuning of weighting parameters.

- 2) The number of control inputs are sufficient for the master problems, which overcomes the drawback of the hierarchical structure. The proposed algorithm improves its effectiveness by resolving the global optimal for the master problems. Due to an avoidance of a worst case for both the master problems, a smaller ripples are obtained in the performance metrics.

- 3) The algorithm complexity is reduced by modifying the collected results in the master problems. Owing to a proper number of candidate vectors, fewer circumstances are considered in the subproblem. The number of comparisons is reduced by a fast-sorting algorithm. Based on the above, the proposed decision-making approach is computationally efficient.

The rest of the article is organized as follows. The problem formulation of multi-objective FCS-MPC scheme is described in Section II. The principle of cooperative decision-making approach is investigated in Section III. The proposed cooperative decision-making approach for multi-objective FCS-MPC is experimentally verified in Section IV. Finally, Section V concludes this article.

II. PROBLEM FORMULATION OF MULTI-OBJECTIVE FCS-MPC

A. Control Plant Description

The state-space model of IM is represented in the stationary reference frame,

$$\begin{bmatrix} \frac{d\hat{\psi}_s}{dt} \\ \frac{d\hat{\psi}_r}{dt} \end{bmatrix} = \left(\begin{bmatrix} -R_s & 0 \\ 0 & -R_r \end{bmatrix} \begin{bmatrix} L_s & L_m \\ L_m & L_r \end{bmatrix}^T + \begin{bmatrix} 0 & 0 \\ 0 & j\omega \end{bmatrix} \right) \begin{bmatrix} \hat{\psi}_s \\ \hat{\psi}_r \end{bmatrix} + \begin{bmatrix} 1 & 0 \\ 0 & 0 \end{bmatrix} \begin{bmatrix} u_s \\ 0 \end{bmatrix}, \quad (1)$$

$$\begin{bmatrix} \hat{i}_s \\ \hat{i}_r \end{bmatrix} = \begin{bmatrix} L_s & L_m \\ L_m & L_r \end{bmatrix}^T \begin{bmatrix} \hat{\psi}_s \\ \hat{\psi}_r \end{bmatrix}, \quad (2)$$

where the stator and rotor resistances are represented by R_s and R_r , the stator, rotor and magnetizing inductances are denoted by L_s , L_r and L_m , respectively. The stator and rotor currents are \hat{i}_s and \hat{i}_r , $\hat{\psi}_s$ and $\hat{\psi}_r$ are the estimated stator and rotor flux, ω denotes the rotor angular speed. The applied topology of the inverter is a 2-level voltage-source-inverter (VSI). The gate drive signal of the upper power device in the phase-leg configuration is denoted by S_a , S_b , S_c , respectively. As the upper power device turns on, the corresponding gate drive signal is 1. Otherwise, the gate drive signal is 0. The control input u_s is the applied voltage vector, which is transformed into the stationary $\alpha\beta$ frame,

$$u_{s\alpha\beta} = \begin{bmatrix} \frac{2}{3} & -\frac{1}{3} & -\frac{1}{3} \\ 0 & \frac{1}{\sqrt{3}} & -\frac{1}{\sqrt{3}} \end{bmatrix} u_{sabc}. \quad (3)$$

B. Multi-objective FCS-MPC

The FCS-MPC schemes solve the multi-objective optimization problem by minimizing the tracking errors between the predicted and reference values. Multiple conflicting targets, e.g., torque, flux and switching frequency are evaluated in the formulated objective function. Regarding the time-delay compensation, the future behavior of stator current and flux $\hat{i}_s(k+2)$ and $\hat{\psi}_s(k+2)$ are calculated by forward Euler discretization,

$$\hat{\psi}_s(k+1) = \hat{\psi}_s(k) + T_s (u_s(k) - \hat{i}_s(k) \cdot R_s), \quad (4)$$

$$\hat{i}_s(k+1) = (1 - \frac{T_s}{\tau_\sigma}) \cdot \hat{i}_s(k) + \frac{T_s}{\tau_\sigma R_\sigma} \cdot [k_r (\frac{1}{\tau_r} - j\omega(k)) \hat{\psi}_r(k) + u_s(k)], \quad (5)$$

$$\hat{\psi}_s(k+2) = \hat{\psi}_s(k+1) + T_s (u_s(k+1) - \hat{i}_s(k+1) \cdot R_s), \quad (6)$$

$$\hat{i}_s(k+2) = (1 - \frac{T_s}{\tau_\sigma}) \cdot \hat{i}_s(k+1) + \frac{T_s}{\tau_\sigma R_\sigma} \cdot [k_r (\frac{1}{\tau_r} - j\omega(k)) \hat{\psi}_r(k+1) + u_s(k+1)], \quad (7)$$

where T_s is the sampling period, $k_r = L_m/L_r$, $R_\sigma = R_s + k_r^2 \cdot R_r$, $\sigma = 1 - (L_m^2/L_s L_r)$ and $L_\sigma = \sigma \cdot L_s$ are the parameters of IM. The predicted torque $\hat{T}(k+2)$ is expressed as

$$\hat{T}(k+2) = \frac{3}{2} p \cdot Im \{ \hat{\psi}_s(k+2) \cdot \hat{i}_s(k+2) \}. \quad (8)$$

The objective function J with the involvement of torque, flux and switching frequency terms is formulated as

$$J = [T^* - \hat{T}(k+2)]^2 + \lambda_\psi [\|\psi_s^*\| - \|\hat{\psi}_s(k+2)\|]^2 + \lambda_{sw} \cdot n_{sw}^2 + I_m(k+2), \quad (9)$$

where λ_ψ and λ_{sw} are the weighting parameters. n_{sw} is the number of switching changes in a sampling interval, $I_m(k+2)$ is the limitation term for stator current magnitude,

$$I_m(k+2) = \begin{cases} 0, & \text{if } |\hat{i}_s(k+2)| \leq |\hat{i}_{smax}| \\ \gamma >> 0, & \text{if } |\hat{i}_s(k+2)| > |\hat{i}_{smax}| \end{cases} \quad (10)$$

As can be understood, multiple control objectives are simultaneously optimized in the objective function of FCS-MPC (see Fig. 1). Note that the weighting parameters, e.g., λ_ψ and λ_{sw} are applied to balance the importance of all the control objectives. Therefore, the selection of weighting parameters has a significant influence on the performance metrics of FCS-MPC schemes.

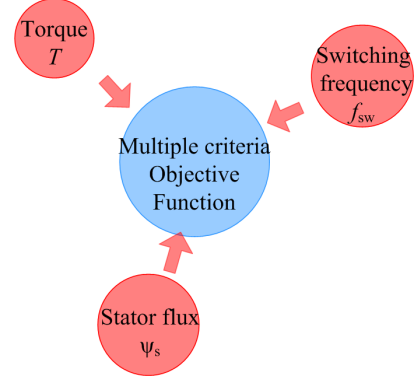


Fig. 1. Multiple control objectives in FCS-MPC.

III. PRINCIPLE OF PROPOSED COOPERATIVE DECISION-MAKING APPROACH

A cooperative decision-making approach is proposed for the multi-objective FCS-MPC schemes, to avoid the time-consuming task of weighting parameters design. As shown in Fig. 2, the proposed approach consists decomposition of the FCS-MPC problem, results collection of the decomposed problems, adaptive mechanism for the master problem and the decision-making for the subproblem. Owing to that there is no weighting factor optimization for the current limitation term, the current limitation term is not reflected in Fig. 2.

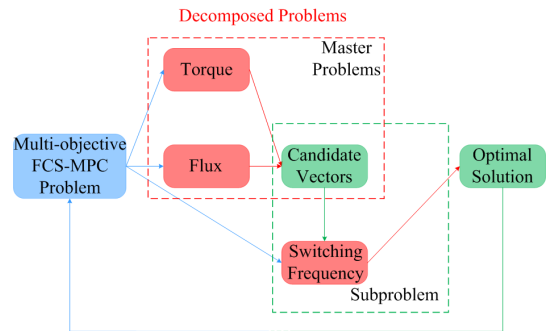


Fig. 2. Close-loop schematic of the proposed cooperative decision-making approach.

A. Decomposition of the FCS-MPC problem

The concept behind the proposed approach is to separate the multi-objective FCS-MPC (which is a high-dimension optimization problem) into a series of decomposed problems. As shown in Fig. 3, the decomposed problems are optimizing

the torque, flux and switching frequency terms, respectively. The tracking error terms (11-13) are expressed as

$$J_1 = [T^* - \hat{T}(k+2)]^2 + I_m(k+2), \quad (11)$$

$$J_2 = [\|\psi_s^* - \|\hat{\psi}_s(k+2)\|]^2 + I_m(k+2), \quad (12)$$

$$J_3 = n_{sw}^2 + I_m(k+2). \quad (13)$$

It is noteworthy that the current limitation term is not a conflicting control objective in the weighting factor optimization of FCS-MPC schemes. There is no requirement to design or optimize a weighting factor for the current limitation term. The optimization of the parameter γ has no compromise on the performance of the other control objectives. Thus, the design of weighting parameters is not required, because the dimensions of the decomposed problems are 1. Based on the above, "how to deal with the results of the decomposed problems" has become an open issue.

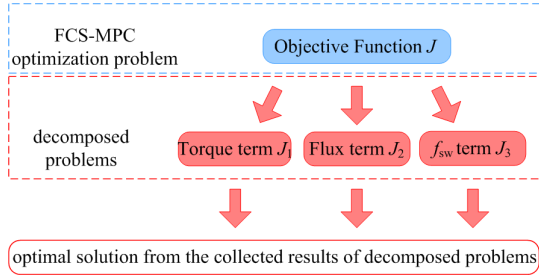


Fig. 3. Decomposition of the multi-objective FCS-MPC problem.

B. Results Collection of the Decomposed Problems

The design of weighting parameters is eliminated by the decomposition of multi-objective FCS-MPC problem. The results of the decomposed problems are subsequently collected by a fast-sorting algorithm. The fast-sorting algorithm for torque, flux and switching frequency terms are carried out in a concurrent manner. As shown in Fig. 4, the results collection for the torque term is illustrated as an example. Note that there are two arrays u_T and J_1 to collect the control inputs and the values of tracking error term, respectively. i denotes the index of the control input. u_0 and $J_1(u_0)$ are initially saved in the first element of the arrays. If the index i is an even value ($i = 2m$), e.g., $i = 2$, the value $J_1(u_2)$ is compared with $J_1[1]$. u_2 and $J_1(u_2)$ are saved in $u_T[2]$ and $J_1[2]$, when $J_1(u_2) \geq J_1[1]$. Otherwise, a comparison between $J_1(u_2)$ and $J_1[0]$ is conducted. $u_T[0]$ is replaced by u_2 when $J_1(u_2) < J_1[1]$. Conversely, $u_T[1]$ is replaced by u_2 . If the index i is an odd value ($i = 2m + 1$), the value $J_1(u_i)$ is compared with $J_1[m]$. The aim of the fast-sorting algorithm is to obtain the rearranged control inputs, for which the value of tracking error term are monotonically increasing. The number of control inputs for each control objective is 7. As shown in Fig. 5, the vectors $u_T[0 - 6]$ are applied for torque optimization, and the vectors $u_F[0 - 6]$ are applied for flux optimization. If we optimize torque, flux and switching frequency in a concurrent manner, 7 more vectors $u_{sw}[0 - 6]$ are required also for the optimization of switching frequency. Therefore, the total number of vectors is reduced from 21 to 14 in the proposed method.

C. Adaptive Selection Mechanism for the Master Problems

The control inputs are rearranged for both the master problems that the values of tracking error terms are monotonically increasing. The description of the adaptive selection mechanism for the master problems is depicted in Fig. 5. The first three control inputs for the two master problems $u_T[0 - 2]$ and $u_F[0 - 2]$ are initially selected, to achieve an overall decent performance (because the corresponding tracking errors are smaller). As can be understood, a considerable good performance for torque and flux can be obtained by the vector which shows the similarity with one of the preselected control inputs (for the two master problems).

However, the drawback is that the number of the candidate vectors generated by $u_T[0 - 2]$ and $u_F[0 - 2]$ is uncertain, for which the number ranges from 0 to 3. Note that the subproblem optimization is categorized by the number of candidate vectors n . The optimal solution can not be resolved in the FCS-MPC optimization problem, if there is no candidate vectors for the two master problems. On the contrary, the torque and flux performance is not satisfactory, when the optimal solution is selected from the three candidate vectors in the suboptimal solution. Therefore, the desired number of candidate vectors is 1 or 2.

To obtain the desired number of candidate vectors, an adaptive mechanism on the number of preselected control inputs for flux optimization (Master problem 2). As shown in Fig. 5, one more control input in u_F is preselected as $n < 1$. Otherwise, the number of preselected control inputs in u_F is reduced as $n > 2$. The adaptive number of preselected control inputs is applied in the current sampling period, and defined as the initial value in the next interval.

The merits of the proposed adaptive selection mechanism is clarified as twofold. First, an overall decent performance is achieved by the candidate vector which shows the similarity with the preselected control inputs for both the master problems. Moreover, a worst case for torque and flux is avoided, which results in a smaller ripple. The latter advantage is a few number of circumstances are considered in the subproblem, which leads to a reduced algorithm complexity.

D. Subproblem Optimization

The subproblem optimization aims to select the optimal solution from the candidate vectors, by minimizing the number of switching changes. As $n = 1$, the only candidate vector is directly considered as the optimal solution, which achieves a considerably decent performance in terms of torque and flux. If there are two candidate vectors, the one minimizes J_3 (the number of switching changes) is selected as the optimal.

According to the collected results for torque and flux, the proposed algorithm obtains the common candidates which performs well in terms of torque and flux. Moreover, the worst case is always avoided for both torque and flux. As the common candidates are obtained, the switching frequency term is optimized on the basis of a good torque and flux performance. Therefore, the proposed algorithm can achieve satisfactory performance metrics for all the control objectives.

E. Performance Evaluation

Comparisons between a series of FCS-MPC schemes without weighting parameters (by the decomposition of multi-objective optimization problem) are summarized in TABLE I.

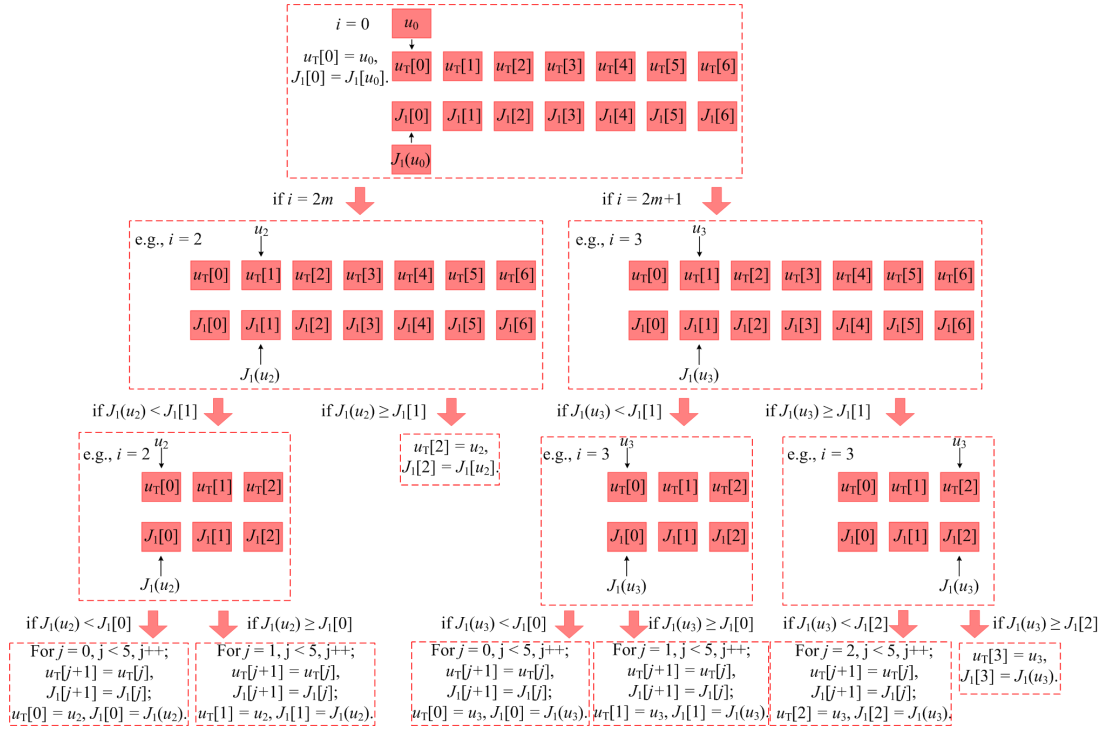


Fig. 4. Description of the fast-sorting algorithm.

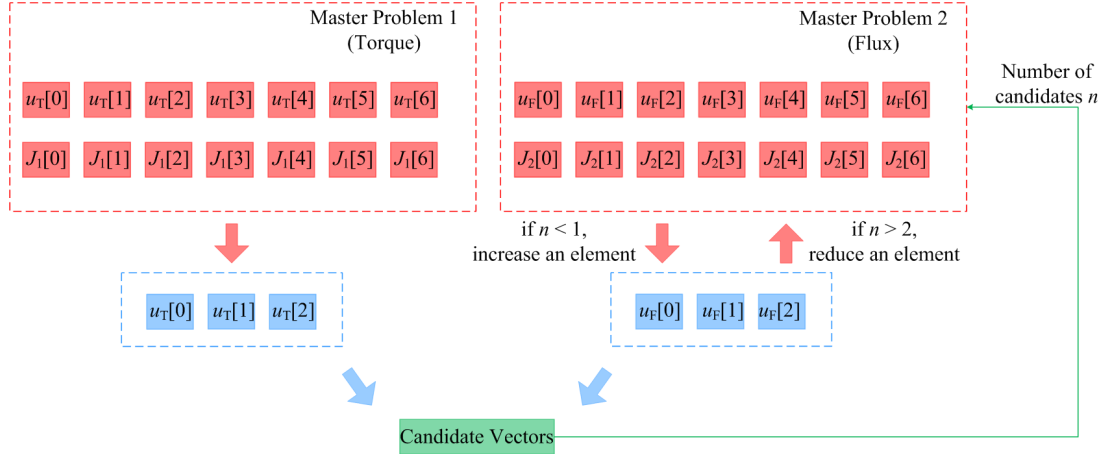


Fig. 5. Description of the Adaptive Mechanism for the Master Problems.

All the three methods has the merits of relationship optimization between multiple control objectives, adaptive tuning during the transient state and no requirement of extra parameters. Compared with the state-of-the-art methods [21, 25], both the effectiveness and efficiency of the proposed approach are improved. It is noteworthy that the proposed approach is not restricted by the number of control inputs and control targets. Both the worse cases for torque and flux are avoided. More specifically, the algorithm complexity is reduced due to a few number of circumstances.

An overall control diagram of the proposed method is shown in Fig. 6. The merits of the proposed control method are summarized as below.

1) The weighting factors of multiple conflicting objectives in the FCS-MPC schemes are fine-tuned by the proposed cooperative decision-making approach. Moreover, the importance for all the control objectives is adaptively optimized during the transient state.

2) The effectiveness of weighting factor optimization is improved. All the control inputs are fully optimized in the

master problems. The number of control inputs are sufficient for the master problems, which overcomes the drawback of the hierarchical structure. A smaller ripples are obtained in the performance metrics due to an avoidance of the worst case.

3) The algorithm efficiency of weighting factor optimization is improved. The number of comparisons is reduced by a fast-sorting algorithm. Only two circumstances are considered in the subproblem. The proposed cooperative decision-making approach is computationally efficient.

IV. EXPERIMENTAL VERIFICATION

The proposed cooperative decision-making approach for multi-objective FCS-MPC is investigated on a 2.2 kW lab-built IM testbench (see Fig. 7). The applied structure of motor is a pair of 2.2 kW squirrel-cage induction machine. As shown in Fig. 7, the left IM (E) driven by the Servostar inverter (B) is used as the main machine, the right one (F) driven by the Danfoss FC-302 inverter (A) is used as the load

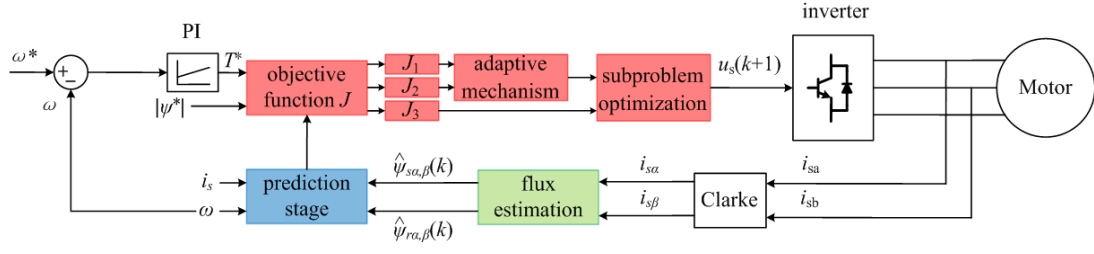


Fig. 6. Control diagram of the proposed method.

TABLE I
COMPARISONS BETWEEN A SERIES OF FCS-MPC SCHEMES WITHOUT WEIGHTING PARAMETERS

Methods	Generalized Sequential [21]	Effective Method [25]	Cooperative Decision-making
Optimization the importance between multiple objectives	✓	✓	✓
Adaptive tuning during the transient state	✓	✓	✓
No extra parameters	✓	✓	✓
No limitation on the number of control inputs and targets	×	✓	✓
Avoidance of a worse case for torque and flux	×	✓	✓
Reduced algorithm complexity	✓	×	✓

machine. The parameters of the IMs are listed in TABLE. II. A 1.4 GHz self-made real-time controller is applied for the implementation with a sampling period $T_s = 62.5 \mu s$. The proposed algorithm is compared with the GS-MPC [21] and effective MPC [25]. The weighting parameters are eliminated in all the comparative schemes by the decomposition of the FCS-MPC problems.



Fig. 7. Experimental Setup. (A) 3.0 kW Danfoss FC-302 inverter, (B) 14 kVA Servostar620 inverter, (C) Control panel (D) Self-made real-time controller (E) Main machine (F) Load machine.

TABLE II
PARAMETERS OF THE INDUCTION MACHINE.

Parameters	Values
DC link voltage V_{dc} [V]	582
Stator resistance R_s [Ω]	2.68
Rotor resistance R_r [Ω]	2.13
Magnetizing inductance L_m [H]	0.275
Stator inductance L_s [H]	0.283
Rotor inductance L_r [H]	0.283
Speed PI controller gains k_p, k_i [/]	0.23, 5.38
Pole pairs N_p [/]	1
Nominal rotor speed ω_{nom} [rpm]	2772
Nominal stator flux ψ_{snom} [Wb]	0.71
Nominal torque T_{nom} [Nm]	7.5

A. Steady-state Performance

The steady-state performance is initially investigated for the three comparative schemes. The first test scenario is 10 % rotor speed with a 50 % load torque. As shown in Fig. 8, the

smallest torque and current ripples (1.84 Nm and 0.37 A) are obtained by the proposed algorithm. The torque error in the GSMPC is 2.05 Nm, while the value in the effective MPC is 1.96 Nm. The current errors of the GS-MPC and the effective MPC are 0.40 A and 0.38 A. The second test scenario is conducted at the nominal rotor speed with a nominal load torque. The similar performance metrics can be found in Fig. 9. The torque ripples of GS-MPC, effective MPC and the proposed scheme are 2.09 Nm, 2.07 Nm and 1.88 Nm, respectively. Due to more compromises in the vector selection, the ripples in the effective MPC is higher than the proposed algorithm. In the first test scenario, the switching frequencies of the effective MPC and proposed algorithm are 818 Hz and 821 Hz. Owing to lack of effectiveness on switching frequency optimization, a higher switching frequency (845 Hz) is achieved by GS-MPC. In the second test scenario, the switching frequencies of the GS-MPC, effective MPC and the proposed algorithm are 2.82 kHz, 2.77 kHz and 2.77 kHz, respectively. The experimental results on switching frequency validate that the proposed algorithm achieves a similar value of switching frequency with effective MPC, which is lower than that of GS-MPC. The turnaround time of the three algorithms are compared in TABLE. V. The turnaround time of the proposed algorithm is 26 μs . GS-MPC and the effective MPC obtains a longer turnaround time, which is 28 μs and 36 μs , respectively. There are two reasons for a lower turnaround time in the proposed algorithm. First, a fast-sorting algorithm is applied in the proposed cooperative decision-making approach. The least number of comparisons is 10 for each control objective, the highest number of comparisons is 15. The number of comparison is lower than exhaustive search. Second, an adaptive selection mechanism is applied to simplify the circumstances. The number of candidates is only 1 or 2 in proposed algorithm. The optimal is directly obtained by optimizing the switching frequency.

The values of THD are calculated by the collected data of oscilloscope with a sampling interval and 5000 Hz harmonics. In the first steady state scenario, the IM runs at a 10 % rotor speed with a 50 % load torque. In the first test scenario, the flux THD of GS-MPC, effective MPC and the proposed method are 6.33 %, 8.01 % and 5.94 %, respectively.

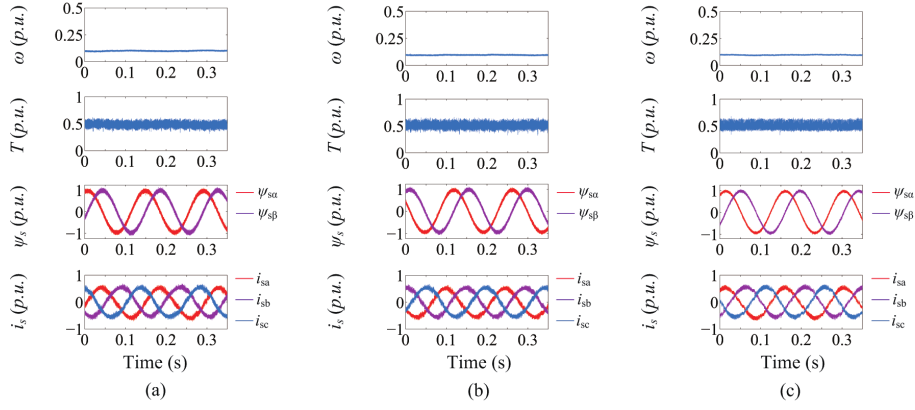


Fig. 8. Stead-state performance at 10 % rotor speed and 50 % load torque. (a) GS-MPC (b) effective MPC (c) proposed cooperative decision-making approach.

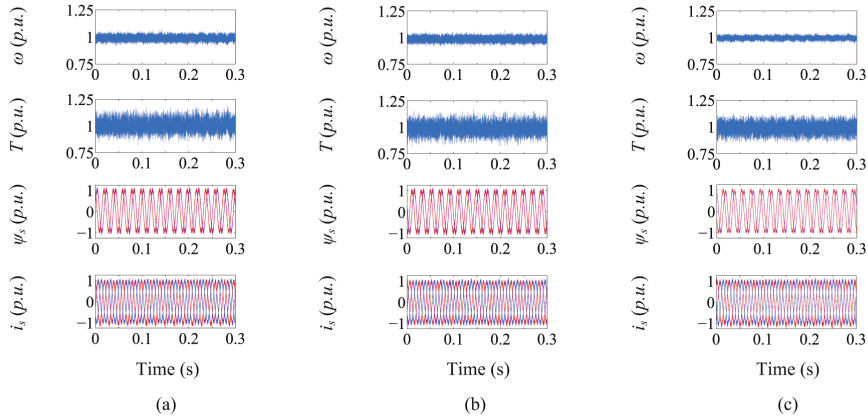


Fig. 9. Stead-state performance at the nominal speed and nominal torque. (a) GS-MPC (b) effective MPC (c) proposed cooperative decision-making approach.

The values of current THD are 11.71 %, 12.91 % and 9.77 %, respectively (see TABLE. III).

TABLE III
STEADY-STATE PERFORMANCE METRICS BETWEEN GS-MPC, EFFECTIVE MPC AND THE PROPOSED ALGORITHM (10 % ROTOR SPEED WITH 50 % LOAD TORQUE)

Algorithms	GS-MPC	effective MPC	proposed
T_{err} [Nm]	2.05	1.96	1.84
i_{serr} [A]	0.40	0.38	0.37
ψ_{sTHD} [%]	6.33	8.01	5.94
i_{sTHD} [%]	11.71	12.91	9.77
f_{sw} [kHz]	0.845	0.818	0.821

In the second test scenario of nominal speed and torque, the values of flux and current THD are compared in TABLE. IV. The flux THD of the three comparative methods are 2.47 %, 3.47 % and 3.21 %, respectively. As shown in TABLE. IV, the current THD of GS-MPC, effective MPC and the proposed algorithm are 7.54 %, 7.94 % and 7.69 %.

The optimization of switching frequency is validated in Fig. 10, which shows the results of the number of candidates in the proposed algorithm. By adjusting the number of collected control inputs in the optimization of flux, the number of common candidates is effectively ranged from 1 to 2. The optimization of switching frequency is taken place between the two candidates, when the number of candidates is 2. It is

TABLE IV
STEADY-STATE PERFORMANCE METRICS BETWEEN GS-MPC, EFFECTIVE MPC AND THE PROPOSED ALGORITHM (NOMINAL ROTOR SPEED AND LOAD TORQUE)

Algorithms	GS-MPC	effective MPC	proposed
T_{err} [Nm]	2.09	2.07	1.88
i_{serr} [A]	0.84	0.83	0.79
ψ_{sTHD} [%]	2.47	3.47	3.21
i_{sTHD} [%]	7.54	7.94	7.69
f_{sw} [kHz]	2.82	2.77	2.77

TABLE V
TURNAROUND TIME OF THE COMPARATIVE ALGORITHMS

Algorithms	GS-MPC	effective MPC	proposed
T_{algo} [μ s]	28	36	26

noteworthy that the possibility of obtaining two candidates is 7/16 in the test scenario of 10 % rated speed with 50 % load torque, while the possibility is 4/16 in the scenario of rated rotor speed and load torque. It is confirmed in Fig. 9 that the switching frequency term is effectively optimized on the basis of a good torque and flux performance.

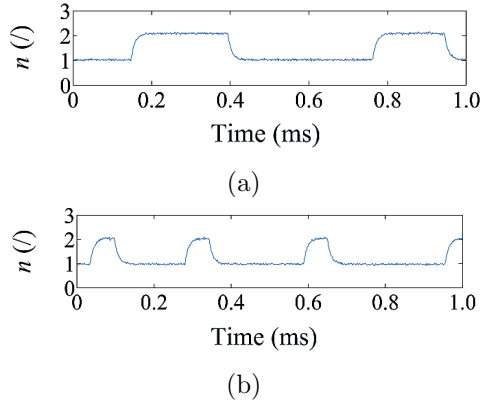


Fig. 10. Collected number of candidate vectors. (a) 10 % rotor speed and 50 % load torque (b) nominal speed and nominal torque.

B. Dynamic Performance

A speed step test is carried out to evaluate the dynamic performance of the proposed algorithm. The IM operates at 50 % rotor speed with a 50 % load torque. At $t = 62 \text{ ms}$, a speed step from 50 % to 75 % rotor speed is implemented. As shown in Fig. 11, all the three algorithms show the fast dynamic response that the settling time is 90 ms. The load torque rises to the nominal value in $300 \mu\text{s}$. Note that the importance of the multiple objectives is fine-tuned after the transient state. It can be observed that the proposed algorithm obtains a smaller torque ripple. The torque errors of the GS-MPC, effective MPC and the proposed algorithm are 1.90 Nm, 1.66 Nm and 1.53 Nm, respectively. The dynamic performance metrics between GS-MPC, effective MPC and the proposed algorithm are listed in TABLE. VI. The proposed algorithm retains the merit of fast dynamic response of the FCS-MPC schemes. The settling time of rotor speed is 90 ms. The rise time of load torque is $300 \mu\text{s}$.

TABLE VI
DYNAMIC PERFORMANCE METRICS BETWEEN GS-MPC, EFFECTIVE MPC AND THE PROPOSED ALGORITHM

Performance metrics	GS-MPC	effective MPC	proposed
T_{err} [Nm]	1.90	1.66	1.53
Settling time [ms]	90	90	90
Torque rise time [μs]	300	300	300

C. Robustness Performance

In the first test scenario, three FCS-MPC methods without weighting factor are compared with a 42 % R_s mismatch (from 2.68Ω to 3.8Ω). The IM runs at a nominal speed with a nominal load torque. It is of great importance to optimize the weighting factor in the robustness validation, because parameter mismatch can be considered as a change in the operating condition. It has been investigated in [29] that the conventional FCS-MPC suffers from a weak robustness against R_s mismatch. As shown in Fig. 12, all of the three comparative methods show a strong robustness against R_s mismatch. The reason is that the weighting factors are optimized in all three methods. As shown in TABLE. VII, it is noteworthy that the proposed algorithm obtains a 8.9 % and 33.6 % reduction in the current THD, compared with GS-MPC and effective MPC, respectively.

The second test scenario validates the robustness performance against 88 % R_r mismatch. The rotor resistance increases from 2.13Ω to 4Ω . As shown in Fig. 13, the GS-MPC, effective MPC for comparison and the proposed method show a strong robustness against a variation of 88 % R_r . The proposed algorithm shares a similar value of current THD with effective MPC.

TABLE VII
COMPARISONS OF CURRENT THD BETWEEN GS-MPC, EFFECTIVE MPC AND THE PROPOSED ALGORITHM

Current THD [%]	GS-MPC	effective MPC	proposed
42 % R_s mismatch	9.07	12.44	8.26
88 % R_r mismatch	9.33	8.34	8.35

V. CONCLUSION

A cooperative decision-making approach for multi-objective FCS-MPC without the involvement of weighting parameters is proposed in this article. The basic concept behind the proposed algorithm is the decomposition of FCS-MPC optimization problem. Based on the above, a fast-sorting algorithm is applied to collect the results of the decomposed problems. Subsequently, the candidate vectors are obtained by an adaptive mechanism for the master problems. The highlight is the adaptive number of collected results, which leads to a proper number of candidate vectors. The candidate vector which minimizes the switching frequency is regarded as the optimal solution for the multi-objective FCS-MPC problem. Compared with two FCS-MPC schemes without weighting parameters, both the effectiveness and efficiency of the proposed algorithm are experimentally validated on the 2.2 kW IM testbench.

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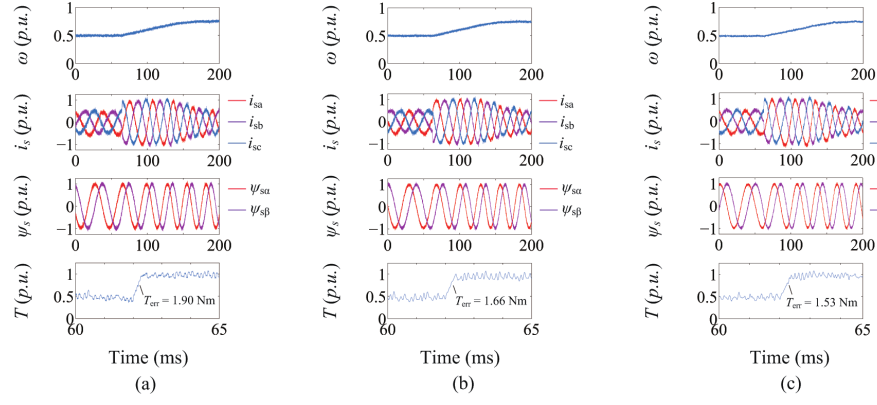


Fig. 11. Dynamic performance from 50 % to 75 % rotor speed with a 50 % load torque. (a) GS-MPC (b) effective MPC (c) proposed cooperative decision-making approach.

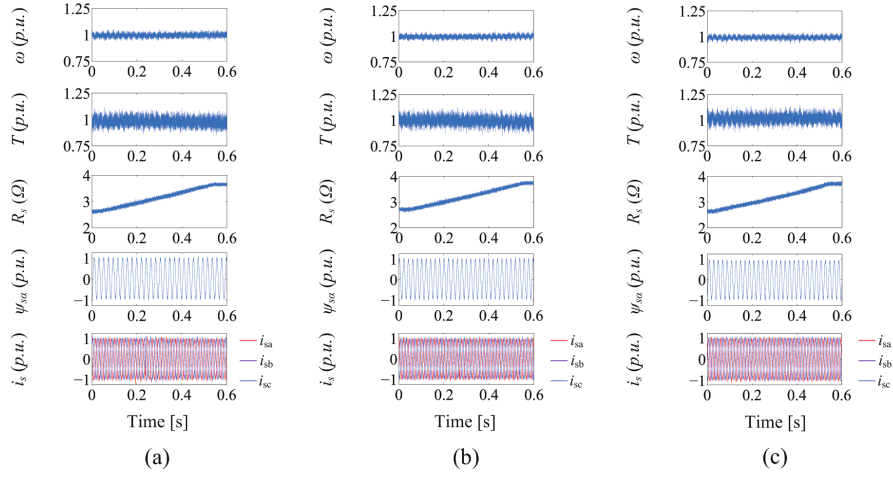


Fig. 12. Comparisons of robust performance with a 42 % R_s mismatch between GS-MPC, effective MPC and the proposed method. (a) GS-MPC (b) effective MPC (c) proposed cooperative decision-making approach.

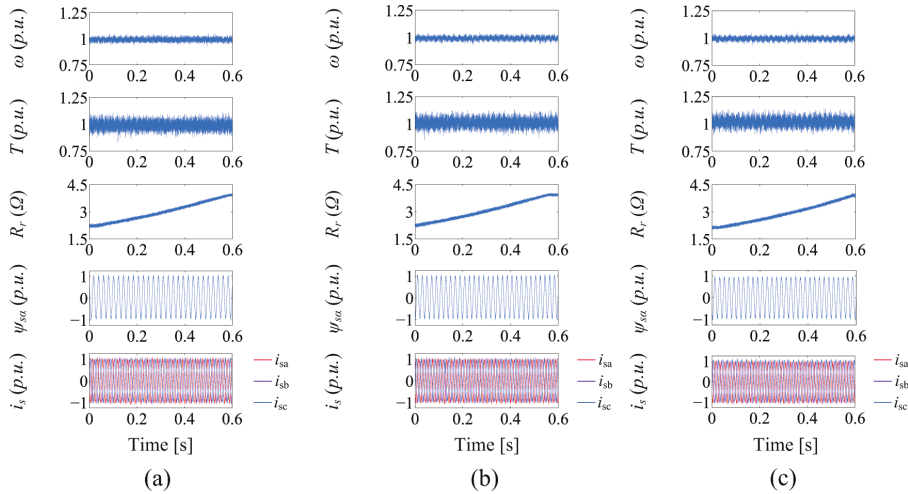


Fig. 13. Comparisons of robust performance with a 88 % R_r mismatch between GS-MPC, effective MPC and the proposed method. (a) GS-MPC (b) effective MPC (c) proposed cooperative decision-making approach.

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Haotian Xie (Member, IEEE) was born in Jiangsu Province, China, in 1990. He received the B.S. and M.Sc degrees in electronic engineering from Nanjing University of Aeronautics and Astronautics, Nanjing, China, in 2013 and 2017, respectively. In 2023, he received Ph.D. degree in electrical engineering at the Chair of High-Power Converter Systems with the Department of Energy and Process Engineering at the Technical University of Munich (TUM), Munich, Germany.

His research interests include modern predictive control, sensorless control for electrical machine drive system.



Mateja Novak (Member, IEEE) received the M.Sc. degree in electrical engineering and information technology from the Zagreb University, Zagreb, Croatia, in 2014, and the Ph.D. degree in electrical engineering from the Aalborg University, Aalborg, Denmark, in 2020.

She was working as a Research Associate with the Faculty of Electrical Engineering and Computing, Zagreb University, until 2016. In 2018, she was a Visiting Researcher with the Chair of Power Electronics, Kiel University, Kiel, Germany.

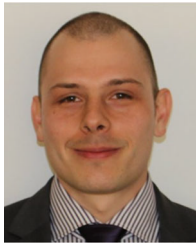
Currently, she is a Postdoctoral Researcher with the Department of Energy Technology, Aalborg University. Her research interests include model predictive control, multilevel converters, statistical model checking, reliability of power electronic systems, and renewable energy systems.

Dr. Novak is the recipient of EPE Outstanding Young EPE Member Award for the year 2019 and 2nd prize winner of 2021 IEEE-IES Student and Young Professional Competition.



Fengxiang Wang (Senior Member, IEEE) was born in Jiujiang, China, in 1982. He received the B.S. degree in electronic engineering and the M.S. degree in automation from Nanchang Hangkong University, Nanchang, China, in 2005 and 2008, respectively. In 2014, he received Ph.D. degree in electrical engineering at the Institute for Electrical Drive Systems and Power Electronics, Technische Universität München, Munich, Germany.

Currently he is working as full professor and deputy director of Quanzhou Institute of Equipment Manufacturing, Haixi Institutes, Chinese Academy of Sciences, China. He serves as IET Fellow, IEEE Senior Member, Associate Editor for IEEE Transactions on Industrial Electronics and IEEE Transactions on Energy Conversion. As General Chair, he organized IEEE 5th International Symposium on Predictive Control of Electrical Drives and Power Electronics (PRECEDE). His research interests include predictive control and sensorless control for electrical drives and power electronics.



Tomislav Dragicevic (Senior Member, IEEE) received the M.Sc. and industrial Ph.D. degrees in electrical engineering from the Faculty of Electrical Engineering, University of Zagreb, Zagreb, Croatia, in 2009 and 2013, respectively.

From 2013 to 2016, he was a Postdoctoral Researcher with the Aalborg University, Aalborg, Denmark. From 2016 to 2020, he was an Associate Professor with the same university. He was a Guest Professor with the Nottingham

University, Nottingham, U.K., during Spring/Summer of 2018. From 2020, he is a Professor with the Technical University of Denmark, Kongens Lyngby, Denmark. He has authored and coauthored more than 230 technical publications (more than 100 of them are published in international journals, mostly in IEEE), eight book chapters, and a book in the field. His research interests include application of advanced control, optimization and artificial intelligence-inspired techniques to provide innovative and effective solutions to emerging challenges in design, control, and cyber-security of power-electronics intensive electrical distributions systems and microgrids.

Dr. Dragicevic serves as an Associate Editor of the IEEE Transactions on Industrial Electronics, IEEE Transactions on Power Electronics, IEEE Emerging and Selected Topics in Power Electronics, and in the IEEE Industrial Electronics Magazine. He is a recipient of the Koncar Prize for the Best Industrial PhD Thesis in Croatia, a Robert Mayer Energy Conservation award, and is the winner of an Alexander Von Humboldt Fellowship for experienced researchers.



José Rodríguez (Life Fellow, IEEE) received the Engineer degree in electrical engineering from the Universidad Tecnica Federico Santa Maria, in Valparaiso, Chile, in 1977 and the Dr.-Ing. degree in electrical engineering from the University of Erlangen, Erlangen, Germany, in 1985.

He has been with the Department of Electronics Engineering, Universidad Tecnica Federico Santa Maria, since 1977, where he was full Professor and President. Since 2015 to 2019

he was the President of Universidad Andres Bello in Santiago, Chile. Since 2022 he is President of Universidad San Sebastian in Santiago, Chile. He has coauthored two books, several book chapters and more than 700 journal and conference papers. His main research interests include multilevel inverters, new converter topologies, control of power converters, and adjustable-speed drives. He has received a number of best paper awards from journals of the IEEE.

Dr. Rodriguez is member of the Chilean Academy of Engineering. In 2014 he received the National Award of Applied Sciences and Technology from the government of Chile. In 2015 he received the Eugene Mittelmann Award from the Industrial Electronics Society of the IEEE. In years 2014 to 2022 he has been included in the list of Highly Cited Researchers published by Web of Science.



Frede Blaabjerg (Fellow, IEEE) received the Ph.D. degree in electrical engineering from the Aalborg University, Aalborg, Denmark, in 1995.

He is Honoris Causa at the University Politehnica Timisoara (UPT), Timisoara, Romania and Tallinn Technical University (TTU), Tallinn, Estonia. He was with the ABB-Scandia, Randers, Denmark, from 1987 to 1988. He became an Assistant Professor in 1992, an Associate Professor in 1996, and a Full Professor of Power Electronics and Drives, in 1998, Aalborg University, Aalborg, Denmark. In 2017, he became a Villum Investigator.

He has published more than 600 journal papers in the fields of power electronics and its applications. He is the coauthor of four monographs and editor of ten books in power electronics and its applications. His research interests include power electronics and its applications such as in wind turbines, photovoltaics (PV) systems, reliability, harmonics, and adjustable speed drives.

Dr. Blaabjerg was the Editor-in-Chief of the IEEE Transactions on Power Electronics, from 2006 to 2012. In 2019-2020, he served as a President of the IEEE Power Electronics Society. He is also the Vice President of the Danish Academy of Technical Sciences. He has been Distinguished Lecturer for the IEEE Power Electronics Society, from 2005 to 2007, and for the IEEE Industry Applications Society, from 2010 to 2011, as well as 2017 to 2018. He was nominated by Thomson Reuters to be between the most 250 cited researchers in Engineering (2014-2019) in the world. He has received 32 IEEE Prize Paper Awards, the IEEE PELS Distinguished Service Award, in 2009, the EPE-PEMC Council Award, in 2010, the IEEE William E. Newell Power Electronics Award 2014, the Villum Kann Rasmussen Research Award 2014, the Global Energy Prize, in 2019, and the 2020 IEEE Edison Medal.



Ralph Kennel (Senior Member, IEEE) was born in 1955 at Kaiserslautern (Germany). In 1979 he got his diploma degree and in 1984 his Dr.-Ing. (Ph.D.) degree in electrical engineering from the University of Kaiserslautern. From 1983 to 1999 he worked on several positions with Robert BOSCH GmbH (Germany). Until 1997 he was responsible for the development of servo drives. From 1994 to 1999 Dr. Kennel was appointed Visiting Professor at the University of Newcastle-upon-Tyne (England, UK). From

1999 - 2008 he was Professor for Electrical Machines and Drives at Wuppertal University (Germany). Since 2008 he is Professor for Electrical Drive systems and Power Electronics at Technische Universität München (Germany). His main interests today are: Sensorless control of AC drives, predictive control of power electronics and Hardware-in-the-Loop systems.

Dr. Kennel is a Senior Member of IEEE, a Fellow of IEE and a Chartered Engineer in the UK. Within IEEE he is Treasurer of the Germany Section as well as ECCE Global Partnership Chair of the Power Electronics society (PELS).



Marcelo Lobo Heldwein (Senior Member, IEEE) received the B.S. and M.S. degrees in electrical engineering from the Federal University of Santa Catarina (UFSC), Florianopolis, Brazil, in 1997 and 1999, respectively, and his Ph.D. degree from the Swiss Federal Institute of Technology (ETH Zurich), Zurich, Switzerland, in 2007.

He is currently the head of the Chair of High-Power Converter Systems with the Department of Energy and Process Engineering at the Technical University of Munich (TUM), Munich, Germany.

From 1999 to 2003, he worked with industry, including RD activities at the Power Electronics Institute, Brazil and Emerson Network Power, in Brazil and Sweden. He was a Postdoctoral Fellow at the ETH Zurich and at the UFSC from 2007 to 2009. From 2010 to 2022 he was a Professor with the Department of Electronics and Electrical Engineering at the UFSC. Dr. Heldwein is a member of the Brazilian Power Electronic Society (SOBRAEP) and a member of the Advisory Board of PCIM Europe. He is currently the Editor-in-Chief of the Brazilian Power Electronics Journal.

His research interests include Power Electronics, Advanced Power Distribution Technologies and Electromagnetic Compatibility.