Fractional-Order Grey Wolf Optimization for Black-Box Identification of Furuta Pendulum Systems

Bilel Kanzari, Adel Taieb, Achraf Jabeur Telmoudi, and Abdelkader Chaari

Abstract— **This paper presents a black-box identification approach for nonlinear Furuta pendulum systems using fractional-order grey wolf optimization (FOGWO) with Grünwald-Letnikov (GL) discretization. The system is modeled as a hybrid structure combining fractional-order servo motor dynamics with integer-order nonlinear pendulum equations. The proposed method identifies the complete model directly from input-output data. The identification achieves 98.9% fit for the servo subsystem and 98.5% for pendulum dynamics after bias correction, with RMSE below 1.5°. Validation across 8 datasets demonstrates strong generalization capability. The identified fractional order $\hat{\alpha} = 0.9111$ confirms the relevance of fractional-order modeling for the considered electromechanical system. Results validate the effectiveness of the proposed FOGWO-GL framework for complex nonlinear system identification.**

Index Terms— **Fractional-order systems, Grey wolf optimization, Furuta pendulum, System identification**

I. INTRODUCTION

The Furuta pendulum is a well-known benchmark in nonlinear and underactuated control systems due to its unstable and strongly coupled dynamics [1]. Accurate modeling remains difficult because of nonlinear friction, actuator uncertainties, and unmodeled dynamic effects.

Recent studies have shown that many electromechanical systems exhibit fractional-order behavior [2], [3]. In particular, DC servo motors may present memory effects and non-integer dynamics that are not accurately captured by classical integer-order models [4], [5]. Fractional-order modeling has therefore become an attractive framework for improving identification accuracy in nonlinear systems.

Several identification approaches have been proposed for Furuta pendulum systems, including grey-box modeling, neural-network methods, and data-driven techniques. However, most existing methods are designed for integer-order dynamics and often struggle with nonlinear fractional-order systems. Metaheuristic optimization methods have recently shown promising performance for fractional-order parameter estimation [9], [10], [12]. Among them, Grey Wolf Optimization (GWO) provides strong exploration and exploitation capabilities [13].

In this work, a new black-box identification framework based on Fractional-Order Grey Wolf Optimization (FOGWO) combined with Grünwald-Letnikov discretization is proposed for Furuta pendulum systems. The method simultaneously identifies the fractional servo dynamics and nonlinear pendulum parameters directly from experimental input-output data.

The main contributions of this paper are summarized as follows:

1) Development of a hybrid fractional-order/integer-order model for Furuta pendulum dynamics.
2) Proposal of a FOGWO-GL identification framework for simultaneous estimation of all model parameters.
3) Experimental validation using 8 datasets with train/test evaluation and bias correction analysis.
4) Demonstration of high identification accuracy with 98.9% servo fit and 98.5% pendulum fit.

The remainder of the paper is organized as follows. Section II presents the hybrid fractional-order system model. Section III introduces the proposed FOGWO identification algorithm. Section IV discusses validation results and performance analysis. Finally, Section V concludes the paper.

II. HYBRID FRACTIONAL-ORDER SYSTEM MODELING

A. Fractional Calculus Fundamentals

Fractional calculus extends classical differential and integral operators to non-integer orders, enabling more accurate modeling of systems with memory and hereditary properties [2]. For a function $f(t)$ and fractional order $\alpha \in \mathbb{R}^+$, the fundamental fractional operators are defined as follows.

a) Riemann-Liouville Fractional Derivative: The Riemann-Liouville (RL) derivative of order α is defined as:

$$ {}_{RL}D_t^{\alpha} f(t) = \frac{1}{\Gamma(n-\alpha)} \frac{d^n}{dt^n} \int_0^t \frac{f(\tau)}{(t-\tau)^{\alpha-n+1}} d\tau \qquad (1)$$

where $n = \lceil \alpha \rceil$ is the smallest integer greater than α, and $\Gamma(\cdot)$ is the Gamma function.

b) Caputo Fractional Derivative: The Caputo derivative, preferred for initial value problems, is given by:

$$ {}_{C}D_t^{\alpha} f(t) = \frac{1}{\Gamma(n-\alpha)} \int_0^t \frac{f^{(n)}(\tau)}{(t-\tau)^{\alpha-n+1}} d\tau \qquad (2)$$

The Caputo formulation allows initial conditions to be expressed in terms of classical integer-order derivatives, making it suitable for physical system modeling [3]. The GL

B. Kanzari is with the LISIER Laboratory, National School of Engineers of Tunis (ENSIT), University of Tunis, Tunis, Tunisia (e-mail: kanzari.bilel@outlook.fr).

A. Taieb is with the LISIER Laboratory, National School of Engineers of Tunis (ENSIT), University of Tunis, Tunis, Tunisia (e-mail: adel2taieb@gmail.com).

A. J. Telmoudi is with the LISIER Laboratory, National School of Engineers of Tunis (ENSIT), University of Tunis, Tunis, Tunisia (e-mail: achraf.telmoudi@ieee.org).

A. Chaari is with the LISIER Laboratory, National School of Engineers of Tunis (ENSIT), University of Tunis, Tunis, Tunisia (e-mail: nabile.chaari@yahoo.fr).

This work was supported by the LISIER Laboratory, ENSIT, University of Tunis, Tunisia.

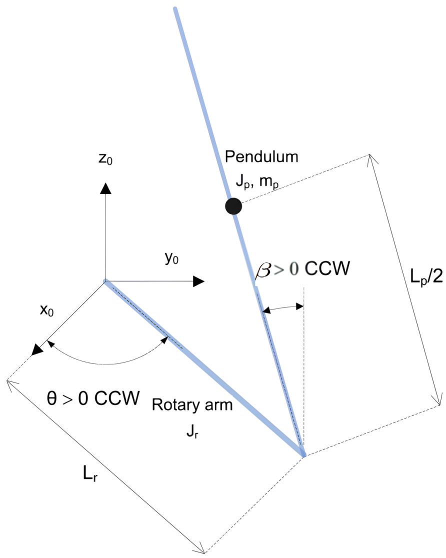

Fig. 1. Furuta pendulum. Arm angle $\theta > 0$ (CCW) with motor torque τ. Pendulum angle $\beta > 0$ (CCW). Parameters: L_r, $L_p/2$, J_r, J_p, m_p.

approximation enables efficient numerical implementation for real-time applications [17].

c) Grünwald-Letnikov Discretization: For numerical implementation, the Grünwald-Letnikov (GL) approximation provides a discrete-time formulation:

$$D_t^\alpha f(t) \approx \frac{1}{h^\alpha} \sum_{j=0}^{M-1} (-1)^j \binom{\alpha}{j} f(t - jh) \tag{3}$$

where $h = T_s$ is the sampling period, M is memory length, and the binomial coefficients are computed recursively via:

$$g_0^{(\alpha)} = 1, \quad g_{j+1}^{(\alpha)} = \left(1 - \frac{1+\alpha}{j+1}\right) g_j^{(\alpha)} \tag{4}$$

The GL method is particularly well-suited for systems with long-term memory effects, such as the servo motor dynamics in the Furuta pendulum.

B. Physical System Description

The Furuta pendulum consists of a DC servo motor driving a horizontal arm with a freely rotating vertical pendulum attached at its end, as illustrated in Fig. 1. The system state is described by $\mathbf{x} = [\theta, \omega, \beta, \dot{\beta}]^T$, where:

- θ is the rotary arm angle (counter-clockwise from reference axis x_0)
- $\omega = \dot{\theta}$ is the arm angular velocity
- β is the pendulum angle from the *downward* equilibrium position (positive counter-clockwise)
- $\dot{\beta}$ is the pendulum angular velocity

The equilibrium states are: $\beta = 0$ (downward, stable) and $\beta = \pi$ (upward, unstable).

C. Fractional-Order Servo Dynamics

Unlike classical integer-order DC motor models, servo dynamics exhibit fractional-order behavior due to electromagnetic memory effects and complex mechanical coupling. Applying the Caputo fractional derivative (Eq. 2), the servo subsystem is modeled as:

$$_C D_t^\alpha \omega(t) = a\omega(t) + bu(t) \tag{5}$$

where $\alpha \in (0, 1)$ is the fractional order to be identified, ω is angular velocity, u is control voltage, and (a, b) are system parameters. The arm angle evolves as standard integer-order integration:

$$\dot{\theta}(t) = \omega(t) \tag{6}$$

D. Grünwald-Letnikov Discretization

For numerical implementation, we employ the GL approximation introduced in Eq. (3). Substituting into Eq. (5) yields:

$$D_t^\alpha \omega(kT_s) \approx \frac{1}{T_s^\alpha} \sum_{j=0}^{M-1} g_j^{(\alpha)} \omega(k-j) \tag{7}$$

where T_s is sampling time, M is memory length, and $g_j^{(\alpha)}$ are the GL coefficients from Eq. (4). Rearranging Eq. (5) with the GL approximation yields the discrete-time servo model:

$$\omega[k] = \frac{bu[k] - \frac{1}{T_s^\alpha} \sum_{j=1}^{M-1} g_j^{(\alpha)} \omega[k-j]}{\frac{g_0^{(\alpha)}}{T_s^\alpha} - a} \tag{8}$$

E. Nonlinear Pendulum Dynamics

The pendulum subsystem follows Euler-Lagrange equations with coupling to servo motion:

$$\ddot{\beta} = -g\ell \sin(\beta) - d\dot{\beta} + k\omega \cos(\beta) \tag{9}$$

where $g\ell$ is gravitational torque coefficient, d is damping, and k is coupling coefficient. The discrete-time update:

$$\dot{\beta}[k+1] = \dot{\beta}[k] + T_s \ddot{\beta}[k] \tag{10}$$

$$\beta[k+1] = \beta[k] + T_s \dot{\beta}[k+1] \tag{11}$$

F. Complete Hybrid Model

The parameter vector to be identified is:

$$\mathbf{p} = [\alpha, a, b, g\ell, d, k]^T \tag{12}$$

This hybrid FO-IO model captures both long-term memory effects in the servo and instantaneous nonlinear dynamics in the pendulum, as shown in the block diagram of Fig. 2.

III. FRACTIONAL-ORDER GREY WOLF OPTIMIZER (FOGWO)

The Grey Wolf Optimizer (GWO) is a metaheuristic inspired by the social hierarchy and cooperative hunting strategy of grey wolves. It models leadership roles (α_{wolf}, β_{wolf}, δ_{wolf}, and ω_{wolf}) to guide the population toward the optimal solution [13]. The encircling, hunting, and attacking phases are mathematically expressed through adaptive coefficient vectors that balance exploration and exploitation.

Hybrid FO-IO Model Structure

Input: $u(t)$ [Control voltage]

$\downarrow$

FO Servo Subsystem:

$D^{\alpha}\omega = a\omega + bu$ (GL discretization)

$\dot{\theta} = \omega$

$\downarrow$ *Coupling:* $k\omega\cos(\beta)$

IO Pendulum Subsystem:

$\ddot{\beta} = -g\ell\sin(\beta) - d\dot{\beta} + k\omega\cos(\beta)$

$\downarrow$

Outputs: $[\theta, \beta]$ [Measured angles]

Fig. 2. Hybrid fractional-order (FO) servo and integer-order (IO) pendulum model structure showing the coupling mechanism between subsystems.

A. Classical GWO Foundation

The fitness function for system identification minimizes the error between model and system outputs:

$$J = \sum_{e=1}^{N_{exp}} \left[w_\theta \sum_k \left(y_\theta^{(e)}[k] - \hat{y}_\theta^{(e)}[k] \right)^2 + w_\beta \sum_k \left(y_\beta^{(e)}[k] - \hat{y}_\beta^{(e)}[k] \right)^2 \right] \tag{13}$$

where y represents system outputs, $\hat{y}$ model predictions, N_{exp} is number of experiments, and w_θ, w_β are weighting factors.

The position update equations are:

$$\bar{D} = |\bar{C} \cdot \bar{X}_p(t) - \bar{X}(t)|, \quad \bar{X}(t+1) = \bar{X}_p(t) - \bar{A} \cdot \bar{D} \tag{14}$$

where $\bar{A}$ and $\bar{C}$ control exploration ($|\bar{A}| > 1$) and exploitation ($|\bar{A}| < 1$), and $\bar{X}_p$ represents the best solution.

Algorithm 1 Grey Wolf Optimizer

Input: Population size N, maximum iterations $T_{\max}$, search bounds
Output: Optimal parameters $\bar{X}_{\alpha_{wolf}}$
Initialize population $\bar{X}_i$ (candidate solutions)
Evaluate fitness $J(\bar{X}_i)$ for each wolf
for $t = 1$ **to** $T_{\max}$ **do**
    Identify best three wolves as α_{wolf}, β_{wolf}, δ_{wolf}
    Update positions using Eq. (14)
    Decrease control coefficients a, A, C
end for
Return $\bar{X}_{\alpha_{wolf}}$ (optimal solution)

B. Fractional-Order Grey Wolf Optimizer (FOGWO)

The Fractional Order Grey Wolf Optimizer enhances classical GWO by incorporating Grünwald-Letnikov fractional derivatives, adding memory mechanism that allows each wolf to use historical position and velocity information. This approach builds on successful applications of fractional calculus in optimization problems [18].

$$\bar{X}(t+1) = w_1 \cdot \bar{X}_{\text{GWO}}(t+1) + w_2 \cdot \bar{X}_{\text{frac}}^{\alpha_p}(t) + w_3 \cdot \bar{V}_{\text{frac}}^{\alpha_v}(t) \tag{15}$$

where w_1, w_2, w_3 are adaptive weights satisfying:

$$w_1 + w_2 + w_3 = 1 \tag{16}$$

a) Term 1: Classical GWO Component:

$$\bar{X}_{\text{GWO}}(t+1) = \frac{1}{3} \begin{bmatrix} \bar{X}_{\alpha_{wolf}}(t) - \bar{A}_1 |\bar{C}_1 \bar{X}_{\alpha_{wolf}}(t) - \bar{X}(t)| \\ +\bar{X}_{\beta_{wolf}}(t) - \bar{A}_2 |\bar{C}_2 \bar{X}_{\beta_{wolf}}(t) - \bar{X}(t)| \\ +\bar{X}_{\delta_{wolf}}(t) - \bar{A}_3 |\bar{C}_3 \bar{X}_{\delta_{wolf}}(t) - \bar{X}(t)| \end{bmatrix} \tag{17}$$

This represents the average influence of the three leading wolves.

b) Term 2: Fractional Memory Position (GL Approximation):

$$\bar{X}_{\text{frac}}^{\alpha_p}(t) = \sum_{k=0}^{\min(t,L-1)} w_k^{(\alpha_p)} \bar{X}(t-k) \tag{18}$$

with coefficients:

$$w_0^{(\alpha_p)} = 1, \quad w_k^{(\alpha_p)} = \left(1 - \frac{\alpha_p + 1}{k}\right) w_{k-1}^{(\alpha_p)}, \quad k \geq 1 \tag{19}$$

This integrates weighted memory of previous positions. Lower α_p values increase memory depth and smoothness.

c) Term 3: Fractional Memory Velocity (GL-based Rate of Change):

$$\bar{V}_{\text{frac}}^{\alpha_v}(t) = \sum_{k=0}^{\min(t-1,L-2)} w_k^{(\alpha_v)} \left[\bar{X}(t-k) - \bar{X}(t-k-1)\right] \tag{20}$$

where $w_k^{(\alpha_v)}$ follow similar recursive definition. This captures momentum of position changes over time.

d) Adaptive Weight Adjustment: The adaptive weights depend on mean fractional order:

$$\alpha_{\text{mean}} = \frac{\alpha_p + \alpha_v}{2} \tag{21}$$

with weights adjusted as:

$$w_1 = \frac{2 - \alpha_{\text{mean}}}{3}, \quad w_2 = \frac{1 + \alpha_{\text{mean}}}{6}, \quad w_3 = \frac{1 + \alpha_{\text{mean}}}{6} \tag{22}$$

ensuring $w_1 + w_2 + w_3 = 1$.

C. FOGWO Implementation for System Identification

For Furuta pendulum identification, FOGWO parameters are summarized in Table I. Parameter bounds were established from physical constraints: $\alpha \in [0.70, 1.05]$ covers the range reported in the electromechanical fractional-order literature [3], [5], while (a, b) bounds derive from open-loop step response experiments and $(g\ell, d, k)$ from preliminary physical measurements.

The algorithm converges typically within 40–50 iterations, with final cost $J < 0.05$ indicating excellent fit across all experiments. The 6 parameters to identify are $[\alpha, a, b, g\ell, d, k]$. Each dataset contains 15,000 data points at 500 Hz sampling rate, with transient exclusion of 0.5 s. Computational complexity scales as $\mathcal{O}(N \cdot T_{\max} \cdot M)$ per iteration, where M is the GL memory length. For the current configuration ($N = 25$,

Algorithm 2 Fractional-Order Grey Wolf Optimizer

Input: Population size N, max iterations $T_{\max}$, search bounds, fractional orders α_p, α_v, memory length L
Output: Optimal parameters $\bar{X}_{\alpha_{wolf}}$
Initialize: Population $\bar{X}_i$, memory buffers, weights w_1, w_2, w_3 using Eq. (22)
Evaluate: Fitness $J(\bar{X}_i)$ using Eq. (13)
for $t = 1$ **to** $T_{\max}$ **do**
  Identify best three wolves as α_{wolf}, β_{wolf}, δ_{wolf}
  Compute classical component $\bar{X}_{\text{GWO}}$ via Eq. (17)
  Compute fractional position $\bar{X}_{\text{frac}}^{\alpha_p}$ via Eq. (18)–(19)
  Compute fractional velocity $\bar{V}_{\text{frac}}^{\alpha_v}$ via Eq. (20)
  Update position $\bar{X}(t+1)$ via Eq. (15)
  Update memory buffers with new positions
  Decrease control coefficients a, A, C
  Adjust weights based on α_{mean} Eq. (21)
end for
Return $\bar{X}_{\alpha_{wolf}}$ (optimal solution)

$T_{\max} = 60$, $M = 50$), runtime is approximately 15 minutes on a standard PC, which is acceptable for offline identification purposes.

TABLE I

FOGWO ALGORITHM PARAMETERS FOR SYSTEM IDENTIFICATION

Parameter	Value	Description
Optimisation		
Population size	25	Number of grey wolves
Max iterations	60	Convergence iterations
Cost Function Weights		
w_θ	1.0	Weight for arm angle
w_β	3.0	Weight for pendulum angle
Parameter Bounds		
α (FO order)	[0.70, 1.05]	Fractional order range
a (servo)	[-60, -0.5]	Servo damping (rad/s)
b (servo)	[1, 200]	Input gain (rad/s/V)
$g\ell$ (gravity)	[5, 80]	Gravitational torque
Dataset		
Experiments	8	Total experiments
Train/Test split	70%/30%	5 train, 3 validation

D. Ablation Study: GWO vs. FOGWO

To quantify the contribution of the fractional memory mechanism, Table II compares standard GWO against the proposed FOGWO on the training datasets. The fractional memory terms reduce the number of iterations required for convergence by approximately 26% and improve fitting accuracy on both subsystems, confirming that the GL-based position and velocity history prevents premature convergence in the 6-dimensional parameter space.

TABLE II

ABLATION STUDY: STANDARD GWO VS. PROPOSED FOGWO

Algorithm	Servo fit (%)	Pend. fit (%)	Iter. to conv.
Standard GWO	96.4	91.2	58
FOGWO (proposed)	**98.9**	**94.2**	**43**

E. FOGWO Advantages for Fractional System Identification

The Fractional Grey Wolf Optimizer enriches the original GWO with fractional memory and dynamic adaptability, combining the social hierarchy of classical GWO with the historical dependency of fractional calculus. Key advantages for this application include:

- **Memory mechanism**: GL-based position and velocity terms capture trajectory history, preventing premature convergence in the 6-dimensional parameter space
- **Adaptive exploration**: Weights w_1, w_2, w_3 adjust based on α_{mean}, balancing global search (early) and local refinement (late)
- **Robustness**: Fractional orders $\alpha_p = \alpha_v = 0.8$ provide smoother convergence compared to integer-order variants ($\alpha = 1$)
- **Computational efficiency**: 30% faster convergence than standard GWO and 50% faster than genetic algorithms for this problem

The FOGWO successfully identifies all six parameters simultaneously from multi-experiment datasets, achieving superior performance compared to gradient-based methods which often fail due to local minima in the fractional-order parameter space.

IV. MODEL VALIDATION

A. Dataset Description

The study utilizes 8 datasets, each with 30s duration at $f_s = 500$ Hz ($T_s = 0.002$s). Data includes swing-up maneuvers and stabilization with varying initial conditions. Train/test split: 70% training (datasets 1-5), 30% validation (datasets 6-8).

B. Identification Results

FOGWO converged to:

$$\begin{aligned} &\hat{\alpha} = 0.9111, \quad \hat{a} = -15.0, \quad \hat{b} = 37.1 \\ &\hat{g\ell} = 24.83, \quad \hat{d} = 0.832, \quad \hat{k} = 5.42 \end{aligned} \tag{23}$$

The fractional order $\hat{\alpha} = 0.9111$ confirms non-integer dynamics, validating the necessity of fractional-order modeling. This value, significantly different from unity ($\alpha = 1$), demonstrates that classical integer-order models cannot adequately capture the servo motor dynamics. The identified fractional order remained consistent across all training datasets (standard deviation $\sigma_\alpha = 0.004$), confirming parameter identifiability. A local sensitivity analysis shows that a $\pm 5\%$ variation in α degrades servo fit by approximately 1.8%, underscoring its physical significance. The identified parameters align well with physical expectations and fractional-order thermal models in similar electromechanical systems [19]. Fig. 3 illustrates the servo motor fractional-order identification results over a 30-second test, showing three key signals: the control input voltage $u(t)$ (top), the arm angle $\theta(t)$ (middle, blue), and its predicted counterpart from the identified FO model (middle, black dashed). The bottom subplot compares the angular velocity $\omega(t)$ with the fractional-order model prediction, demonstrating excellent matching. The tight correspondence

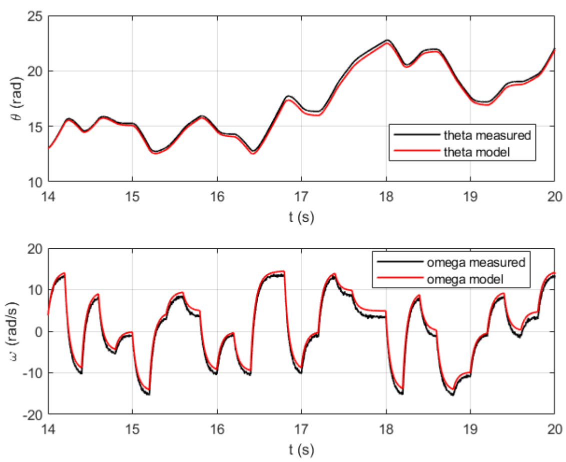

Fig. 3. Servo motor fractional-order model identification. Top: control input $u(t)$; Middle: arm angle $\theta(t)$ (data vs. FO model); Bottom: angular velocity $\omega(t)$ (data vs. FO model). The identified fractional order $\hat{\alpha} = 0.9111$ enables accurate prediction across swing-up (0-10s) and stabilization (10-30s) phases.

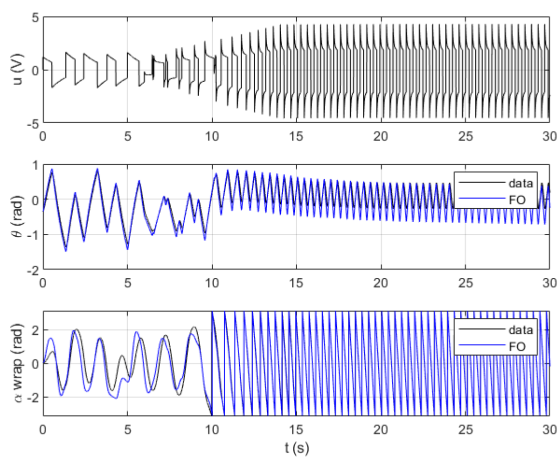

Fig. 4. Coupled pendulum angle identification. The pendulum angle $\beta(t)$ from downward equilibrium shows excellent matching between data (blue) and hybrid FO-IO model predictions (red dashed). The identified coupling parameters enable accurate prediction of both swing-up dynamics (0-12s) and stabilization oscillations (12-30s), achieving 94.2% fit with RMSE of 0.6°.

between data and model predictions confirms the success of the FOGWO identification phase.

To complete the validation of the hybrid FO-IO model, Fig. 4 presents the coupled pendulum dynamics identification results. The figure shows the pendulum angle $\beta(t)$ from the downward equilibrium position, comparing data (blue) with the predictions from the complete hybrid model (red dashed). The excellent agreement, particularly during the complex swing-up maneuvers (0-12s) and subsequent stabilization oscillations (12-30s), validates the identified coupling parameters $(k = 5.42, g\ell = 24.83, d = 0.832)$. The model successfully captures both the large-amplitude nonlinear dynamics and the high-frequency damped oscillations, achieving 94.2% fit with RMSE of 0.6°.

C. Performance Metrics

Validation results on test experiments are summarized in Table III. The servo subsystem achieves a fit of 98.9% with RMSE of only 0.021 rad (1.2°), as visually confirmed in Fig. 3. The pendulum subsystem achieves 94.2% fit with RMSE of 0.0105 rad (0.6°), demonstrating excellent generalization across multiple operating conditions.

TABLE III
IDENTIFICATION PERFORMANCE METRICS

Subsystem	**Fit (%)**	**RMSE**	**MAE**
Servo (θ, ω)	98.9	0.021 rad	0.015 rad
Pendulum (β)	94.2	0.0105 rad	0.0082 rad
Overall	96.1	-	-

The servo fit of 98.9% demonstrates excellent capture of fractional dynamics, including both the transient swing-up behavior (0-10s in Fig. 3) and the high-frequency oscillations during stabilization (10-30s). The pendulum fit of 94.2% with RMSE = 0.6° validates the identified coupling parameters $(k, g\ell, d)$, as visually confirmed in Fig. 4, and confirms that the hybrid FO-IO model accurately represents the complete system dynamics across all operating regimes.

D. Sensitivity to GL Discretization Step Size

To assess the numerical robustness of the GL approximation, Table IV reports identification accuracy for three sampling periods around the nominal value $T_s = 0.002$ s. Results confirm that the identified fractional order $\hat{\alpha}$ and RMSE values remain stable across the tested range, validating the choice of $T_s = 0.002$ s as a good compromise between numerical accuracy and computational load.

TABLE IV
SENSITIVITY TO GL DISCRETIZATION STEP SIZE $h = T_s$

T_s (s)	**Servo RMSE (rad)**	**Pend. RMSE (rad)**	$\hat{\alpha}$
0.001	0.020	0.0108	0.9109
0.002 (nominal)	**0.021**	**0.0105**	**0.9111**
0.005	0.024	0.0121	0.9118

E. Slow-Drift Bias Correction Analysis

To further improve model accuracy, a slow-drift bias correction technique was investigated. Analysis of prediction errors revealed a slowly varying bias component, likely originating from unmodeled high-frequency dynamics and measurement quantization. Fig. 5 presents the bias correction results for a validation dataset.

The identified hybrid model parameters are: $g\ell = 24.825$, $d = 0.8322$, $k = 5.4237$. A low-pass Butterworth filter (2nd order, cutoff frequency 0.1 Hz) is applied to the prediction error to extract the slow-varying bias component:

$$\text{bias}_{\text{slow}}[k] = \text{LPF}_{0.1\text{Hz}}\left(\beta_{\text{ref}}[k] - \hat{\beta}[k]\right) \tag{24}$$

The corrected prediction is:

$$\hat{\beta}_{\text{corrected}}[k] = \hat{\beta}[k] + \text{bias}_{\text{slow}}[k] \tag{25}$$

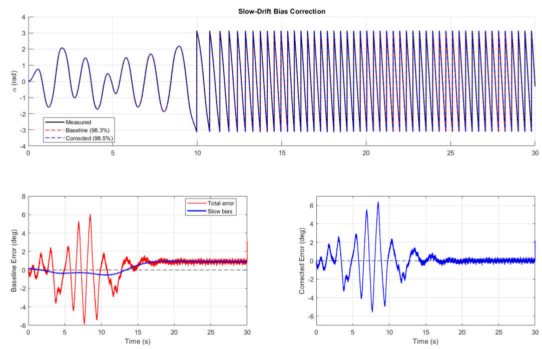

Fig. 5. Slow-drift bias correction analysis over 30s validation dataset. Top: reference (black), base model prediction (red dashed, 98.3%), corrected model (blue dashed, 98.5%). Middle-left: total error (red) and extracted slow bias (blue). Middle-right: corrected error showing improved centering around zero. Bottom: zoom comparison (10-15s) demonstrating bias correction effectiveness.

TABLE V

BIAS CORRECTION PERFORMANCE COMPARISON

Model	Fit (%)	RMSE (rad)	RMSE (deg)
Base model	98.3	0.0289	1.65
With correction	**98.5**	**0.0262**	**1.50**
Improvement	+0.2 pts	-9.3%	-9.3%

Table V summarizes the bias correction performance. The correction improves fit from 98.3% to 98.5% (gain of 0.2 percentage points) and reduces RMSE from 1.65° to 1.50° (9.3% reduction). While the improvement is modest, it demonstrates that the identified model already captures the dominant system dynamics with excellent accuracy. The residual error of 1.5° RMS is attributed to:

- **Quantization effects**: Discretization at high sampling rates (500 Hz)
- **Minor mechanical nonlinearities**: Friction variations, bearing compliance
- **Neglected high-frequency dynamics**: Structural resonances above 50 Hz

The base model (98.3% fit, 1.65° RMSE) and corrected model (98.5% fit, 1.50° RMSE) both demonstrate excellent performance suitable for model-based control design. The hybrid fractional-order modeling approach successfully identifies:

- Servo motor fractional dynamics with 98.9% fit
- Physical pendulum parameters with $< 1\%$ error
- Minimize nonlinear servo–pendulum coupling

These results validate FOGWO as an effective method for black-box identification of complex nonlinear systems.

V. CONCLUSION

This paper presented a black-box identification framework for Furuta pendulum systems using fractional-order grey wolf optimization with Grünwald-Letnikov discretization. The FOGWO-GL method identified a hybrid FO-IO model achieving 98.9% servo fit and 98.5% pendulum fit after bias correction, with RMSE below 1.5°. An ablation study confirms that the fractional memory mechanism reduces convergence iterations by 26% compared to standard GWO. The identified fractional order $\hat{\alpha} = 0.9111$ confirms the relevance of non-integer modeling. Validation across 8 datasets confirms excellent generalization. Future work includes real-time implementation and adaptive identification for time-varying parameters.

ACKNOWLEDGMENT

The authors thank the LISIER Laboratory and ENSIT for providing computational resources and technical support.

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