LIST OF SYMBOLS

s	Sliding surface
R^n	The vector space of vectors of length l with real entities
u_{eq}	Equivalent control
ϕ	State Matrix of discrete system
Γ	Control input matrix of discrete system
C_0	Measurement matrix of the controlled system
D_0	Transmission matrix of the controlled system
c^T	Switching gain matrix
F	Gain Matrix
γ	Reaching Parameter
ϵ	Reaching Law Parameter
τ	Sampling rate
A	State matrix of continuous system
b	Input matrix of continuous system
C	Output matrix of continuous system
u	Control input of the system
q	Gain factor
f_s	Frequency of Carrier wave
f_1	Frequency of reference wave
i_{ds}^*	Direct axis stator current
i_{qs}^*	Quadrature axis stator current
$d^s - q^s$	Stationary reference frame direct and quadrature axes
$d^e - q^e$	Synchronous rotating reference frame direct and quadrature axes
θ_e	Angle of synchronously rotating frame
θ_r	Rotor angle
θ_{sl}	Slip angle