Decoupled Control of Activeand Reactive Power for DFIG

A.Hocine#1, A. Benalia\*2

LACoSERE laboratory, Amar Telidji University

Laghouat, Algeria

1a.hocine@lagh-univ.dz

2a.benalia@lagh-univ.dz

***Abstract*—this paper focuses on the decoupled control of activeand reactive power for doubly fed induction generator (DFIG).The system analysis is based on the mathematic model of doubly fed induction generator (DFIG) intwo-phase synchronous coordinate system, the decoupled control of active and reactive power using the method of stator field oriented vector control. An effective method of independentactive power and reactive power control is proposed. Detailed simulation on MATLAB/SIMULINK verifies the feasibility andvalidity of the proposed control strategy.**

Keywords— **doubly-fedinduction generator(DFIG); active and reactive decoupled control, PI controller.**

1. Introduction

Double-fed induction generators (DFIG) are gaining more attention especially in the field of wind power generation due to rapid development in power electronics. Variable-speed wind-energy conversion system using DFIG, fed with variable frequency rotor voltage allows fixed-frequency electric power generation from the generator stator. One of the main advantages of these generators is that, if rotor current is governed applying stator-flux-oriented vector control—carried out using commercial double-sided PWM inverters [1][2], decoupled control of stator side active and reactive powers results [3][4]. Also, power converter is designed in partial scale, just about 30% of the generator rated power, which makes it attractive from economical point of view. The back to back AC-DC-AC voltage source converter has two main parts: grid side converter (GSC) that rectifies grid voltage and rotor side converter (RSC) which feeds rotor circuit. One of the most common control techniques is decouple [5].

So far, several different control method have been appliedto PWM rectifiers for improving their functionality and usefulness. A well-known method of indirect active andreactive power control is based on current vector orientation with respect to the line voltage vector and is known asvoltage-oriented control (VOC). VOC guarantees high dynamics and static performance via internal current controlloops. However, the final configuration and performance of the VOC system largely depends on the quality of the appliedcurrent control strategy. Another less known method is based on instantaneous direct active and reactive power control, and is called direct power control (DPC) [6].

In thispaper, the principles of the DFIG as well as its mathematic model have been presented. In the model areintroduced the transformations which are later used for the construction of the machine control. This paper introduces thetraditional stator flux-oriented vector control and improves the traditional PI controllerof active and reactive power to improve the dynamic behavior of (DFIG) through tuning of PI parameters.The simulation on the MATLAB/SIMULINK plat was performed,and the validity of this control was verified by the result of simulation[7].

1. MODELING AND VECTOR CONTROL OF (DFIG)

The electrical equations of DFIG in the repository can be written d-q Park [8-9] [10]:

$\left\{\begin{array}{c}v\_{ds}=R\_{s}∙I\_{ds}+\frac{dφ\_{ds}}{dt}-ω\_{s}∙φ\_{qs}\\v\_{qs}=R\_{s}∙I\_{qs}+\frac{dφ\_{qs}}{dt}+ω\_{s}∙φ\_{ds}\\v\_{dr}=R\_{r}∙I\_{dr}+\frac{dφ\_{dr}}{dt}-(ω\_{s}-ω\_{r})∙φ\_{qr}\\v\_{qr}=R\_{r}∙I\_{qr}+\frac{dφ\_{qr}}{dt}+(ω\_{s}-ω\_{r})∙φ\_{dr}\end{array}\right.$(1)

Equation magnetic of flux:

$\left\{\begin{array}{c}φ\_{ds}=L\_{s}∙I\_{ds}+M∙I\_{dr}\\φ\_{qs}=L\_{s}∙I\_{qs}+M∙I\_{qr}\\φ\_{dr}=L\_{r}∙I\_{dr}+M∙I\_{ds}\\φ\_{qr}=L\_{r}∙I\_{qr}+M∙I\_{qs}\end{array}\right.$(2)

Equation of the electromagnetic torque$C\_{em}$:

$C\_{em}=-\frac{3}{2}p\frac{M}{L\_{s}}(φ\_{ds}∙I\_{qr}-φ\_{qs}∙I\_{dr})$(3)

The mechanical equation of motion is defined by:

$$J∙\frac{dω\_{r}}{dt}=C\_{em}-C\_{r}-f∙ω\_{r}$$

The active and reactive power and stator rotor of **(DFIG**)are written as follows:

$\left\{\begin{array}{c}P\_{s}=v\_{ds}∙I\_{ds}+v\_{qs}∙I\_{qs}\\Q\_{s}=v\_{qs}∙I\_{ds}-v\_{ds}∙I\_{qs}\\P\_{r}=v\_{dr}∙I\_{dr}+v\_{qr}∙I\_{qr}\\Q\_{r}=v\_{qr}∙I\_{dr}-v\_{dr}∙I\_{qr}\end{array}\right.$(4)

1. CONTROLLED FLOW GUIDANCE STATOR

To simplify the control of the **(DFIG)**, we approximate the model to that of the DC machine, the latter having the advantage of having a natural coupling between flows and currents. For this, we choose a benchmark two-phase d-q related rotating field and apply the order by orientation of the stator flux. [11] The stator flux $φ\_{s}$ is oriented along the axis, and thus we can write:

$φ\_{ds}=φ\_{s} ;φ\_{qs}=0$(5)

Figure1 shows the principle of control Vector by orientation of the stator flux

$φ\_{s}=φ\_{ds}$

$axe stator$

$axe rotor$

$axe d$

$v\_{s}=v\_{qs}$

$$θ\_{s}$$

$$θ\_{r}$$

$$θ$$

Fig. 1 Principle of the vector control.

The expression of the electromagnetic torque becomes then:

$C\_{em}=-\frac{3}{2}p\frac{M}{L\_{s}}φ\_{ds}∙I\_{qr}$(6)

The expressions of the stator currents may be given as follows:

$\left\{\begin{array}{c}I\_{qs}=-\frac{M}{L\_{s}}∙I\_{qr}\\I\_{ds}=\frac{φ\_{s}}{L\_{s}}-\frac{M}{L\_{s}}∙I\_{dr}\end{array}\right.$(7)

Generally in the field of production of wind power, they are average and high power machinery. Thus one can neglect the stator resistance [8]. This gives us a constant stator flux:

$\left\{\begin{array}{c}v\_{qs}=v\_{s}= φ\_{s}∙ω\_{s}\\v\_{ds}=0 \end{array}\right.$(8)

When the orientation of the stator flux aligned on the direct axis, tension is aligned with the quadrature axis. The active and reactive power of the stator will be reduced to:

$\left\{\begin{array}{c}P\_{s}=v\_{qs}∙I\_{qs}\\Q\_{s}=v\_{qs}∙I\_{ds}\end{array}\right.$(9)

Replace the expression (7) into (8):

$\left\{\begin{array}{c}P\_{s}=-v\_{s}∙\frac{M}{L\_{s}}∙I\_{qr}\\Q\_{s}=-v\_{s}∙\frac{M}{L\_{s}}∙I\_{dr}+\frac{v\_{s}^{2}}{ω\_{s}∙L\_{s}}\end{array}\right.$(10)

The terms rotor voltage based on rotor currents are given as follows: $\begin{array}{c}v\_{dr}=R\_{r}∙I\_{dr}+L\_{r}∙σ∙\frac{dI\_{dr}}{dt} -L\_{r}∙ω\_{r}∙σ∙I\_{qr}\\v\_{qr}=R\_{r}∙I\_{qr}+L\_{r}∙σ∙\frac{dI\_{qr}}{dt}+L\_{r}∙ω\_{r}∙σ∙I\_{dr}+g∙\frac{M∙v\_{s}}{L\_{s}}\end{array}$(11)

With:$σ=1-\frac{M^{2}}{L\_{s}∙L\_{r}},g=\frac{ω\_{s}}{ω\_{r}}$

This model for the control of powersas presented by the block diagram figure 2 [12, 13].

$Q\_{s}$

$v\_{dr\\_ref}$

$v\_{qr\\_ref}$

$$g∙ω\_{s}(L\_{r}-\frac{M^{2}}{L\_{s}})$$

$g∙\frac{M∙v\_{s}}{L\_{s}}$

$$\frac{v\_{s}^{2}}{ω\_{s}∙L\_{s}}$$

$-\frac{M∙v\_{s}}{L\_{s}}$

$-\frac{M∙v\_{s}}{L\_{s}}$

$P\_{s}$

$$g∙ω\_{s}(L\_{r}-\frac{M^{2}}{L\_{s}})$$

Fig.2: Model of MADA for control of powers

1. INDEPENDENT CONTROL OF ACTIVE AND REACTIVE POWER

After developing the model for independent control of the powers of MADA, simply now to reverse his blocks to derive the reference voltages of the inverter from the active and reactive power references [12, 14].

* 1. Direct Control

If we observe the equations (10), we see that the rotor currents are related to the active and reactive power by the term. Moreover, the terms involving derivatives of the rotor currents in the two-phase system (11), go steady. We can write[15]:

$\left\{\begin{array}{c}v\_{dr}=R\_{r}∙I\_{dr} -g∙ω\_{s}(L\_{r}-\frac{M^{2}}{L\_{s}})∙I\_{qr}\\v\_{qr}=R\_{r}∙I\_{qr}+g∙ω\_{s}(L\_{r}-\frac{M^{2}}{L\_{s}})∙I\_{qr} ∙I\_{dr}+g∙\frac{M∙v\_{s}}{L\_{s}}\end{array}\right.$(12)

$$PI$$

$$Q\_{\\_ref}$$

$v\_{dr\\_ref}$

$$PI$$

$v\_{qr\\_ref}$

$$P\_{\\_ref}$$

$g∙\frac{M∙v\_{s}}{L\_{s}}$

$\frac{R\_{r}∙v\_{s}}{ω\_{s}M}$

$$Q\_{\\_mes}$$

$$P\_{\\_mes}$$

Fig.3:Block diagram of the direct control

* 1. indirect control

1) Open loop control

Open loop control is essentially based on the assumption of a stable network voltage and frequency, it is to subjugate either the powers but rather indirectly by the rotor currents do not like using the measured power back on Compare but the rotor currents to d and q axis.

From the expressions of the stator active and reactive power of the system is deduced references rotor currents and direct quadrature according to the relations [15].

$\left\{\begin{array}{c}I\_{qr\\_ref}=\frac{L\_{s}}{M∙v\_{s}}∙P\_{s\\_ref}\\I\_{dr\\_ref}=-\frac{L\_{s}}{M∙v\_{s}}∙Q\_{s\\_ref}+\frac{v\_{s}}{M∙ws}\end{array}\right.$(13)

These currents are used as references in place of references to the active and reactive power, it then leads to the block diagram of Figure 4[15].

$$PI$$

$$Q\_{\\_ref}$$

$v\_{dr\\_ref}$

$$PI$$

$v\_{qr\\_ref}$

$$P\_{\\_ref}$$

$$-\frac{L\_{s}}{M∙v\_{s}}$$

$$g∙ω\_{s}(L\_{r}-\frac{M^{2}}{L\_{s}})$$

$$g∙ω\_{s}(L\_{r}-\frac{M^{2}}{L\_{s}})$$

$I\_{dr}$

$I\_{qr}$

$g∙\frac{M∙v\_{s}}{L\_{s}}$

$$-\frac{L\_{s}}{M∙v\_{s}}$$

$$\frac{v\_{s}^{2}}{ω\_{s}∙L\_{s}}$$

Fig.4:Block diagram of indirect control open loop.

This configuration remains as the reliable electrical network remains stable voltage and frequency. Grid instability will therefore cause an error on the follow instructions for active and reactive power.

2) Control closed loop

Powers to regulate optimally, we will set up two control loops on each axis with proportional integral controller for each, a loop on the power and the other on the current corresponding while compensating the terms of disturbance and couplings appearing on the block diagram modelMADA. We obtain the control structure shown in Figure 5[15].

$$PI$$

$$PI$$

$$Q\_{\\_ref}$$

$v\_{dr\\_ref}$

$$PI$$

$$PI$$

$v\_{qr\\_ref}$

$$P\_{\\_ref}$$

$$Q\_{\\_mes}$$

$$P\_{\\_mes}$$

$$-\frac{L\_{s}}{M∙v\_{s}}$$

$$g∙ω\_{s}(L\_{r}-\frac{M^{2}}{L\_{s}})$$

$$g∙ω\_{s}(L\_{r}-\frac{M^{2}}{L\_{s}})$$

$I\_{dr}$

$I\_{qr}$

$g∙\frac{M∙v\_{s}}{L\_{s}}$

$$-\frac{L\_{s}}{M∙v\_{s}}$$

$$\frac{v\_{s}^{2}}{ω\_{s}∙L\_{s}}$$

Fig.5:Block diagram of indirect control closed loop.

1. SIMULATION AND RESULTS

 Simulation results show the figure below, allows us to present performance driving the DFIG powered by a two-level inverter controlled by the strategy triangulo-sinusoidal, with a vacuum and then start with the application of active power P = -3000W between t = 1 s and t = 3s, and reactive power between t = t = 2s and 4s for two carrier frequency $f\_{p}=1000 Hz$.

Fig (9) and (10) the three-phase voltage applied to the stator and that applied to the rotor of the DFIG [15].





Fig.6:active and reactive stator powers online ordering





Fig.7:Powers and reactive stator indirect command without

power loop





Fig.8:Powers and reactive stator indirect control withpower loop



Fig.9:stator voltage (V).



Fig. 10: rotor voltage (V).

The above simulation results show the effectiveness of the control in powers ofMADA for the three methods studied. Indeed, active power levels are monitored by the generator mostly indirect closed loop control (without overshoot or disturbance) (Figure 8), and active and reactive power following the reference (Figure (6) (7), (8)). However, we note the oscillations at the instants of application of power levels due to coupling between the two axes of the machine and power fluctuations for the open-loop method, particularly the active and reactive power (Figure 4) due in the absence of a control loop on the power to this method, these oscillations and these power fluctuations are compensated for in the closed loop methods (direct and indirect closed loop) (Figure 6, 8) [15].

1. CONCLUSION

This paper has allowed us to establish the synthesis of vector control for active and reactive power of the stator doubly fed induction machine. Three control modes have been detailed using a proportional integral regulator. Direct control, based on the assumption of a perfect decoupling between the two axes and quadrature Direct and indirect control, with and without power loop, which hold account the coupling between the axes and uses terms for compensation correct.Although direct command we gave satisfactory results with a simplicity of implementation, indirect control closed loop on power, certainly more complex, allowed us to have a more efficient and robust system. The presence of a current loop in the indirect control offers an advantage, relative to direct control, allowing the limitation of the rotor currents to protect the machine and also the ability to overlay references of harmonic currents for the possible application of MADA into an active filter.

1. APPENDIX

TABLE I
DATA OF DFIG

|  |  |
| --- | --- |
| Rated Power | 4 kW |
| Stator Voltage | 311.127 V |
| Stator Frequency | 50 Hz |
| Stator Resistance, Rs | 1.2Ω |
| Rotor Resistance, Rr | 1.8Ω |
| Stator Inductance, Ls | 0.1554mH |
| Rotor Inductance, Lr | 0.1568mH |
| Magnetizing Inductance, Lm | 0.15mH |
| J | 0.2 |
| Number of Poles | 2 |

NOMENCLATURE

$v\_{s},v\_{r}$Stator, rotor voltage vectors.

$I\_{s},I\_{r}$Stator, rotor current vectors.

$ω\_{s},ω\_{r}$Stator, rotor angular frequency.

$P\_{s},Q\_{s}$Stator active and reactive power.

$M$Mutual inductance.

$L\_{s},L\_{r}$Stator, rotor self-inductance.

$R\_{s},R\_{r}$Stator, rotor resistance.

$p$Machine pole pairs.

$s,r$ Stator, rotor.

1. References
2. P. Vas, Vector control of AC Machines, Clarendon Press Oxford 1990.
3. Bimal K. Bose, Modern Power Electronics and AC Drives,India, Pearson Education, 2002.
4. A. Tapia, G. Tapia, J. XabierOstolaza, and Jose R. Saenz, “Modeling and Control of a Wind Turbine Driven Doubly FedInduction Generator,” IEEE Transactions on Energyconversion, pp.194-204, 2003.
5. H. Karimi-Davijani, A. Sheikholeslami, H. Livani and M. Karimi-Davijani, “Fuzzy Logic Control of Doubly FedInduction Generator Wind Turbine,” World Applied Sciences Journal, vol. 6, no. 4, pp. 499-508, 2009.
6. J.P. Mishra, DebirupaHore, andAsadur Rahman, Fuzzy logic based improved Active andReactivePower control operation of DFIG for Wind Power Generation,8th International Conference on Power Electronics - ECCE Asia, the ShillaJeju, Korea,May 30-June 3, 2011.
7. H.H.Lee, P.Q.Dzung, Le.M.Phuong, Le.D.Khoa, N.H.Nhan, "A New Fuzzy Logic Approach for Control Systemof Wind Turbine with Doubly Fed Induction Generator”, IEEE IFOST Proceedings, 2010.
8. J.Guo, X.Cai ,Y.Gong, “Decoupled Control of Active and ReactivePower for a Gridconnected Doubly-fed Induction Generator", DRPT2008 Nanjing China, 6-9 April 2008.
9. A. Boyette, ‘‘Control and monitoring of a double-fed asynchronous generator with storage system for wind power generation’', PhD Thesis, Nancy (France) 2006.
10. MouradLoucif, AbdelmadjidBoumediene and AbdelkaderMechernene “Backstepping Control of Double Fed Induction Generator Driven by Wind Turbine’', Proceedings of the 3rd International Conference on Systems and Control, Algiers, Algeria, October 29-31, 2013.
11. MouradLoucif, AbdelmadjidBoumediène and AbdelkaderMechernene, ‘‘The Association of Nonlinear Backstepping approach to setting mode by Slippery When applied to asynchronous Dual Power Generator Integrated into a Wind Power System '', Proceedings of the 1st Day Study in Automatic and his Applications (1AA14) , Algiers, Laghouat , April 24, 2014.
12. F. Blaschke, ‘‘the principle of field oriented as applied to the new transvector closed-loop control system for rotating-field machine’'. Siemens Review XXXIX, vol.5, no.4, 1972, pp.217- 220.
13. A. BOYETTE, "Control and Monitoring of a double-fedasynchronous generatorwith storage system for wind generation, "PhD thesis in electrical engineering,University Henri Poincare, Nancy I, December 11, 2006.
14. F. POITIERS, T. BOUAOUICHE, M.MACHMOUM « Advanced control of a doubly-fed induction generator for wind energy conversion Electric », Power Systems Research 79 (2009)1085–1096.
15. H. HOLTTINEN,”The impact of large scale wind power production on the Nordic electricalsystem ", VTT Processes, Finland, in December 2004.
16. T. Abderrahim, ‘Study and control of a variable speed wind turbine has built the MV network '', Magister memory, pp 432012.