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Dual Mode Two-Layer Fuzzy Logic Based Load-Frequency Controller for a Two-Area Interconnected Power System with Super Capacitor Energy Storage Units using Control Performance Standards Criterion

Adhimoorthy Venkatachalam [1], Chidambaram Ilangi Akilandam [2]

Abstract*— The Load Frequency Control (LFC) is of great importance in power system operation and control for providing sufficient and reliable electric power with good quality. The simple Proportional- Integral (PI) controllers are still popular in power industry for to enhance power system stability. However, PI controllers are not fully reliable always as it is incapable of obtaining good dynamic performance for a wide range of operating conditions. The proportional plus integral control does not eliminate the conflict between the static and dynamic accuracy. This conflict may be resolved by employing the principle of Dual Mode control. The Dual Mode controller operates by switching between proportional controller mode and Integral controller mode depending on the magnitude of the Area Control Error (ACE). In this paper the Dual Mode Two Layered Fuzzy Logic controller is adopted and each mode consists of two layer fuzzy logic controllers. The first layer is called pre compensator, which is used to generate and update the reference value of Area Control Error (ACE). The second layer called feedback fuzzy logic controllers namely Proportional (P) like fuzzy logic controller, or Integral (I) like fuzzy logic controller. In addition to leveling load, the Super Capacitor Energy Storage Unit (SCES) is advantageous for the secondary control of the power system and maintains the power quality with the distributed power resource. When an AC power system is subjected to load disturbances, considerable frequency oscillations may result to system instability. So as to ensure the system stability, the power modulation control offered by SCES is enhanced to suppress the peak value of the transient frequency deviation. Simulation results show that the proposed Dual Mode two layered fuzzy logic controller is not only effective in damping out the frequency oscillations, but also capable of alleviating the transient frequency swing caused by large load disturbance. Moreover, the output results obtained proves that the proposed Dual Mode two layered fuzzy load frequency controller provides very good transient and steady state response compared to and Dual Mode PI controllers. Compliance with North American Electric Reliability Council (NERC) standards for LFC has also been established in this work.

***Index Terms*— Load-Frequency Control, Area Control Error, Integral Squared Error criterion, Dual Mode Contr ol, Control Performance Standards, Two Layered Fuzzy Logic Controller, Super Capacitor Energy Storage Unit.**

I. INTRODUCTION

Large scale Power Systems are normally composed of control areas or regions representing coherent group of generators. Power System operation has to ensure whether adequate power is being delivered to the consumer's reliably and economically or not. The analysis and design of Automatic Generation Control (AGC) system of individual generator eventually controlling large interconnections between different control areas plays a vital role in automation of power system. The primary objectives of AGC are to regulate frequency to the specified nominal value and to maintain the interchange power between control areas at the scheduled values by adjusting the output of the selected generators. This function is commonly defined as Load Frequency Control (LFC). Load Frequency Control (LFC) is a very important issue in power system due to the increasing load demand and results to more complicated environment which requires adequate and efficient control. Therefore the objective of LFC of a power system is to maintain the frequency of each area and tie-line power flow (among the interconnected system) within specified tolerance by adjusting the new outputs of LFC generators so as to accommodate the fluctuating load demand. A number of control schemes have been employed for the design of load frequency controllers [1] in order to achieve better dynamic performance. Among the various types of load frequency controllers the most widely used conventional schemes are based on the tie-line biased control and flat frequency control. With the conventional design approach using proportional plus integral controllers results in relatively large over shoots in transient frequency deviations [2]. Further, the settling time of the system frequency deviations is also relatively long. It is well known that, if the control law employs integral control, the system has no steady state error. However, it increases the order of the system by one. Therefore, the response with the integral control is slow during the transient period. In the absence of integral control, the gain of the closed loop system can be increased significantly thereby improving the transient response [3]. The proportional plus integral control does not eliminate between the static and dynamic accuracy. This conflict may be resolved by employing the dual mode control [4, 5].

Generally most of the conventional control schemes have been successful to some extent only [6]. This suggests the necessity of more advanced control strategies that has be incorporated for a better control. In this aspect a better sophisticated intelligent controllers [9-12] be adopted for a better power quality by replacing the conventional controllers because of their ability in ensuring fast and good dynamic response for the load frequency control problems. Fuzzy logic controllers have received considerable interest in recent years. Fuzzy based methods are found to be very useful in the places where the solution to the mathematical formulations is complicated. Moreover, fuzzy logic controller often yields superior results to conventional control approaches. The fuzzy logic based intelligent controllers are designed to facilitate the operation smooth and less oscillatory when system is subjected to load disturbances but the design procedures require more skill. The Artificial Bee Colony (ABC) algorithm, a new swarm intelligent algorithm, was proposed by Karabog [6] is simple in concept, easy to implement and has fewer control parameters. ABC algorithm has applied successfully to unconstrained numerical optimization problems [7]. The extended version of the ABC algorithm is also developed for solving optimization problems in 2007 [8]. ABC algorithms are highly robust yet remarkably simple to implement. Thus, it is quite pertinent to apply the ABC, with more new modifications, to achieve better optimization and handle the load-frequency problems more efficiently. In this study, an ABC algorithm is used to optimizing the proportional and integral controller gains for load frequency control of a two area thermal power system.

The conventional load-frequency controller may no longer be able to attenuate the large frequency oscillation due to the slow response of the governor even though a more sophisticated controller is adopted. A fast-acting energy storage system in addition to the kinetic energy of the generator rotors provides adequate control to damp out the frequency oscillations. The problems like low discharge rate, increased time required for power flow reversal and maintenance requirements have led to the evolution of Super Capacitor Energy Storage (SCES) or Ultra Capacitor Energy Storage
(UCES) devices for their applications also load frequency stabilizers. Super capacitors are electrochemical type capacitor which offer large capacitances in the order of thousands of farads at a low voltage rating of about 2.5V [13] and are used to store electrical energy during surplus generation and deliver high power within a short duration of time especially during the peak-load demand period [14, 15]. The energy density of Super Capacitor (SC) is 100 times larger than the conventional electrolytic capacitor and their power density is 10 times larger than the lead-acid battery. Ultra capacitors possess a number of attractive properties like fast charge-discharge capability, longer life, no-maintenance and environmental friendliness. The effective specific energy for a prescribed load can be satisfied using various SC bank configurations. The SCES will, in addition to load leveling, a function conventionally assigned to them, have a wide range of applications such as power quality maintenance for decentralized power supplies. The SCES are excellent for short-time overload output and the response characteristics possessed in the particular. The effect of generation control and the absorption of power fluctuation needed for power quality maintenance are expected. However, it will be difficult to locate the placement of SCES alone in every possible area in the interconnected system due to the economical reasons. In this paper SCES unit is located in area 1 of the two-area interconnected reheat thermal power system

In this paper, the control scheme consists of dual mode two layers viz fuzzy pre-compensator and fuzzy like P and Fuzzy like I controller. The purpose of the fuzzy pre-compensator is to modify the command signals to compensate for the overshoots and improve the steady state error. Fuzzy rules from the overall fuzzy rule vectors are used at the first layer, linear combination of independent fuzzy rules are used at the second layer. The two layer fuzzy system has less number of fuzzy rules as compared with the fuzzy logic system [16]. The proposed dual mode two layered fuzzy logic controllers give better simulation results which is compared with the simulation results obtained using the dual mode PI controllers. Thus the Dual mode two layered fuzzy PI controller enhances an efficient way of coping even with imperfect information, offers flexibility in decision making processes.

The main function of LFC is to regulate a signal called Area Control Error (ACE), which accounts for error in the frequency as well as the errors in the interchange power with neighboring areas. Conventional LFC uses a feedback signal that is either based on the Integral of ACE or is based on ACE and it’s Integral. These feedback signals are used to maneuver the turbine governor set points of the generators so that the generated power follows the load fluctuations. However, continuously tracking load fluctuations definitely causes wear and tear on governor’s equipment, shortens their lifetime, and thus requires replacing them, which can be very costly. Control Performance Criteria (CPC) has been formerly used to evaluate AGC performance. The Control Performance Standard (CPS) is specifically designed to comply with the performance standards imposed by the North American Electric Reliability Council (NERC) for equitable operation of an interconnected system. CPS1 and CPS2 are derived from rigorous theoretical basis. CPS1 is a measurement to asses the performance of frequency control in each area. CPS2 is designed to restrain the ACE 10-minute average value and in doing so provides a means to limit excessive unscheduled power flows that could results from large ACEs. In this paper a novel load frequency controller is presented. It is manipulated by a Fuzzy logic system whose rules are designed to reduce wear and tear of the equipment and assure its control performance is in compliance with NERC's control performance standards, CPS1 and CPS2 [18,19]. Considering the power system load frequency control, this paper establishes a fuzzy logic controller to predict the future frequency of the target object, thus forecasting the optimized controller is designed, which follows the CPS performance standards through the fuzzy logic rules [20]. This control structure is a decentralized, integral type controller whose parameter is automatically tuned using Bacterial Foraging Optimization algorithm. The control parameter is reduced to diminish high frequency movement of the speed governor's equipment when the control area has high compliance with NERC's standards. When the compliance is low, the control parameter is raised to the normal value [21]. This paper adopts CPS1 and CPS2 as input to the fuzzy logic controller and output gain of fuzzy controller adjust control parameter gains depending up on NERC's compliance. The simulation results show that the dynamic performance of the system with SCES unit had improved a lot with the proposed controller.

II. PROBLEM FORMULATION

The state variable equation of the minimum realization model of ' N ' area interconnected power system may be expressed as [19].

$$\dot{\mathrm{x}} = \mathrm{Ax} + \mathrm{B}u + \Gamma d$$

(1) $y = \mathrm{Cx}$

(2)

Where $\mathrm{x} = [\mathrm{x}_1^{\mathrm{T}}, \Delta \mathrm{p}_{\mathrm{ei}} \ldots \mathrm{x}_{(\mathrm{N}-1)}^{\mathrm{T}}, \Delta \mathrm{p}_{\mathrm{e(N-1)}} \ldots \mathrm{x}_{\mathrm{N}}^{\mathrm{T}}]^{\mathrm{T}}$,

n- State vector,

$$n = \sum_{i=1}^{N} n_i + (N-1)$$

$u = [u_1, \ldots u_N]^T = [\Delta P_{C1} \ldots P_{CN}]^T$ N- Control input vector $d = [d_1, \ldots d_N]^T = [\Delta P_{D1} \ldots P_{DN}]^T$ N - Disturbance input vector, $\mathrm{y} = [y_1 \ldots y_N]^T$, $2N$ - Measurable output vector

Where A is system matrix, B is the input distribution matrix, Γ is the disturbance distribution matrix, C is the control output distribution matrix, x is the state vector, u is the control vector and d is the disturbance vector consisting of load changes

III. PROPOSED DUAL MODE CONTROL SCHEME

The fixed gain controllers are designed at nominal operating conditions and fail to provide best control performance over a wide range of operating conditions. The well designed integral controller can bring the steady state error to zero but the speed of the response of the system becomes slow resulting high over/ under shoot and settling time. The over/under shoot is reduced and speed of the response improves by using only proportional controller. It is obvious that the presence of the proportional controller is highly required at transient to make system response faster thus reducing the over/under shoot. But incorporating the proportional controller alone fails to bring the steady state error to zero. So there is need to have both proportional and integral controllers. In view of the above context, it seems appropriate selection of the proportional or integral controller be adopted to ensure a better transient and steady state response. When the error is large one control strategy might be chosen and for sufficiently small error another control strategy might be chosen.

The control law employed during the transient period, is switched between Eqn (3) and Eqn (4) depending on the magnitude of error signal i.e., ACE (t). For | ACE (t)| > ε the output of the controller

$$\Delta P_c(t) = -K_p . ACE(t) \tag{3}$$

Where $\Delta P_c(t)$ output signal of the controller and E is is constant indicating the specified limit of error signal.

$$\Delta P_c(t) = -K_i . \int ACE(t)\, dt \tag{4}$$

Based upon the above mentioned facts, the dual mode concept is introduced here in the following way. The proportional controller will act during the transient period when the error (ACE) is sufficiently larger, whereas the integral controller would be the better option when the error is small. The proposed control dual mode control scheme for two area interconnected reheat thermal power system is shown in Fig 1. For the proposed control scheme, the control law is taken as follows

$$\Delta P_{c1}(t) = -K_{p1}\,(ACE(t)), \quad for|ACE_1| > \varepsilon_1$$

(5)

$$\Delta P_{c1}(t) = -K_{i1} \int (ACE(t)\, dt), \quad for|ACE_1| \le \varepsilon_1$$

(6)

$$\Delta P_{c2}(t) = -K_{p2}\,(ACE(t)), \quad for|ACE_2| > \varepsilon_2$$

(7)

$$\Delta P_{c2}(t) = -K_{i2} \int (ACE(t)\, dt), \quad for|ACE_2| \le \varepsilon_2$$

(8)

When the error signal remains within the specified limit, i.e., | ACE (t)| < ε , the system will operate in the integral control strategy.

IV. DESIGN OF FUZZY LOGIC SYSTEM

Fuzzy logic systems belong to the category of computational intelligence technique. One advantage of the fuzzy logic over the other forms of knowledge-based controllers lies in the interpolative nature of the fuzzy control rules. The overlapping fuzzy antecedents to the control rules provide transitions between the control actions of different rules. Because of this interpolative quality, fuzzy controllers usually require far fewer rules than other knowledge-based controllers [10, 11]. A fuzzy system knowledge base consists of a fuzzy if then rules and membership functions characterizing the fuzzy sets. The block diagram and architecture of fuzzy logic controller is shown in Fig 2. Membership Function (MF) specifies the degree to which a given input belongs to a set. Here triangular membership function have been used to explore best dynamic responses namely Negative Big (NB), Negative Small (NS), ZEro (ZE), Positive Small (PS), Positive Big (PB). Fuzzy rules are conditional statement that specifies the relationship among fuzzy variables. These rules help to describe the control action in quantitative terms and have been obtained by examining the output response to the corresponding inputs to the fuzzy controllers. Defuzzification, to obtain crisp value of FLC output is done by centre of area method. The fuzzy rules are designed as shown in Table I.

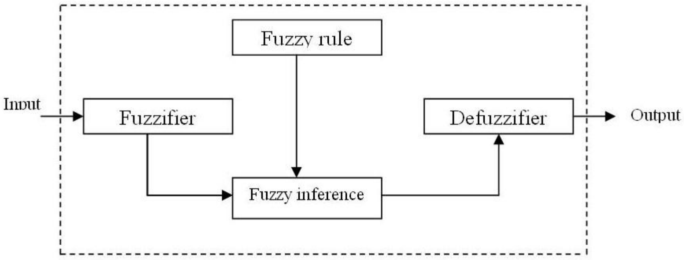


Fig. 2 Block diagram of Fuzzy Logic Controller

TABLE.I FUZZY LOGIC RULES FOR LFC

ACE ACE	NB	NS	Z	PS	PB
NB	NB	NB	NS	NS	ZE
NS	NB	NB	NS	ZE	ZE
Z	NS	NS	ZE	PS	PS
PS	ZE	NS	PS	PS	PB
PB	ZE	ZE	PS	PB	PB

A. Two Layered Fuzzy Logic Controller

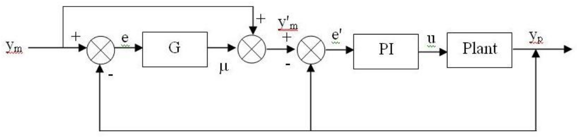


Fig 3. Basic structure of fuzzy pre-compensated PI controller

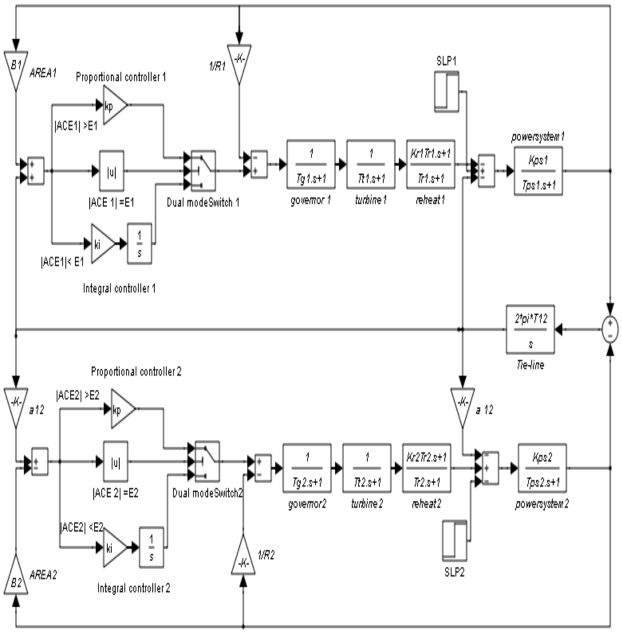


Fig.1 Linearized model of Dual mode PI Controller based two- area interconnected reheat thermal Power system

The aim of introducing two layered fuzzy logic controller [16] is to eliminate the steady state error and improve the performance of the output response of the system under study. The proposed control scheme is shown in Fig. 3. The controller consists of two "layers": a fuzzy pre-compensator and a usual fuzzy PI controller. The error e(k) and change of error Δe(k) are the inputs to the pre compensator. The output of the pre-compensator is μ(k). The PI Controller is usually implemented as follows:

$$u(k) = k_p e(k) + TK_i \sum_{n=0}^{k} e(n) \qquad (9)$$

Where $e(k) = y(k) - y_r(k)$ and Δ e(K) = e (k) - e(k-1) The controller output, process output and the set point are denoted as u, y and y_r respectively. Experience-based tuning method especially Ziegler-Nichols method requires a close attention since the process has to be operated near instability to measure the ultimate gain and period. This tuning technique may fail to tune the process with relatively large dead time. In order to improve the performance of PI tuning a number of attempts have been made which can be categorized into two groups: Set point modification and gain modification. The set point modification introduces new error terms

$$e_p = y_r(k) F_p(e, \Delta e) - y(k) \qquad (10)$$

$$e_i = y_r(k) F_i(e, \Delta e) - y(k) \qquad (11)$$

The corresponding control law is given by, Where F_p , F_i are non linear functions of e and Δe.

$$u(k) = k_p e_p(k) + TK_i \sum_{n=0}^{k} e_i(n) \qquad (12)$$

As a special case, the set point is being modified only in proportional terms which implies F_p = β; F_i =1 set point weight [17]

$$\therefore \mathrm{U(k)} = K_p\{\beta y_r(k) - y(k)\} + TK_i \sum_{n=0}^{k} e(n) \qquad (13)$$

$$U(k) = K_p e'(k) + TK_i \sum_{n=0}^{k} e'(n)$$

The pre-compensation scheme [17] is easy to implement in practice, since the existing PI control can be used without modification in conjunction with the fuzzy pre-compensator as shown in Fig 3. The procedure of rule generation consists of two parts (i) learning of initial rules which determines the linguistic values of the consequent variables. (ii) Fine tuning adjusts the membership function of the rules obtained by the previous step. The structure of the pre-compensation rule is written as If e is L_e, and Δe is LΔe then C is L_c where L_e, ΔL_e and L_c are linguistic values of e, Δe, C respectively. Each fuzzy variable is assumed to take 5 linguistic values Le, LΔe, or L_c = {NB, NS, ZE, PS, and PB} this leads to fuzzy rules, if the rule base is complete.

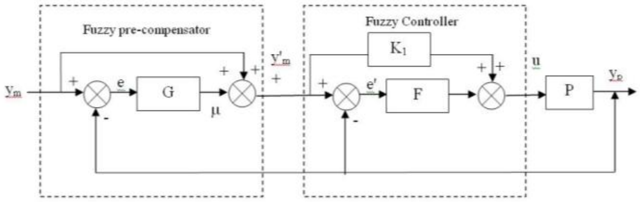


Fig 4. Proposed two layered fuzzy logic controller

The dynamics of overall system is than described by following equations

$$e(k) = ym(k) - yp(k) \qquad (14)$$

$$\Delta e(k) = e(k) - e(k-1) \qquad (15)$$

$$\mu(k) = G[e(k), \Delta e(k)] \qquad (16)$$

Where μ(k) is a compensating term which is generated using a fuzzy logic scheme

$$y'_m(k) = y_m(k) + \mu(k) \qquad (17)$$

$$e'(k) = y'_m(k) + y_p(k) \qquad (18)$$

$$\Delta e'(k) = e'(k) - e'(k-1) \qquad (19)$$

The proposed two layered FLC compensate these defects and gives fast responses with less overshoot and/or undershoot. Moreover the steady state error reduces to zero. The first layer fuzzy pre-compensator is used to update and modify the reference value of the output signals to damp out the oscillations. The fuzzy states of the input and output all are chosen to be equal in number and use the same linguistic descriptors as N =Negative, Z = Zero, P = Positive to design the new fuzzy rules. The fuzzy logic rules for pre-compensator are presented in Table-II.

TABLE II. FUZZY LOGIC RULES FOR PRECOMPENSATOR

ACE $\dot{ACE}$	N	Z	P
N	N	N	N
Z	Z	Z	Z
P	Z	P	P

The second layer which is known as feedback fuzzy logic control reduces the steady state error to zero. The output of the FLC is given by

$$u(k) = K_1 y'_m(k) + F[e'(k), \Delta e'(k)] \qquad (20)$$

V.APPLICATION OF THE MATHEMATICAL MODEL OF SUPER CAPACITOR ENERGY STORAGE UNIT FOR A TWO- AREA THERMAL REHEAT INTERCONNECTED POWER SYSTEM

A. Mathematical Model of SCES unit

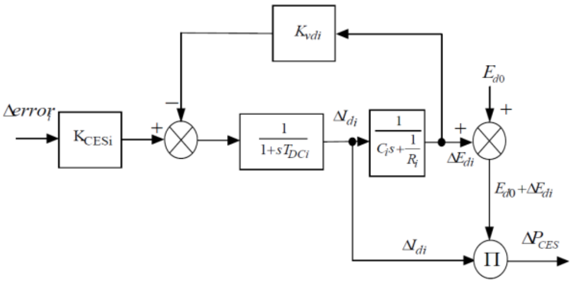


Fig.5 block diagram with capacitor voltage deviation feedback

The block diagram representation of SCES unit is shown in fig. 5. Either frequency deviation or Area Control Error (ACE) can be used as the control signal to the CES unit ($\Delta error_i$ = Δf_i or ACE_i). E_{di} is then continuously controlled in accordance with this control signal. For the ith area, if the frequency deviation Δf_i (i.e., $\Delta error_i$ = Δf_i). of the power system is used as the control signal to CES, then the deviation in the current, ΔI_{di} is given by [15].

$$\Delta_{di} = \left\lfloor \frac{1}{1+sT_{DCi}} \right\rfloor \left[K_{CESi} * \Delta F_i - K_{vdi} * \Delta E_{di} \right] \qquad (21)$$

If the tie-line power flow deviations can be sensed, then the Area Control Error (ACE) can also be fed to the CES as the control signal (i.e., $\Delta error_i$ = ACE_i). Being a function of tie-line power deviations, ACE as the control signal to CES, will further improve the tie-power oscillations. Thus, ACE of the two areas are given by

$$ACE_i \;=\; B_i\ \Delta F_i + \Delta P_{tie-i\ j} \quad ; \mathrm{i, j = 1,2} \qquad (22)$$

Where $\Delta P_{tie\ ij}$ is the change in tie-line power flow out of area i to j. Thus, if ACE_i is the control signal to the CES, then the deviation in the current ΔI_{di} would be

$$\Delta_{di} = \left\lfloor \tfrac{1}{1+sT_{DCi}} \right\rfloor \left[K_{CESi} * \Delta ACE_i - K_{vdi} * \Delta E_{di} \right]; \text{i j} = 1,2 \qquad (23)$$

The control actions of Super Capacitor Energy Storage units are found to be superior to the action of the governor system in terms of the response speed against, the frequency fluctuations [13]. The SCES units are tuned to suppress the peak value of frequency deviations quickly against the sudden load change, subsequently the governor system are actuated for compensating the steady state error of the frequency deviations. Fig.6 shows the linearized reduction model for the control design of two area interconnected power system with SCES units. The SCES unit is modeled as an active power source to area 1 with a time constant T_{SCES}, and gain constant K_{SCES}. Assuming the time constants T_{SCES} is regarded as 0 sec for the control design [15]. Then the state equation of the system represented by Fig 6 becomes.

$$\begin{bmatrix} \Delta\dot{F}_1 \\ \Delta\dot{P}_{T12} \\ \Delta\dot{F}_2 \end{bmatrix} = \begin{bmatrix} -\dfrac{1}{T_{p1}} & -\dfrac{k_{p1}}{T_{p1}} & 0 \\ 2\pi T_{12} & 0 & -2\pi T_{12} \\ 0 & \dfrac{a_{12}\,k_{p2}}{T_{p2}} & -\dfrac{1}{T_{p2}} \end{bmatrix} \begin{bmatrix} \Delta F_1 \\ \Delta P_{T12} \\ \Delta F_2 \end{bmatrix} + \begin{bmatrix} \dfrac{k_{p1}}{T_{p1}} \\ 0 \\ 0 \end{bmatrix} \begin{bmatrix} \Delta P_{SCES} \end{bmatrix} \qquad (24)\ (24)$$

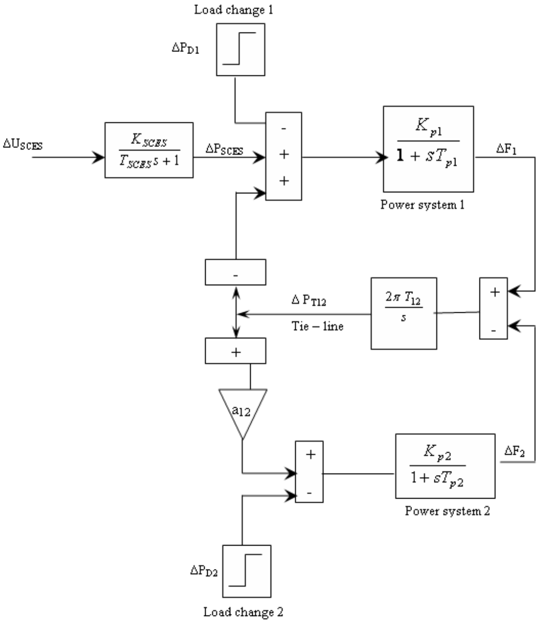


Fig. 6 Linearized reduction model for the control design

B. Control design of Super Capacitor Energy Storage unit

The design process starts from the reduction of two area system into one area which represents the Inertia centre mode of the overall system. The controller of SCES is designed for the equivalent one area system to reduce the frequency deviation of inertia centre. The equivalent system is derived by assuming the synchronizing coefficient T_{12} to be large. From the state equation of $\Delta\dot{P}_{T12}$ in Eq (24)

$$\frac{\Delta\dot{P}_{T12}}{2\pi T_{12}} = \Delta F_1 - \Delta F_2 \qquad (25)$$

Setting the value of T_{12} in Eq (25) to be infinity yields $\Delta F_1 = \Delta F_2$. Next, by multiplying state equation of $\Delta\dot{F}_1$ *and* $\Delta\dot{F}_2$ in Eq (24) by $\dfrac{T_{p1}}{k_{p1}}$ and $\dfrac{T_{p2}}{a_{12}\,k_{p2}}$ respectively, then

$$\frac{T_{p1}}{k_{p1}}\Delta\dot{F}_1 = -\frac{1}{k_{p1}}\Delta F_1 - \Delta P_{T12} + \Delta P_{SCES} \qquad (26)$$

$$\frac{T_{p2}}{a_{12}\,k_{p2}}\Delta\dot{F}_2 = \frac{-1}{k_{p2}\,a_{12}}\Delta F_2 + \Delta P_{T12} \qquad (27)$$

By summing Eq (26) and Eq (27) and using the above relation $\Delta F1 = \Delta F_2 = \Delta F$

$$\Delta\dot{F} = \frac{\left(-\dfrac{1}{k_{p1}} - \dfrac{1}{k_{p2}a_{12}}\right)}{\left(\dfrac{T_{p1}}{k_{p1}} + \dfrac{T_{p2}}{k_{p2}a_{12}}\right)}\Delta F + \frac{1}{\left(\dfrac{T_{p1}}{k_{p1}} + \dfrac{T_{p2}}{k_{p2}a_{12}}\right)}\Delta P_{SCES} + C\Delta P_D \quad (28)$$

Where the load change in this system ΔP_D is additionally considered, here the control $\Delta P_{SCES} = -K_{SCES}\,\Delta F$ is applied then.

$$\Delta F = \frac{C}{s + A + K_{SCES}\;B}\Delta P_D \qquad (29)$$

Where $A = \left(-\dfrac{1}{k_{p1}} - \dfrac{1}{k_{p2}a_{12}}\right) \Big/ \left(\dfrac{T_{p1}}{k_{p1}} + \dfrac{T_{p2}}{k_{p2}a_{12}}\right)$

$$B = \frac{1}{\left[\dfrac{T_{p1}}{K_{p1}} + \dfrac{T_{p2}}{K_{p2}a_{12}}\right]}$$

Where C is the proportionality constant between change in frequency and change in load demand. Since the control action of SCES unit is to suppress the deviation of the frequency quickly against the sudden change of ΔP_D, the percent reduction of the final value after applying a step change ΔP_D can be given as a control specification. In Eq (29) the final values with $K_{SCES} = 0$ and with $K_{SCES} \neq 0$ are C/A and C/(A+K_{SCES} B) respectively therefore the percentage reduction is represented by

$$C/(A + K_{SCES}\;B) \big/ (C/A) = R \big/ 100 \qquad (30)$$

For a given R, the control gain of SCES is calculated as

$$K_{SCES} = \frac{A}{BR}(100 - R) \qquad (31)$$

VI. NERC' S CONTROL PERFORMANCE STANDARDS

North American Electric Reliability Council (NERC) had proposed new control performance standards CPS1 and CPS2 to evaluate the control area performance in normal interconnected power system operation [18, 19]. Each control area is required to monitor its control performance and report its compliance CPS1 and CPS2 to NERC at regular intervals [20, 21].

A. Control Performance Standard 1(CPS1)

CPS1 assesses the impact of ACE on frequency over a certain period window or horizon and it is defined as follows: over a sliding period, the average of the "clock-minute averages" of a control area's ACE divided by "10 times its area frequency bias" times the corresponding "clock- minute averages of the interconnection frequency error" shall be less than the square of a given constant, ϵ_1, representing a target frequency bound.This is expressed by [20,21]

$$AVG_{period}\left[\left(\frac{ACE_i}{-10\beta_i}\right)_1 \Delta F_i\right] \le \varepsilon_1^2 \tag{32}$$

Where $ACE_i = \Delta P_{Tie} + \beta_i \Delta F_i$, ΔF_i is the clock- minute average of frequency deviation, βi the frequency bias of the i^{th} control area, ε_1 the targeted frequency bound and n-scaling factor for CPS1 and $(.)_1$ is the clock -1 min average. To calculate CPS1 (K_{CPS1}), a compliance factor (K_{CF}) is defined as:

$$K_{CF} = \frac{\sum\left[\left(\frac{ACE_i}{-10\beta_i}\right)_1 \Delta F_1\right]}{n\varepsilon_1^2} \tag{33}$$

CPS1 is then obtained from the following equation

$$K_{CPS1} = \left(2 - K_{CF}\right) * 100\% \tag{34}$$

1. When $K_{CPS1} \ge 200\%$, which means $K_{CF} \le 0$, there is $\sum(ACE_1 * \Delta F_1) \le 0$. Under this condition, ACE facilitates the frequency quality
2. When $100\% \le K_{CPS1} < 200\%$, which means $0 < K_{CF} \le 1$, there is $0 \le \Sigma\left[\left(\frac{ACE_i}{-10\beta_i}\right)_1 * \Delta F_1\right] \le n\varepsilon_1^2$. The CPS1 standard is satisfied.
3. When $K_{CPS1} < 100\%$, which means $K_{CF} > 1$, there is $\Sigma\left[\left(\frac{ACE_i}{-10\beta_i}\right)_1 * \Delta F_1\right] > n\varepsilon_1^2$. ACE has exceeded the permitted range so that it has a bad effect on the frequency and quality of power grid.

B. Control Performance Standard 2 (CPS2)

The second performance standard, CPS2 (K_{CPS2}), limits the magnitude of short- term ACE values. It requires the 10-min averages of a control area's ACE be less than a given constant (L_{10}), as in the equation below:

$$AVG_{10\min}(ACE_i) \le L_{10} \tag{35}$$

Where, $L_{10} = 1.65\,\varepsilon_{10}\sqrt{(-10\beta_i)(-10\beta_s)}$. Note that β_s is the summation of the frequency bias settings of all control areas in the considered interconnection, and ε_{10} is the target frequency bound for CPS2. To comply with this standard, each control area must have its compliance no less than 90%. A compliance percentage is calculated from the following equation:

$$K_{CPS2} = \frac{AVG_{10\min}(ACE_i)}{L_{10}} \tag{36}$$

In order to meet the requirements of the power grid frequency quality, the average ACE value during 10 min in each control region should be in the normal distribution as:

$$\sigma = \varepsilon_{10}\sqrt{(-10\beta_i)(-10\beta_s)} \tag{37}$$

C. Application of Dual Mode Two Layered Fuzzy Logic controller for the two- area interconnected Power System with SCES units considering CPS1 and CPS2

The Linearized model of two- area reheat thermal interconnected power system with SCES unit considering CPS1 and CPS2 as shown in Fig 7.

VII. SIMULATION RESULTS AND OBSERVATIONS

Dual Mode Two Layered Fuzzy logic based controllers are designed and implemented in a two- area interconnected reheat thermal power system without and with SCES Unit considering Control Performance Standard CPS1 and CPS2 for 1% step load disturbance in area 1. The nominal parameters are given in Appendix- B. The gain values of SCES (K_{SCES}) are calculated for the given value of speed regulation coefficient (R). The gain value is of the super capacitor is found to be $K_{SCES} = 0.67$. The fuzzy rules are designed according to ACE is shown in Table I and II. Relative compliance of the proposed controller based LFC schemes to the NERC standards have been established for the above power system. In the present work, variation of load in only area1 has been considered. The compliance factor (K_{CF}) for one hour was computed with the consideration that the response of the controller to the load variations for the year will be similar to that obtained during the sample period of one hour, the CF value so computed was used to calculate CPS1. In addition, the CPS 2 was also computed. It is seen from figures (8 to 10) it is evident that the dynamic responses have improved significantly with the use of information that reflects compliance with CPS1 and CPS2. This algorithm will significantly reduce the wear and tear of the equipment since movements of the governor set point or raise/lower signal (ΔP_c) generated from the integral controller are less frequent when the control area has high compliance or that values of 1-minute average compliance factor (CF) or accumulatively average compliance factor (CF_{ac}) is less than unity.

The comparative transient response from Fig 8 and 9, it can be observed that the oscillations in area frequencies, tie-line power deviation and control input requirements have decreases to a considerable extent for the system with use of dual mode Two layered fuzzy logic control considering CPS1 and CPS2 as compared to that of the system using Dual Mode Two Layered Fuzzy Logic control. Moreover the Super Capacitor Energy Storage unit is located in area 1 which is adopted to ensure the coordinated control action along with the governor unit to enable more improvement in the inertia mode oscillations as shown in Fig 8. It is also evident that the settling time and peak over/under shoot of the frequency deviations in each area and tie-line power deviations decreases considerable amount with use of SCES unit. In Fig 9, it should be noted that SCES coordinated with governor unit requires lesser control effort. Fig 10 shows the generation responses for the three case studies as the load disturbances have occurred in area1, at steady state, the powers generated by generating units in both areas are in proportion to the area participation factors. From the Table III it can be observed that the controller design using dual mode Two layered fuzzy logic controller for two area thermal reheat power system with SCES unit have not only reduces the cost function but also ensure better stability, as they possesses less over/under shoot and faster settling time. Thus SCES unit coordinated with governor unit improves not only inertia mode but also the inter area mode oscillations effectively.

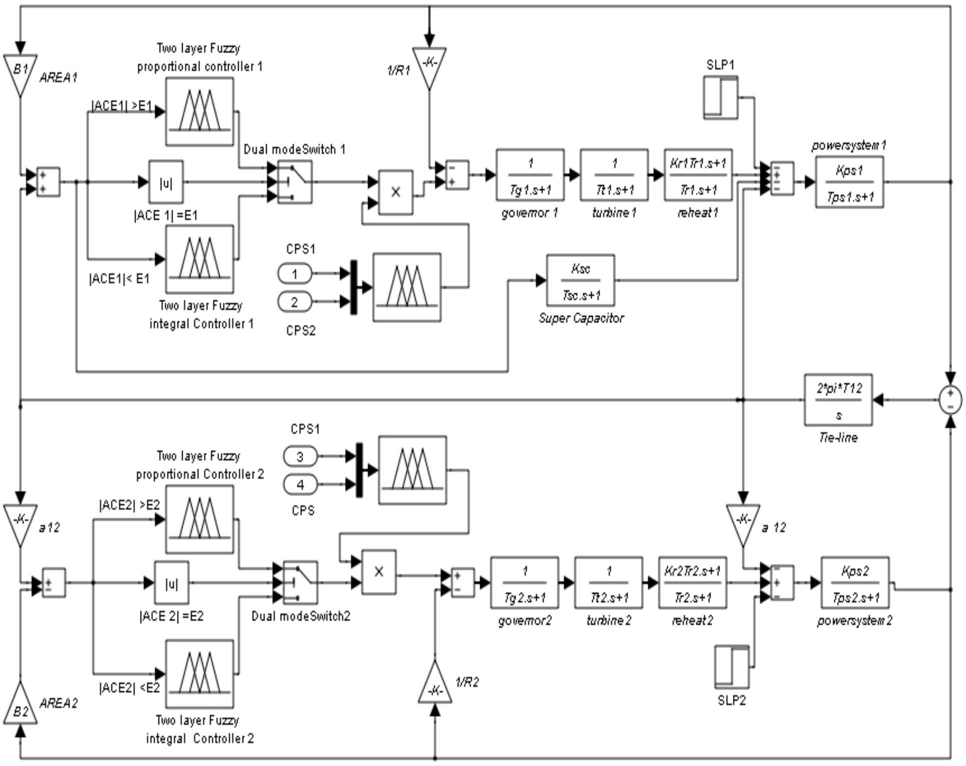


Fig.7 Linearized model of a two- area interconnected reheat thermal power system with SCES unit considering Dual Mode Two Layered Fuzzy Logic Controller designed using CPS1 and CPS2 criteria

TABLE III.COMPARISON OF THE SYSTEM PERFORMANCE

Two area interconnected power system	Setting time(τ_s)in sec			Peak over / under shoot		
	ΔF_1	ΔF_2	ΔP_{tie}	ΔF_1 (Hz)	ΔF_2 (Hz)	ΔP_{tie} (p.u. MW)
Case:1 Dual mode Two layer fuzzy controller	6.347	5.572	6.634	0.009	0.008	0.0021
Case:2 Dual mode Two layer fuzz controller considering CPS1 and CPS2	4.647	4.134	5.823	0.007	0.006	0.0017
Case:3 Dual mode Two layer fuzzy controller considering CPS1 and CPS2with SCES unit	3.643	3.184	4.153	0.003	0.002	0.0006

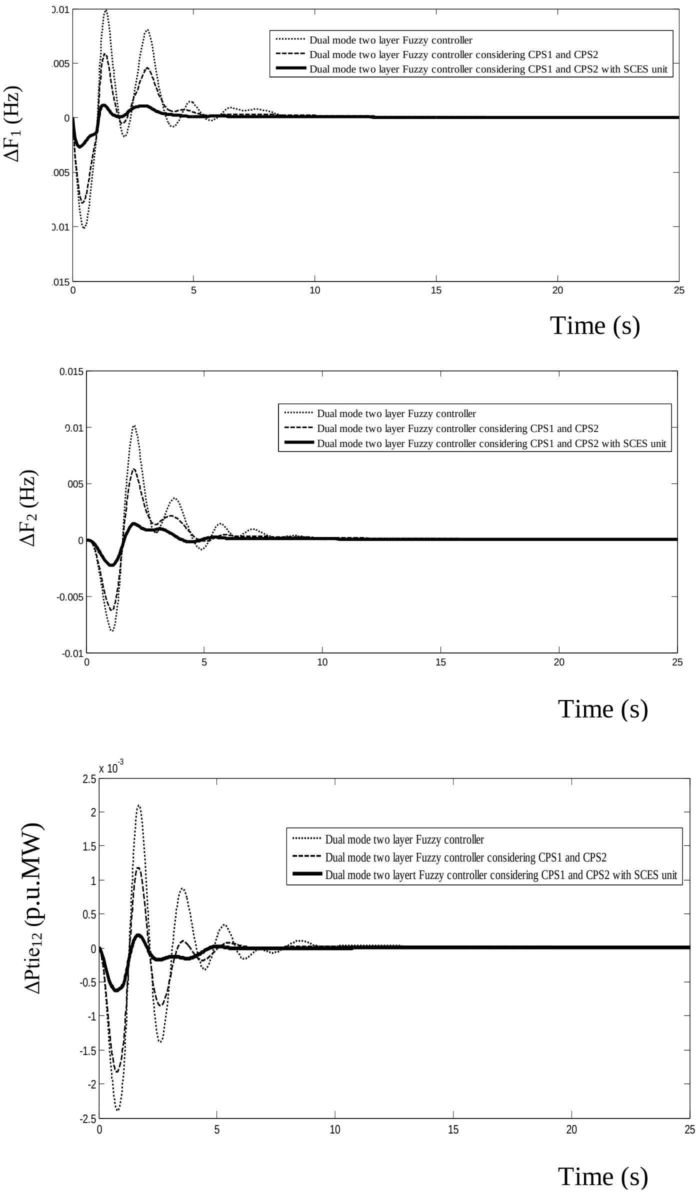
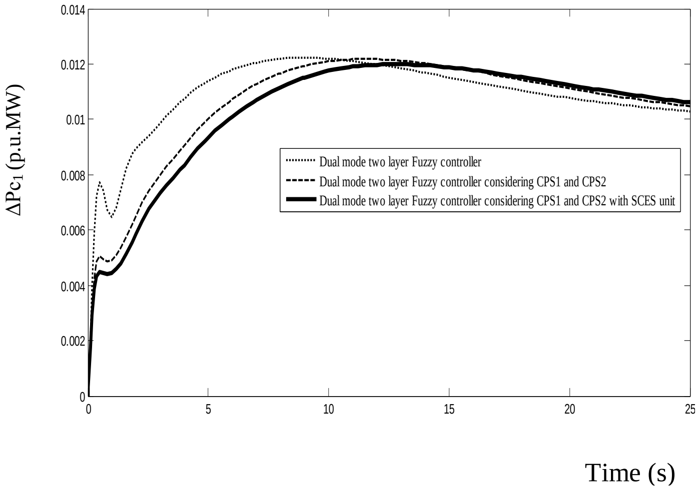


Fig.8 Dynamic responses of the frequency deviations and tie line power deviation of a two-are thermal reheat interconnected Power System considering a step load disturbance of 0.01 p.u. MW in area 1



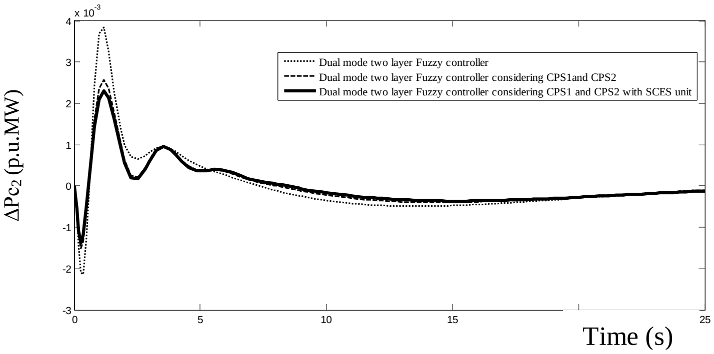


Fig. 9 Dynamic responses of the Control input deviations of a two-area thermal reheat interconnected Power System considering a step load disturbance of 0.01p.u.MW in area 1

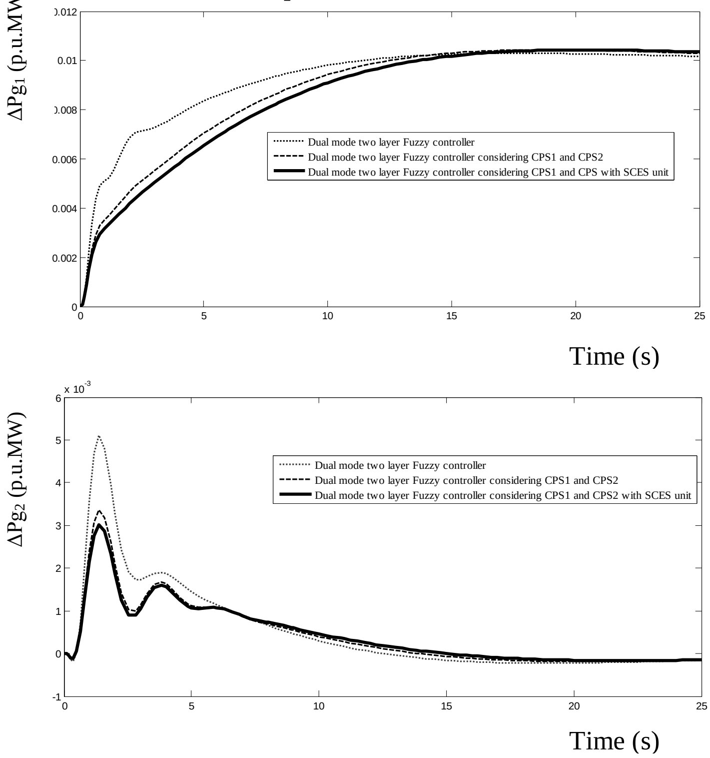


Fig 10 Dynamic responses of the required additional mechanical power generation for two-area thermal reheat interconnected Power System considering a step load disturbance of 0.01p.u.MW in area 1

VIII CONCLUSION

A Dual mode Two Layered Fuzzy logic controller were designed and implemented for a two area thermal reheat interconnected power system with super capacitor energy storage devices. In this the control scheme consists of two layers viz fuzzy pre-compensator and fuzzy like P and fuzzy like I controllers. Fuzzy rules from the overall fuzzy rule vectors are used at the first layer, linear combination of independent fuzzy rules are used at the second layer. The two layer fuzzy system has less number of fuzzy rules as compared with the fuzzy logic system. Simulation result ensures that the Dual mode two layered fuzzy logic controllers give better simulation results when compared with the simulation results obtained using the Dual mode PI controllers for the system without super capacitor energy storage unit.

The design objectives are (i) to comply with the North American Electric Reliability council's Control Performance Standards (CPS1 and CPS2) (ii) to reduce wear and tear of generating unit's equipments, and (iii) to design feasible control structure. The gain of this proportional/integral-type controller consists of products of two terms, a conventional control gain and fuzzy gain. The fuzzy gain is set using fuzzy logic rules which are developed to comply with NERC' s standards and to manipulate the generator's set points only if need be to reduce the excessive maneuvering and hence minimize the cost of operation and maintenance associated with LFC.

The advantages of the expected SCES over existing power system in the LFC applications were examined. For an overload condition for a short time period because of nature of SCES, extremely faster response is obtained with use of SCES unit. From this it is evident that SCES contributes a lot in promoting the efficiency of overall generation control through the effect of the use in load leveling and the assurance of LFC capacity after overload characteristic and quick responsiveness. It should be noted that the design concept accounts for damping out the inertia mode and inter-area mode oscillations in an effective manner by suppressing the frequency deviation of two area system simultaneously. It may be concluded that, Super Capacitor Energy Storage devices with a sufficient margin of LFC capacity absorbs the speed governor capability in excess of falling short of the frequency bias value. It may be expected to be utilized as a new ancillary service for stabilization of the tie-line power oscillations even under congestion management environment of the power transfer.

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AUTHOR BIOGRAPHY

V.Adhimoorthy (1974) received Bachelor of Engineering in Electrical and Electronics Engineering (2002), Master of Engineering in Power System Engineering (2008) and he is working as Assistant Professor in the Department of Electrical Engineering, Annamalai University He is currently pursuing Ph.D degree in Electrical Engineering at Annamalai University, Annamalainagar. His research interests are in Power Systems, Control Systems, Electrical Measurements. (Electrical Measurements Laboratory, Department of Electrical Engineering, Annamalai University, Annamalainagar-608002, Tamilnadu, India, adhisuganthi@gmail.com

I.A.Chidambaram (1966) received Bachelor of Engineering in Electrical and Electronics Engineering (1987), Master of Engineering in Power System Engineering (1992) and Ph.D in Electrical Engineering (2007) from Annamalai University, Annamalainagar. During 1988 - 1993 he was working as Lecturer in the Department of Electrical Engineering, Annamalai University and from 2007 he is working as Professor in the Department of Electrical Engineering, Annamalai University, Annamalainagar. He is a member of ISTE and ISCA. His research interests are in Power Systems, Electrical Measurements and Controls, Department of Electrical Engineering, Annamalai University, Annamalainagar – 608002, Tamilnadu, India, Tel: - 91-04144-238501, Fax: -91-04144-238275 driacdm@yahoo.com

APPENDIX

A. Super Capacitor Energy Storage Units

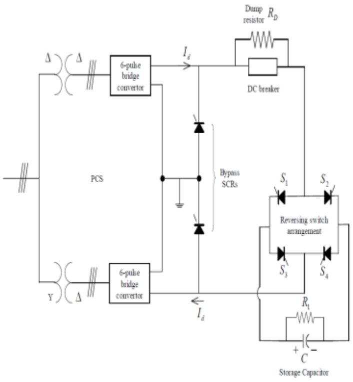

Fig A.1Super Capacitive Energy Storage Unit

A Super Capacitive Energy Storage (SCES) consists of a super capacitor or a Cryogenic Hyper Capacitor (CHC), a Power Conversion System (PCS) and the associated protective circuitry as shown in Fig.A.1. The CHCs differ from the conventional capacitors in that they are multilayer ceramic capacitors with a dielectric that has its peak dielectric constant at 77 K, the temperature of liquid nitrogen. The dimensions of the capacitor are determined by the energy storage capacity required. The storage capacitor C may consists of many discrete capacitance units connected in parallel. The resistor R_1 connected in parallel across the capacitor is the lumped equivalent resistance representing the dielectric and leakage losses of the capacitor bank. The PCS, consisting of an ac-to dc rectifier and a dc-to-ac inverter, form the electrical interface between the capacitor and the power system. Two bridges are preferred so that harmonics produced on the ac bus and in the output voltage to the capacitor are reduced. The bypass thyristors provide a path for current I_d in the event of a converter failure. The dc breaker allows current I_d to be diverted into the energy dump resistor R_D if the converter fails. Assuming the losses to be negligible, the bridge voltage E_d is given by

$$E_d = 2E_{d0}\cos\alpha - 2I_dR_D \quad \text{(A.1)}$$

By changing the relative phase angle α of this pulse through a range from 0° to 180° voltage across the capacitor, E_d can be made to vary from its maximum positive value to the maximum negative value. The voltage pulses from the firing circuits are timed to cause each SCR to begin conduction at a prescribed time. The sequence maintains a constant average voltage across the capacitor. The exact timing of the firing pulses relative to the phase of 50 Hz AC voltage determines the average dc voltage across the capacitor. Since the bridges always maintain unidirectional current and E_d is uniquely defined by α for positive and negative values, the power flow P_d in the capacitor is uniquely determined by α in both magnitude and direction. Thus, without any switching operation, reversibility as well as magnitude control of the power flow is achieved by continuously controlling the firing angle α. The firing angle of the converter is controlled by an algorithm determined by utility needs, but basically the control circuit responds to a demand signal for a certain power level, either positive or negative. Then based on the voltage across the capacitor, a firing angle is calculated and transmitted to the firing circuit. The response time of the control and firing circuits to a new demand signal are so short that a new firing angle may be chosen for the very next SCR to be pulsed, say within a few milliseconds. This rapid response to power demands that may vary by hundreds of megawatts is a unique capability of SCES relative to other energy storage systems such as pumped hydro, compressed air, flywheels etc. This ability to respond quickly allows the SCES unit to function not only as an energy storage unit but also as a spinning reserve and to provide stability in case of disturbances on the utility system. The reversing switch arrangement provided accommodates the change of direction of the current in the capacitor during charging (rated load period) and discharging (during peak load period), since the direction of the current through the bridge converter (rectifier/inverter) cannot change. During the charging mode, switches S_1 and S_4 are on and S_2 and S_3 are off. In the discharging mode, S_2 and S_3 are on and S_1 and S_4 are off [12].

The normal operating point of the capacitor can be such that the maximum allowable energy absorption equals the maximum allowable energy discharge. This will make the SCES unit very effective in damping the oscillations created by sudden increase or decrease in load. If E_{d0} denotes the set value of voltage and Ed_{max} and Ed_{min} denote the maximum and minimum limits of voltage respectively, then

$$\frac{1}{2}CE_{d\max}^{2}-\frac{1}{2}CE_{do}^{2}=\frac{1}{2}CE_{do}^{2}-\frac{1}{2}CE_{d\min}^{2} \qquad \text{(A.2)}$$

$$E_{do}=\frac{\left[E_{d\max}^{2}+E_{d\min}^{2}\right]^{1/2}}{2} \qquad \text{(A.3)}$$

The capacitor voltage should not be allowed to deviate beyond certain lower and upper limits. During a sudden system disturbance, if the capacitor voltage goes too low and if another disturbance occurs before the voltage returns to its normal value, more energy will be withdrawn from the capacitor which may cause discontinuous control. To overcome this problem, a lower limit is imposed for the capacitor voltage and in the present study; it is taken as 30% of the rated value. Initially, the capacitor is charged to its set value of voltage E_{d0} (less than the full charge value) from the utility grid during its normal operation. To charge the capacitor at the maximum rate, E_d is set at its maximum value by setting $\alpha = 0°$. At any time during the charging period, the stored energy in Joules is proportional to the square of the voltage as described. Once the voltage reaches its rated value, it is kept floating at this value by a continuous supply from PCS which is sufficient to overcome the resistive drop. Since this E_{d0} is very small, the firing angle α will be nearly 90°. The SCES is now ready to be put into service. When there is a sudden rise in load demand, the stored energy is almost immediately released through the PCS to the grid. As the governor and other control mechanisms start working to set the power system to an equilibrium condition, the capacitor charges to its initial value of voltage E_{d0}. The action during sudden releases of load is similar that the capacitor immediately gets charged instantaneously towards its full value, thus absorbing some portion of the excess energy in the system, and as the system returns to its steady state, the excess energy absorbed is released and the capacitor voltage attains its normal value. The power flow into the capacitor at any instant is

$$P_d = E_d I_d \qquad \text{(A.4)}$$

And, the initial power flow into the capacitor is

$$P_{do} = E_{do}.I_{do} \qquad \text{(A.5)}$$

Where E_{d0} and I_{d0} are the magnitudes of voltage and current prior to the load disturbance. When a load disturbance occurs, the power flow into the coil is

$$P_{do}+\Delta P_d=\left(E_{do}+\Delta E_d\right)\left(I_{do}+\Delta I_d\right) \qquad \text{(A.6)}$$

so that the incremental power change in the capacitor is

$$\Delta P_d=\left(I_{do}\Delta E_d+\Delta E_d \Delta I_d\right) \qquad \text{(A.7)}$$

The term $E_{d0}.I_{d0}$ is neglected since $E_{d0} = 0$ in the storage mode to hold the rated voltage at constant value

B. Data for Thermal Power System with Reheat Turbines [5].

f^0 = 60 Hz, $Pr_1 = Pr_2$ = 2000 MW, $K_{p1}=K_{p2}$= 120 Hz / pu.MW, $T_{pS1} = T_{pS2}$ = 20 sec, $T_{t1} = T_{t2}$ = 0.3 sec, $T_{g1}=T_{g2}$= 0.08 sec, $K_{r1}=K_{r2}$= 0.5, $T_{r1} = T_{r2}$ = 10 sec, R1 = R2 = 2.4 Hz/p.u MW, $\beta_1=\beta_2$ = 0.425 pu.MW/Hz, ΔP_{D1} = 0.01 p.u MW, T = 2 sec (Normal sampling rate), T_{12}=0.545 pu.MW/Hz, ε_1 =18mHZ, ε_{10} = 5.7mHZ

C. Data for Super Capacitor Energy Storage unit [15]

T_{SCES} =0.01 sec, K_{vd} = 0.1 KV / KA, Ko = 70 KV/Hz, T_{DC}= 0.055 sec, C = 1 F, R= 100ohm, E_{do} =2 kV