Wind Energy Conversion Systems Based On a DFIG Controlled By Indirect Vector Using PWM And SVM

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Abstract: A well-prepared abstract enables the reader to identify the basic content of a document quickly and accurately. This work presents consideration and use of the asynchronous generator in the production of wind energy. To do this, a model of the wind turbine has been established, the mathematical model of the doubly fed induction generator (DFIG) variable speed is presented and the control quantities used when integrated with a wind system. A modeling in a diphasic reference mark related to the stator field and a strategy vector control active and reactive power are offered with a PWM and SVM technique for inverter control is considered in our work.

Key words: Wind, Turbine, DFIG, PWM, SVM

1. Introduction

This paper is to study the indirect control power of doubly fed induction generator (DFIG) operation generator for this, our work is organized as follows:
The first part is dedicated to the description and modeling of wind turbines based on physical equations responsive operation.
The second part, we present a mathematical model of the (DFIG) will simulate the model in generator mode.
The third is devoted to the study of the technique of indirect control power to realize the conversion DC-AC inverter using two voltage levels with technical using the PWM controller (Pulse Width Modulation) and SVM (space vector modulation)

2. Model of The Turbine

A wind turbine, commonly called wind is a device which transforms a part of the kinetic energy of wind into mechanical energy available on a shaft and then into electrical energy via a generator (DFIG)[1].
Mechanical power available on the shaft of a wind turbine is expressed as:

\[ P_m = \frac{1}{2} \cdot C_p \cdot \rho \cdot \pi \cdot R^2 \cdot V_i^3 \]  \hspace{1cm} (1)

With:
\[ \lambda = \frac{\Omega_1 \cdot R}{V_i} \]  \hspace{1cm} (2)

\[ \Omega_1; \text{ Rotation speed before multiplier.} \]
\[ R; \text{ rotor radius 35.25 m.} \]
\[ \rho; \text{ air density,1.225 kg.m}^{-3}. \]

\[ C_p = f(\lambda, \beta)=C_1 \left( \frac{C_2}{\lambda} - C_3 \cdot \beta - C_4 \right) \exp \left( \frac{C_5}{\lambda} \right) + C_6 \lambda \]  \hspace{1cm} (3)

With:
\[ \frac{1}{\lambda} = \frac{1}{\lambda + 0.08 \beta - 0.035} \]
\[ C_1=0.5176; \hspace{0.5cm} C_2=116; \hspace{0.5cm} C_3=0.4; \hspace{0.5cm} C_4=5; \hspace{0.5cm} C_5=21; \hspace{0.5cm} C_6=0.0068 \ [1], [2]. \]

Characteristics of \( C_p \) in terms of \( \lambda \) for different values of the pitch angle are shown in Fig.1. The maximum value of \( C_p \) \((C_{p,\text{max}}=0.4353)\) is reached of \( \beta=2^\circ \) and \( \lambda=10.01 \). This particular value of \( \lambda \) is defined as the nominal value [1], [3].

![Fig. 1. The power factor for different angles of stalls.](image-url)
3. Model of the Doubly Fed Induction Generator

A commonly used model for the doubly fed induction generator (DFIG) is the Park model. The electrical equations of the DFIG in the Park reference frame are given as follows [4], [5]:

\[
\begin{align*}
V_{sd} &= R_s i_{sd} + \frac{d\varphi_{sd}}{dt} - \omega_r \varphi_{sq} \\
V_{sq} &= R_s i_{sq} + \frac{d\varphi_{sq}}{dt} + \omega_r \varphi_{sd} \\
V_{rd} &= R_r i_{rd} + \frac{d\varphi_{rd}}{dt} - \omega_r \varphi_{rq} \\
V_{rq} &= R_r i_{rq} + \frac{d\varphi_{rq}}{dt} + \omega_r \varphi_{rd}
\end{align*}
\] (4)

The stator and rotor flux are given as:

\[
\begin{align*}
\varphi_{sd} &= L_s i_{sd} + L_m i_{rd} \\
\varphi_{sq} &= L_s i_{sq} + L_m i_{rq} \\
\varphi_{rd} &= L_r i_{rd} + L_m i_{sd} \\
\varphi_{rq} &= L_r i_{rq} + L_m i_{sq}
\end{align*}
\] (6)

In these equations, \(R_s, R_r, L_s\) and \(L_r\) are respectively the resistances and the inductances of the stator and the rotor windings, \(L_m\) is the mutual inductance.

\(V_{sd}, V_{sq}, V_{rd}, V_{rq}, i_{sd}, i_{sq}, i_{rd}, i_{rq}, \varphi_{sd}, \varphi_{sq}, \varphi_{rd}, \varphi_{rq}\) are the d and q components of the stator and rotor voltages, currents and flux, whereas \(\omega_r\) is the rotor speed in electrical degree.

The electromagnetic torque is expressed as:

\[C_{em} = -p \frac{L_m}{L_s} i_{rq} \varphi_{sd}\] (8)

By replacing (9) in (6) and (8), the electromagnetic torque can be given as follows:

\[
\begin{align*}
V_{sd} &= 0 \\
V_{sq} &= V_s + \omega_r \varphi_s \\
\varphi_{sd} &= L_s i_{sd} + L_m i_{rd} \\
0 &= L_s i_{sq} + L_m i_{rq}
\end{align*}
\] (11)

From (12), the equations linking the stator currents to the rotor currents are deduced below:

\[
\begin{align*}
i_{id} &= \frac{\varphi_{s}}{L_s} - \frac{L_m}{L_s} i_{rd} \\
i_{iq} &= -\frac{L_m}{L_s} i_{rq}
\end{align*}
\] (13)

The active and reactive powers at the stator side are defined as:

\[
\begin{align*}
P_s &= V_{sd} i_{sd} + V_{sq} i_{sq} \\
Q_s &= V_{sq} i_{sd} - V_{sd} i_{sq}
\end{align*}
\] (14)

Replacing the stator currents by their expressions given in (15), the equations below are obtained:

\[
\begin{align*}
P_s &= -V_s \frac{L_m}{L_s} i_{rq} \\
Q_s &= V_s \varphi_{s} - \frac{V_{s} L_m}{L_r} i_{rd}
\end{align*}
\] (16)

The block diagram of the DFIG model in Park reference frame is depicted in Fig 3, assuming a constant stator voltage \(V_s\)[7].
4. Regulation With Buckle of Power

to improve the control system the DFIG, we will introduce an additional loop control of active and reactive power in the block diagram of the control loop without power so that each axis controller contains two PI control, one to control the power and the other rotor current (figure 4) [8].

5. Modeling of Voltage Inverters Two Levels

The three-phase voltage inverter at two levels, is composed of three independent arms, comprising two switches each. each switch comprises an IGBT or GTO thyristors and a diode connected in antiparallel. can be replaced group each transistor-diode switches by kj with (j = 1, 2, 3, 4, 5, 6), we obtain the simplified diagram for each inverter as shown in Fig. 5. [9].

\[
\begin{align*}
V_{AC} &= V_{AO} + V_{ON} \\
V_{BC} &= V_{BO} + V_{ON} \\
V_{CE} &= V_{CO} + V_{ON} \\
\end{align*}
\]

(17)

Knowing that the system is symmetrical stator phase voltages:

\[ V_A + V_B + V_C = 0 \]  

(18)

The voltage converter can be modeled by a matrix \([T]\) providing passage DC to AC.

\[
\begin{bmatrix}
V_{AC} \\
V_{BC} \\
V_{CE}
\end{bmatrix} = [T]
\begin{bmatrix}
V_{dc}
\end{bmatrix}
\]

(19)
such that:

\[
\begin{bmatrix}
V_{AC} \\
V_{de} \\
V_{DC}
\end{bmatrix} =
\begin{bmatrix}
V_A & V_B & V_C \\
V_AO & V_BO & V_CO \\
E & S_1 & S_2 & S_3
\end{bmatrix}^T
\]

(20)

So, for each arm there are two independent states, these states can be considered as Boolean variables. Supposed ideal switching: \( S_i = (1 \text{ ou } 0) \) \( \{i=1,2,3\} \).

The transfer matrix is:

\[
[T] =
\begin{bmatrix}
2 & -1 & -1 \\
-1 & 2 & -1 \\
-1 & -1 & 2
\end{bmatrix}
\]

(21)

In our work, the switches of the inverter are made by using the PWM controller (Pulse Width Modulation) and SVM (space vector modulation).

6. Pulse Width Modulation (PWM)

The most widely used method of pulse width modulation is based carrier. this method is also known as the sinusoidal (SPWM), triangulation, subharmonic, or method suboscillation [10], [11]. Sinusoidal modulation is based on a triangular carrier signal as shown in Fig. 6. In this method, three reference signals \( U_A, U_B, U_C \) comparing with triangular carrier signal \( U_t \) which is common to all three phases. In this way, the logic signals \( S_a, S_b, S_c \) are generated, which define the switching times of the power transistors.

7. The Simulation Results of The Indirect Control With PWM

The simulation is performed by imposing the active and reactive power reference (\( P_{ref}, Q_{ref} \)), while the DFIG is driven at variable speed \( P_{ref} \) varies between \(-300000\) and \(-100000\) watts and \( Q_{ref} \) varies between \(-100000\) and \(-400000\) VAR and \( d_e \) \( s_{abc} \) varies between \( 1000 \) A and \( 2500 \) A.

Fig. 7. Electrical active power produced with PWM.

Fig. 8. Electrical reactive power produced with PWM.

Fig. 9. Stator phase currents with PWM.
8. Space Vector Modulation (SVM)

Modulation techniques different spatial vectors of the carrier on the basis of this manner, there is no separate modulators used for each of the three phases. Instead of them, the reference voltages are supplied by the voltage vector of the space and the output voltages of the inverter are considered space vectors [12]:

\[
V_i = \begin{cases} 
\frac{2}{3} U_{dc} e^{j(\sigma-1)\pi/3}, & i = 1, 2, 3, 5, 6 \\
0, & i = 0, 4, 7 
\end{cases} \quad (22)
\]

There is a possible eight vectors output voltage, six active vectors V1 – V6, and two zero vectors V0, V7 figure 10. The reference voltage vector is performed by sequentially switching the active and zero vectors.

In Fig.10 shows voltage vector reference voltage Vc and eight vectors, which corresponds to the possible states of the inverter. The six active vectors divide a plane for the six sectors 1-6. In the sector of each of the voltage reference vector Vc is obtained by switching on, for a suitable time, two adjacent vectors. Shown in Fig.10 reference vector Vc can be implemented by switching vectors V1, V2 and zero vectors V0, V7 [13], [14].

![Fig.10. THD of current Isa with PWM.](image1)

![Fig.11. Principle of the space vector modulation](image2)

![Fig.12. Block scheme of the space vector modulator](image3)

9. The Simulation Results of The Indirect Control with SVM

The reference voltage vector Vc is sampled with the fixed clock frequency \( f_s = 1/T_s \), and next a sampled value \( V_c(T_s) \) is used for calculation of times \( t_1, t_2, t_0 \) and \( t_7 \). The signal flow in space vector modulator is shown in Fig. 11.

The rotor of the DFIG is powered by a three-phase balanced system, and by a voltage to SVM inverters. To simulate the behavior of the DFIG, we opted for the MATLAB / Simulink software, the simulation results are given by the following figures.
10. Conclusion

In our work, we have established the model the machine with its electric equations in axis linked to the d-q synchronous system. We have also developed the method of vector control power of the machine to know the order and dedicated to the study of the art of the power of indirect control to achieve the DC-AC conversion using two voltage levels with technical PWM controller Pulse Width Modulation and SVM Modulation Vector Space. Indeed we have seen that the control indirectly allows us, together with the closure powers, to have an efficient system and robust. It is certainly more complex to work, but will have an operation optimal system of electric generation minimizing potential problems related to changes in machine parameters and the wind system.

Appendix A

- Nominal Power = 1.5 (Mw)
- Stator Per Phase Resistance = 0.012 (Ω)
- Rotor Per Phase Resistance = 0.021 (Ω)
- Stator Leakage Inductance = 2.0372.10^{-04} (H)
- Rotor Leakage Inductance = 1.7507.10^{-04} (H)
- Magnetizing Inductance = 0.0135 (H)
- Number Of Poles Pairs = 2
- Moment Of Inertia = 1000 (Kg.M²)
- Friction Coefficient = 0.0024
REFERENCES


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