An Adaptive Voltage Control Strategy of Three-Phase Inverter for Standalone Distributed Generation Systems

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Abstract—This paper proposes an adaptive control method of three-phase inverter for standalone distributed generation systems (DGSs). The proposed voltage controller includes two control terms: an adaptive compensating term and a stabilizing term. The adaptive compensating control term is constructed to avoid directly calculating the time derivatives of state variables. Meanwhile, the stabilizing control term is designed to asymptotically stabilize the error dynamics of the system. Also, a fourth-order optimal load current observer is proposed to reduce the number of current sensors and enhance the system reliability and cost effectiveness. Stability of the proposed voltage controller and the proposed load current observer is fully proven by using Lyapunov theory. The proposed control system can establish good voltage regulation such as fast dynamic response, small steady state error, and low total harmonic distortion (THD) under sudden load change, unbalanced load, and nonlinear load. Finally, the validity of the proposed control strategy is verified through simulations and experiments on a prototype DGS tested with a TMS320F28335 DSP. For a comparative study, the feedback linearization for multi-input and multi-output (FL-MIMO) control scheme is implemented and its results are presented in this paper.

Index Terms—Adaptive control, distributed generation system (DGS), load current observer, standalone, three-phase inverter, voltage control.

I. INTRODUCTION

Distributed generation systems (DGSs) using renewable energy sources (such as wind turbines, photovoltaic arrays, biomass, fuel cells, etc.) are gaining more and more attention in electric power industry to replace existing fossil fuels and reduce global warming gas emissions. Nowadays, the DGSs are extensively used in grid-connected applications, but they are more economical in a standalone operation in case of rural villages or remote islands because connecting to the grid may lead to higher cost [1]-[5].

In standalone applications, the load-side inverter of the DGS operates analogous to an uninterruptible power supply (UPS) for its local loads [6]. Control of standalone DGSs or UPSs is an attractive research area in recent years. In these applications, the regulation performance of inverter output voltage is evaluated in terms of transient response time, steady state error, and total harmonic distortion (THD). Furthermore, the quality of inverter output voltage is heavily affected by the types of loads such as sudden load change, unbalanced load, and nonlinear load. In [7], a conventional PI controller has been investigated. However, the output voltage has a considerable amount of the steady state error and its THD is not satisfactory in case of nonlinear load. The $H_\infty$ loop-shaping control scheme which is presented in [8] also cannot effectively mitigate the THD of the output voltage under nonlinear load. Therefore, the load-side inverters require advanced control techniques to achieve excellent voltage regulation performance, especially, under sudden load disturbance, unbalanced load, and nonlinear load.

Recently, various advanced control methods are applied to the load-side inverters in DGS and UPS applications [6], [9]-[23]. In [9]-[11], a repetitive control is used to regulate UPS inverters, but the general problem with a repetitive control is its slow response and lack of systematical method to stabilize the error dynamics. Feedback linearization control techniques are proposed in [12], [13]. Although these methods can achieve high performance of the output voltage, the control design techniques seem to be complicated. Two iterative learning control strategies are presented in [14], and these methods are capable of achieving high performance. However, the switching frequency of the inverter is very high, so it results in huge switching losses. In [15], a model predictive control with a load current observer is proposed. Although the control technique is simple, the THD of the output voltage is still high. In [16], another predictive control is proposed, but nonlinear load is not investigated. In [17], a robust PI controller is proposed for an autonomous distributed generation unit. A full set of results are presented in case of unbalanced $RLC$ load, but the results about nonlinear load are not presented. Sliding mode control techniques are applied for inverters in [18]-[21]. In [18], the experimental results show that the output voltage THD is still high under nonlinear load. In [19]-[21], although good performance can be obtained, the controller designs are only for single-phase inverters [19], [20] and the results of nonlinear load are not presented [21]. In [6], a robust servomechanism control (RSC) is used to
control three-phase inverter of a DGS in a standalone mode. Even though this control technique can achieve good performance, it is quite complicated and needs exact parameter values of an RLC load. In [22] and [23], the authors propose the control strategies that consist of an RSC in an outer loop and a sliding mode control in an inner loop. Even if the simulation and experimental results show good voltage performance, the control approach is complicated.

This paper proposes an adaptive voltage controller and an optimal load current observer of three-phase inverter for standalone DGSs. Also, it is analytically proven that the proposed voltage controller and the proposed load current observer are asymptotically stable, respectively. The proposed control method can achieve excellent voltage regulation such as fast transient behavior, small steady state error, and low THD under sudden load change, unbalanced load, and nonlinear load. For a comparative study, the feedback linearization for multi-input and multi-output (FL-MIMO) control method in [12] is implemented in this paper. Simulation is done by using Matlab/Simulink software and experiments are carried out on a prototype DGS test-bed with a TMS320F28335 DSP.

The remaining part of this paper is organized as follows. Section II describes the DGS in a standalone operation and the state-space model of the load-side inverter. The design and stability analysis of a proposed adaptive voltage controller are fully addressed in Section III. Section IV illustrates a proposed load current observer and analyzes its stability. In Section V, the simulation and experimental results are given to evaluate the performance of the proposed control algorithm. Finally, conclusions are drawn in Section VI.

II. SYSTEM DESCRIPTION AND MATHEMATICAL MODEL

The configuration of a typical DGS in a standalone operation is illustrated in Fig. 1. It consists of renewable energy sources (e.g., wind turbines, solar cells, and fuel cells), an ac-dc power converter (wind turbines) or a unidirectional dc-dc boost converter (solar cells or fuel cells), a three-phase ac-dc inverter, an LC output filter, a DSP control unit, and a local load. As shown in Fig. 1, a transformer can be used to provide an electrical isolation or boost the output voltage of the three-phase inverter, but it may lead to higher cost and larger volume. Also, storage systems such as batteries, ultra-capacitors, and flywheels may be used to generate electric power during the transient (e.g., start-up or sudden load change) and improve the reliability of renewable energy sources.

In this paper, we deal with the voltage controller design of the three-phase inverter for standalone DGSs that can assure excellent voltage regulation (i.e., fast transient response, small steady state error, and low THD) under sudden load change, unbalanced load, and nonlinear load. Thus, renewable energy sources and ac-dc power converter or unidirectional dc-dc boost converter can be replaced with a dc voltage source \( V_{dc} \). Fig. 2 describes the circuit model of a three-phase inverter with an LC output filter for standalone DGSs. As depicted in Fig. 2, the system comprises four parts: a dc voltage source \( V_{dc} \), a three-phase PWM inverter \( (S_f \text{ through } S_0) \), an output filter \( (L_f \text{ and } C_f) \), and a three-phase load \( (R_L) \). Note that the LC filter is required to suppress high-order harmonic components of the inverter output voltage due to the PWM action and then provide the load with sinusoidal voltages.

The circuit model in Fig. 2 uses the following quantities. The inverter output line to neutral voltage and phase current vectors are given by \( \mathbf{V}_i = [v_{ia} \ v_{ib} \ v_{ic}]^T \) and \( \mathbf{I}_i = [i_{ia} \ i_{ib} \ i_{ic}]^T \), respectively. In addition, the load neutral line to neutral voltage and phase current are represented by the vectors \( \mathbf{V}_L = [v_{la} \ v_{lb} \ v_{lc}]^T \), and \( \mathbf{I}_L = [i_{la} \ i_{lb} \ i_{lc}]^T \), respectively.

Assume that three-phase voltages and currents used in Fig. 2 are balanced. By applying Kirchoff’s current law (KCL) and Kirchoff’s voltage law (KVL) at the LC output filter, the following voltage and current equations can be derived:

\[
\begin{align*}
\frac{d\mathbf{V}_L}{dt} &= \frac{1}{C_f} \mathbf{I}_i - \frac{1}{C_f} \mathbf{I}_L \\
\frac{d\mathbf{I}_L}{dt} &= \frac{1}{L_f} \mathbf{V}_i - \frac{1}{L_f} \mathbf{V}_L
\end{align*}
\]

Under balanced conditions, the above state equations (1) in the stationary abc reference frame can be transformed to the equations in the stationary alf reference frame by using the following expression [2]-[3]:

\[
\mathbf{X}_{alf} = x_a e^{j0} + x_b e^{j\pi/3} + x_c e^{j2\pi/3}
\]

where \( \mathbf{X}_{alf} = x_a + jx_b \).

Thus, the state equations (1) can be transformed to the following:
where $V_\text{Ldq} = [v_{Ld} v_{Lq}]^T$, $I_\text{Ldq} = [i_{Ld} i_{Lq}]^T$, $V_{iq} = [v_i v_q]^T$, and $I_{iq} = [i_i i_q]^T$.

Next, the state equations in the stationary $a\beta$ reference frame can be transformed to the equations in the synchronously rotating $dq$ reference frame from the following formula:

$$X_{dq} = x_d + jx_q = X_{a\beta} e^{-j\theta}$$

where $\theta(t) = \int_0^t \omega(t) d\tau + \theta_0$ is the transformation angle, $\omega$ is the angular frequency ($\omega = 2\pi f$), and $f$ is the fundamental frequency of voltage or current.

Finally, the equations (3) can be transformed to

$$\begin{align*}
\frac{dV_{Ldq}}{dt} + j\omega V_{Ldq} &= \frac{1}{C_f} I_{Ldq} + \frac{1}{C_f} I_{Ldq}^* \\
\frac{dI_{Ldq}}{dt} + j\omega I_{Ldq} &= \frac{1}{L_f} V_{Ldq} + \frac{1}{L_f} V_{Ldq}^*
\end{align*}$$

where $V_{Ldq} = [v_{Ldq} v_{Lq}]^T$, $I_{Ldq} = [i_{Ldq} i_{Lq}]^T$, $V_{Ldq}^* = [v_{Ldq}^* v_{Lq}^*]^T$, and $I_{Ldq}^* = [i_{Ldq}^* i_{Lq}^*]^T$.

Also, (5) can be rewritten as follows:

$$\begin{align*}
\dot{v}_{Ld} &= \omega v_{Lq} - \frac{1}{C_f} i_{Ld} + \frac{1}{C_f} i_{Lq} \\
\dot{v}_{Lq} &= -\omega v_{Ld} - \frac{1}{C_f} i_{Ld} + \frac{1}{C_f} i_{Lq} \\
\dot{i}_{Ld} &= -\frac{1}{L_f} v_{Ld} + \omega i_{Lq} + \frac{1}{L_f} v_{Lq} \\
\dot{i}_{Lq} &= -\frac{1}{L_f} v_{Lq} - \omega i_{Ld} + \frac{1}{L_f} v_{Ld}
\end{align*}$$

where $\dot{v}_{Ld}$, $\dot{v}_{Lq}$, $\dot{i}_{Ld}$, and $\dot{i}_{Lq}$ denote the time derivatives of $v_{Ld}$, $v_{Lq}$, $i_{Ld}$, and $i_{Lq}$, respectively.

Note that $V_{Ldq}$ and $I_{Ldq}$ are the state variables, $V_{Ldq}$ is the control input, and $I_{Ldq}$ is defined as the disturbance.

In this paper, the following assumptions are made to design an adaptive controller and a load current observer:

1. $V_{Ldq}$, $V_{Ldq}^*$, $i_{Ld}$, and $i_{Lq}$ are available.
2. The desired load $dq$-axis voltages $v_{Ldq}$ and $v_{Lq}$ are constant, and its derivatives can be set to zero.
3. $i_{Ld}$ and $i_{Lq}$ are unknown, and they change very slowly during the sampling period [15].

III. ADAPTIVE VOLTAGE CONTROLLER DESIGN AND STABILITY ANALYSIS

Based on the system model (6), this section fully addresses the proposed adaptive control algorithm and its stability analysis.

First, the errors of the load $dq$-axis voltages ($v_{Ldq}$ and $v_{Lq}$) and the inverter $dq$ currents ($i_{Ld}$ and $i_{Lq}$) can be defined as

$$\tilde{v}_{Ld} = v_{Ld} - v_{Ldq}$$

$$\tilde{v}_{Lq} = v_{Lq} - v_{Lq}$$

$$\tilde{i}_{Ld} = i_{Ld} - i_{Ldq}$$

$$\tilde{i}_{Lq} = i_{Lq} - i_{Lq}$$

where $v_{Ldq}$ and $v_{Lq}$ are the reference values of $v_{Ld}$ and $v_{Lq}$, and $i_{Ldq}$ and $i_{Lq}$ are the reference values of $i_{Ld}$ and $i_{Lq}$. Again, the $i_{Ldq}$ term is defined as

$$i_{Ldq} = i_{Ld} - \omega C_f v_{Lq}$$

$$i_{Lq} = i_{Lq} + \omega C_f v_{Ld}$$

Next, the uncertainty terms $u_d$ and $u_q$, which cannot be accurately computed in real system, can be defined as

$$u_d = -\frac{\alpha f}{\alpha_d} v_{Lq} + \frac{L_f}{C_f} i_{Ld} - \frac{L_f}{C_f} i_{Ldq}$$

$$u_q = \frac{\alpha f}{\alpha_q} v_{Ld} + \frac{L_f}{C_f} i_{Lq} - \frac{L_f}{C_f} i_{Ldq}$$

where $\alpha_d$ and $\alpha_q$ are positive numbers.

As shown in (9), it should be noted that $u_d$ and $u_q$ include the time derivatives $i_{Ldq}$ and $i_{Ldq}$ which cannot be calculated directly because they are very noisy. In addition, assume that $L_f$ has some uncertainties due to nonlinear magnetic properties. Therefore, the uncertainty terms $u_d$ and $u_q$ need to be correctly estimated in real time instead of straightforwardly computing the time derivatives of $i_{Ldq}$ and $i_{Ldq}$.

Then, the following error dynamics can be obtained

$$\begin{align*}
\dot{\tilde{v}}_{Ld} &= \frac{1}{C_f} \tilde{v}_{Ld} \\
\dot{\tilde{v}}_{Lq} &= \frac{1}{C_f} \tilde{v}_{Lq} \\
\dot{\tilde{i}}_{Ld} &= -\alpha_d \tilde{v}_{Ld} + \frac{L_f}{C_f} (u_d - \tilde{v}_{Ld}) \\
\dot{\tilde{i}}_{Lq} &= -\alpha_q \tilde{v}_{Lq} + \frac{L_f}{C_f} (u_q - \tilde{v}_{Lq})
\end{align*}$$

The control inputs $v_{Ld}$ and $v_{Lq}$ can be divided into the following two control terms:

$$\begin{align*}
v_{Ld} &= u_{fLd} + u_{fLd} \\
v_{Lq} &= u_{fLq} + u_{fLq}
\end{align*}$$

where $u_{fLd} = u_d + v_{Ld}$ and $u_{fLq} = u_q + v_{Lq}$ are the $d$-axis and $q$-axis compensation control terms, and $u_{fLd}$ and $u_{fLq}$ are the $d$-axis and $q$-axis feedback control terms to stabilize the error dynamics of the system.

In order to establish this estimation law, let the following lemma be considered: **Lemma 1**: Assume that $(L_f i_{Ldq} + L_f i_{Ldq}^*)$ and $(L_f i_{Ldq} + L_f i_{Ldq}^*)$ slowly vary, so they can be set to the constant. There exist constant parameter vectors $m_d = [m_{d1} m_{d2} m_{d3} m_{d4}]^T$ and $m_q = [m_{q1} m_{q2} m_{q3} m_{q4}]^T$ such that

$$P_d m_d = \sum_{i=1}^4 P_{d_i} m_{d_i} = u_d$$

$$P_q m_q = \sum_{i=1}^4 P_{q_i} m_{q_i} = u_q$$

where $u_{dLd} = [u_{dLd} u_{dLd} u_{dLd} u_{dLd}]^T$ and $u_{dLq} = [u_{dLq} u_{dLq} u_{dLq} u_{dLq}]^T$.
where \( p_d = [p_{d1}, p_{d2}, p_{d3}, p_{d4}]^T = [\xi_{Ld}, i_{ad}, i_{qd}, 1]^T \) and \( p_q = [p_{q1}, p_{q2}, p_{q3}, p_{q4}]^T = [\xi_{Lq}, i_{ad}, i_{qq}, 1]^T \).

**Proof:** It is clear that (12) holds with

\[
\begin{align*}
    m^*_d &= \left[ -\frac{\omega L_f}{\alpha_d} \frac{f_{d} L_f}{C_f \alpha_d} \frac{L_f i_{\text{dref}}}{C_f \alpha_d} \right]^T \\
    m^*_q &= \left[ \frac{\omega L_f}{\alpha_q} \frac{L_f i_{\text{qref}}}{C_f \alpha_q} \frac{L_f i_{\text{qref}}}{C_f \alpha_q} \right]^T
\end{align*}
\]

Therefore, the following theorem can be established.

**Theorem 1:** Assume that \( C_j \) is known. Let the compensation control terms \((u_{fd}\) and \(u_{fq}\)) and the feedback control terms \((u_{bfd}\) and \(u_{bq}\)) be calculated by the following adaptive control laws:

\[
\begin{align*}
    u_{fd} &= \sum_{i=1}^{4} m_{di} p_{di} + v_{Ld}, \quad u_{fd} = -\delta_d \sigma_d \\
    u_{fq} &= \sum_{i=1}^{4} m_{qi} p_{qi} + v_{Lq}, \quad u_{fq} = -\delta_q \sigma_q
\end{align*}
\]

where

\[
\begin{align*}
    m_{di} &= -\frac{1}{\phi_{di}} \int_{0}^{t} \sigma_{d} d\tau, \quad m_{qi} = -\frac{1}{\phi_{qi}} \int_{0}^{t} \sigma_{q} d\tau \\
    \sigma_{d} &= (\nu_{Ld} + \alpha_d i_{Ld}), \quad \sigma_{q} = (\nu_{Lq} + \alpha_q i_{Lq})
\end{align*}
\]

and \( \alpha_d \) and \( \alpha_q \) are positive design constants, \( m_{di} \) and \( m_{qi} \) are estimates of \( m_d \) and \( m_q \), \( \delta_d > 0 \), \( \delta_q > 0 \), \( \phi_{di} > 0 \), \( \phi_{qi} > 0 \). Then \( \nu_{Ld} \) and \( \nu_{Lq} \) converge to zero, and \( m_d \) and \( m_q \) are bounded.

**Proof:** Let the Lyapunov function be defined as

\[
V(t) = \sigma_d^2 + \sigma_q^2 + \sum_{i=1}^{4} \alpha_d \phi_{di} m_{di}^2 + \sum_{i=1}^{4} \alpha_q \phi_{qi} m_{qi}^2
\]

which is bounded above by

\[
\sigma_d = (\nu_{Ld} + \alpha_d i_{Ld}), \quad \sigma_q = (\nu_{Lq} + \alpha_q i_{Lq})
\]

and \( \alpha_d \) and \( \alpha_q \) are positive design constants, \( m_{di} \) and \( m_{qi} \) are estimates of \( m_d \) and \( m_q \), \( \delta_d > 0 \), \( \delta_q > 0 \), \( \phi_{di} > 0 \), \( \phi_{qi} > 0 \). Then \( \nu_{Ld} \) and \( \nu_{Lq} \) converge to zero, and \( m_d \) and \( m_q \) are bounded.

\[
\begin{align*}
    m^*_d &= \left[ -\frac{\omega L_f}{\alpha_d} \frac{f_{d} L_f}{C_f \alpha_d} \frac{L_f i_{\text{dref}}}{C_f \alpha_d} \right]^T \\
    m^*_q &= \left[ \frac{\omega L_f}{\alpha_q} \frac{L_f i_{\text{qref}}}{C_f \alpha_q} \frac{L_f i_{\text{qref}}}{C_f \alpha_q} \right]^T
\end{align*}
\]

where the following equalities are used

\[
\begin{align*}
    \sum_{i=1}^{4} m_{di} p_{di} &= u_d - \sum_{i=1}^{4} \bar{m}_{di} p_{di}, \quad \sum_{i=1}^{4} m_{qi} p_{qi} &= u_q - \sum_{i=1}^{4} \bar{m}_{qi} p_{qi}
\end{align*}
\]

Substituting (19) and (20) into (17) yields

\[
\dot{V} = -2\left( \delta_d \frac{\alpha_d}{L_f} \sigma_d^2 + \delta_q \frac{\alpha_q}{L_f} \sigma_q^2 \right) \leq 0
\]

Integrating both sides of (20) gives

\[
\int_{0}^{\infty} \dot{V}(t) d\tau \leq -2\left( \delta_d \frac{\alpha_d}{L_f} \int_{0}^{\infty} \sigma_d^2 d\tau + \delta_q \frac{\alpha_q}{L_f} \int_{0}^{\infty} \sigma_q^2 d\tau \right)
\]

or equivalently

\[
V(\infty) - V(0) \leq -2\left( \delta_d \frac{\alpha_d}{L_f} \int_{0}^{\infty} \sigma_d^2 d\tau + \delta_q \frac{\alpha_q}{L_f} \int_{0}^{\infty} \sigma_q^2 d\tau \right)
\]

Thus, the above equation can be rewritten as

\[
\int_{0}^{\infty} \sigma_d^2 d\tau < \infty, \quad \int_{0}^{\infty} \sigma_q^2 d\tau < \infty
\]

which implies that \( \sigma_d, \sigma_q \in L_2 \). Since \( \nu \) is nonincreasing and is upper bounded as \( V(t) \leq V(0) \), this implies that \( \sigma_d \in L_{\infty}, \sigma_q \in L_{\infty}, m_{di} \in L_{\infty}, m_{qi} \in L_{\infty} \).

Meanwhile, from first two equations of (10), the \( \sigma_d \) and \( \sigma_q \) given in (16) can be rearranged as

\[
\begin{align*}
    \sigma_d &= (\nu_{Ld} + C_f \alpha_d \nu_{Ld}) \\
    \sigma_q &= (\nu_{Lq} + C_f \alpha_q \nu_{Lq})
\end{align*}
\]

Then, the transfer functions \( H_d(s) \) from \( \sigma_d \) to \( \nu_{Ld} \) and \( H_q(s) \) from \( \sigma_q \) to \( \nu_{Lq} \) are given by the following strictly positive functions:

\[
H_d(s) = \frac{1}{(1 + C_f \alpha_d s)}, \quad H_q(s) = \frac{1}{(1 + C_f \alpha_q s)}
\]

Therefore, by (24) it can be concluded that \( \nu_{Ld} \) and \( \nu_{Lq} \) converge to zero.

**Remark 1:** This remark discusses how the controller gains are chosen. The adaptive gains \( m_d \) and \( m_q \) are incorporated in the compensation control terms \( u_{fd} \) and \( u_{fq} \) as depicted in (14). To realize the fast convergence and transient response, the adaptive gains are tuned to large values. Since these adaptive gains are inversely related to \( \phi_{di} \) and \( \phi_{qi} \), the smaller values selected for \( \phi_{di} \) and \( \phi_{qi} \), the more likely to result in larger values of the adaptive gains. On the other hand, with the feedback terms \( u_{bq} \) and \( u_{bc} \) given in (14), \( \sigma_d \) and \( \sigma_q \) are...
further defined in (25), and these feedback terms can be regarded as a PD controller. In this context, the control parameters \( \alpha_d, \alpha_q, \delta_d, \) and \( \phi_q \) can be decided based on the tuning rule of \([25]\). Finally, the parameters \( \alpha_d, \alpha_q, \delta_d, \) and \( \phi_q \) can be tuned by the following procedure: 1) By utilizing the tuning rule of \([25]\), the parameters \( \alpha_d, \alpha_q, \delta_d, \) and \( \delta_q \) are tuned; 2) Set quite large values for \( \phi_d \) and \( \phi_q \); 3) Reduce \( \phi_d \) and \( \phi_q \) by a small amount; 4) If the acceptable transient performance is attained by current control parameters, then it is done. Otherwise, return to step 3 above.

**Remark 2:** As shown in (14), the proposed voltage controller includes two parts: feedback terms and adaptive compensation terms. The function of the feedback terms is to stabilize the error dynamics of the system. On separate note, the adaptive compensation terms take into accounts not only parameter uncertainties but also noises. Therefore, the proposed control technique can attain good performance with the existence of parameter uncertainties and noises in practice.

Fig. 3 depicts the block diagram of the proposed adaptive voltage control scheme.

### IV. LOAD CURRENT OBSERVER DESIGN AND STABILITY ANALYSIS

In Fig. 3, it is clear that the proposed adaptive controller needs load current information. Using the current sensors to measure the load currents \( (L) \) makes the system more expensive and less reliable. In this section, a linear optimal load current observer is designed to accurately estimate load current information that can heavily affect the controller performance. Based on assumption 3 and first two equations of (6), a fourth-order dynamic model can be obtained as follows:

\[
\dot{x} = Ax + Bu
\]

where

\[
x = \begin{bmatrix} i_{ld} \\ i_{lq} \\ v_{ld} \\ v_{lq} \end{bmatrix}, \quad A = \begin{bmatrix} 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ -1/C_f & 0 & 0 & \omega \\ 0 & -1/C_f & -\omega & 0 \end{bmatrix}, \quad B = \begin{bmatrix} 0 & 0 \\ 0 & 0 \\ 1/C_f & 0 \\ 0 & 1/C_f \end{bmatrix}, \quad u = \begin{bmatrix} i_{ld} \\ i_{lq} \end{bmatrix}
\]

Then, the load current observer model can be represented as

\[
\dot{x} = Ax + My - MC\hat{x} + Bu
\]

\[
y = Cx
\]

\[
\hat{i}_{ld} = \begin{bmatrix} \hat{i}_{ld} \\ \hat{i}_{lq} \end{bmatrix} = C_T\hat{x}
\]

where \( \hat{i}_{ld} \) and \( \hat{i}_{lq} \) are estimates of \( i_{ld} \) and \( i_{lq} \), \( M \in R^{4 \times 2} \) is an observer gain matrix, and

\[
\dot{x} = \begin{bmatrix} \dot{i}_{ld} \\ \dot{i}_{lq} \\ \dot{v}_{ld} \\ \dot{v}_{lq} \end{bmatrix}, \quad C = \begin{bmatrix} 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \\ 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \end{bmatrix}
\]

Fig. 4 illustrates the block diagram of the proposed load current observer.

Next, the error dynamics of the load current observer can be obtained as follows:

\[
\dot{\hat{x}} = (A - MC)\hat{x}
\]

**Theorem 2:** Consider the following algebraic Riccati equation (ARE)

\[
AP + PA^T - PC^T R^{-1} CP + Q = 0
\]

where \( Q \in R^{4 \times 4} \) is a symmetric positive semidefinite matrix, \( R \in R^{2 \times 2} \) is a symmetric positive definite matrix, and \( P \in R^{4 \times 4} \) is a solution matrix. Also, assume that the load current observer gain matrix \( M \) is given by

\[
M = PC^T R^{-1}
\]

Then, the estimation error converges exponentially to zero.

**Proof:** Let us define the Lyapunov function as

\[
V_o(\hat{x}) = \hat{x}^T \hat{x}
\]

where \( X = P^T \). Its time derivative along the error dynamics (29) is given by

\[
\dot{V}_o(\hat{x}) = \frac{d}{dt} \hat{x}^T \hat{x} = 2\hat{x}^T \left( XA - XPC^T R^{-1} C \right) \hat{x}
\]

\[
= \hat{x}^T X \left( AP + PA^T - 2PC^T R^{-1} CP \right) \hat{x} \leq -\gamma^T XQX \hat{x}
\]

This implies that \( \dot{V} \) is exponentially stable.

**Remark 3:** The proposed fourth-order load current observer is the Kalman-Bucy optimal observer which minimizes the performance index \( E(\hat{x}^T \hat{x}) \) representing the expectation value of \( \hat{x}^T \hat{x} \) for the following perturbed model

\[
\dot{x} = Ax + Bu + d, \quad y = Cx + v
\]

where \( d \in R^l, v \in R^m \) are independent white Gaussian noise signals with \( E(d) = 0, E(v) = 0, E(dd^T) = Q, \) and \( E(vv^T) = R \).
Remark 4: By referring to [26], this remark details on how the observer gain matrix $M$ is determined. Normally, the observer performance is mostly influenced by the system model if the measurements are excessively noisy ($R$ large) and the input noise intensity is small ($Q$ small). On that note, $M$ is small. This leads to a slow observer as measured by the location of its eigenvalues. However, if the measurements are good and the input noise intensity is large, the observer relies on the measurement. In this case, $M$ is large, resulting in a fast observer with high bandwidth. Consequently, by assuming that the measurement is good, the fast observer is desirable. Lastly, the subsequent procedure summarizes the tuning process of the observer gain matrix $M$: 1) $Q$ and $R$ are set as identity matrices; 2) Gradually, increase $Q$ and decrease $R$, then calculate $M$ as in (30) and (31); 3) Unless the observer performance is satisfied, return to step 2 above. Otherwise, quit.

V. PERFORMANCE EVALUATION

In this section, simulations and experiments are made and various results are presented. To evaluate the performance of the proposed observer-based adaptive control system, two kinds of power levels (200 kVA class and 450 VA class) are studied because the 200 kVA unit is too high a power level to build in the laboratory. In this paper, simulations are performed by using Matlab/Simulink software and experiments are implemented on a prototype DGS test-bed with a TMS320F28335 DSP.

![Fig. 5. Overall block diagram of the proposed adaptive control system.](image)

Fig. 5 shows the schematic diagram of the proposed adaptive voltage control approach. As depicted in Fig. 5, the inverter currents ($I$) and load output voltages ($V_L$) are measured with sensors and then transformed to the quantities ($I_{dq}$, $V_{Ldq}$) in the synchronously rotating $dq$ reference frame, respectively. On the other hand, the load currents ($I_{ldq}$) can be estimated by using the proposed current observer. In this paper, a space-vector pulse-width modulation (SVPWM) technique is utilized to approximate the reference voltages and supply less harmonic voltages to the load. Simulations and experiments are accomplished to demonstrate the transient and steady state performances of the proposed control algorithm under the following four different cases:

- **Case 1**: Balanced resistive load (Transient behavior - 0% to 100%)
- **Case 2**: Balanced resistive load (Transient behavior - 100% to 0%)
- **Case 3**: Unbalanced resistive load (phase C opened)
- **Case 4**: Nonlinear load (A three-phase diode rectifier)

Fig. 6 illustrates a nonlinear load circuit that consists of a three-phase full-bridge diode rectifier, an inductor ($L_{load}$), a capacitor ($C_{load}$), and a resistor ($R_{load}$).

![Fig. 6. Nonlinear load circuit with a three-phase diode rectifier.](image)

A. 200 kVA Unit

Consider a 200 kVA DG unit and the system parameters are given in Table I.

| TABLE I | SYSTEM PARAMETERS OF A 200 kVA UNIT |
|---------|-----------------------------------|
| DGS rated power | 200 kVA |
| dc-link voltage ($V_{dc}$) | 600 V |
| Switching & sampling frequency | 4 kHz |
| Load output voltages ($V_{Lrms}$) | 220 V |
| Fundamental frequency ($f$) | 60 Hz |
| Output filter capacitance ($C_f$) | 500 µF |
| Output filter inductance ($L_f$) | 0.3 mH |

As shown in Table I, a three-phase $LC$ output filter is designed with $L_f = 0.3$ mH and $C_f = 500$ µF, and it has a cut-off frequency of 410.9 Hz. It is well known that the larger the values of $L_f$ and $C_f$, the better filter performance. However, large $L_f$ leads to higher cost and larger volume. Also, large $C_f$ results in larger capacitor current at no load besides higher cost. Therefore, there exists a trade-off when selecting $L_f$ and $C_f$.

In this case, the controller gains and observer gain matrix are selected as follows: $\alpha_d = \alpha_q = 0.1$, $\phi_{d0} = \phi_{q0} = 1000$, $\delta_d = \delta_q = 1000$, and

$$M = 10^4 \times \begin{bmatrix} -0.3162 & -0.0039 & 3.0955 & -0.0000 \\ 0.0039 & -0.3162 & -0.0000 & 3.0955 \end{bmatrix}^T$$

Note that these parameters are chosen through extensive simulation studies with the aforementioned procedures in Remark 1 and Remark 4.

Figs. 7 to 10 show the simulation results of the proposed control technique under Cases 1 to 4 for a 200 kVA unit, respectively. Each figure shows the waveforms of load voltages ($V_L$), inverter currents ($I$), load currents ($I_L$),
estimated load currents ($\hat{i}_l$), control inputs ($v_{id}, v_{iq}$), and load current error ($e_{ia} = i_{La} - \hat{i}_{La}$). In Figs. 7 to 9, a 0.726 Ω resistor is used for a balanced resistive load and an unbalanced resistive load. Also, to get the waveforms under nonlinear load in Fig. 10, the following values are chosen: $L_{load} = 0.3$ mH, $C_{load} = 4000$ μF, and $R_{load} = 1.2$ Ω. Figs. 7 and 8 show the transient performance under a balanced resistive load and the load voltage waveforms are only slightly distorted during the transients and return to steady state within 0.52 ms. Figs. 9 and 10 show the steady state performance under an unbalanced resistive load and a nonlinear load, respectively. In both figures, the voltage waveforms look quite sinusoidal throughout the time. In Figs. 7 through 10, it is seen that the proposed observer accurately estimates the load currents under four load scenarios.

Table II presents the steady state performance of the simulation results under four different loads for a 200 kVA unit. It can be observed from Table II that the steady state errors are smaller than 0.31% and the THDs of the output voltages are lower than 0.8% in all cases.

| Load Types                      | Load Output Voltages ($V_{me}$) | THD (%) |
|---------------------------------|---------------------------------|---------|
| Balanced resistive load         | $V_{La} \quad V_{Lb} \quad V_{LC}$ | 219.88 \quad 219.86 \quad 219.85 | 0.211 |
| Unbalanced A&B resistive load   |                                  | 220.17 \quad 219.94 \quad 219.65 | 0.208 |
| No load                         |                                  | 219.89 \quad 219.84 \quad 219.86 | 0.224 |
| Nonlinear load (Crest factor 1.37:1) |                                | 219.57 \quad 219.45 \quad 219.32 | 0.781 |

Fig. 7. Simulation results of the proposed control scheme under Case 1 for a 200 kVA unit (Balanced resistive load: 0% to 100%).

Fig. 8. Simulation results of the proposed control scheme under Case 2 for a 200 kVA unit (Balanced resistive load: 100% to 0%).

B. 450 VA Unit

To testify the performance of the proposed control algorithm, the power size is reduced to 450 VA in the laboratory. Accordingly, for comparison, the simulation and experimental results are illustrated in this subsection. Table III shows the system parameters of a 450 VA unit. As listed in Table III, a three-phase $LC$ output filter is chosen with $L_f = 10$ mH and $C_f = 6.67$ μF, and this filter has a natural frequency ($\omega_c$) of 3872 rad/s. In this case, the controller gains and observer gain matrices are chosen as follows: $\alpha_d = \alpha_q = 20$, $\phi_d = \phi_q = 100$, $\delta_d = \delta_q = 100$, and

Fig. 9. Simulation results of the proposed control scheme under Case 3 for a 200 kVA unit (Unbalanced resistive load: phase C opened).

Fig. 10. Simulation results of the proposed control scheme under Case 4 for a 200 kVA unit (Nonlinear load with crest factor 1.37:1).
\[
M = 10^4 \begin{bmatrix}
-0.1000 & -0.0022 & 1.7406 & -0.0000 \\
0.0022 & -1.0000 & -0.0000 & 1.7406
\end{bmatrix}^T
\]

Figs. 11 to 14 show the simulation results of the proposed control method under Cases 1 to 4 for a 450 VA unit, respectively. Figs. 15 to 18 show the experimental results under the same conditions as Figs. 11 to 14, respectively. Each figure shows the waveforms of load voltages (V_L), inverter currents (I), load currents (I_L), estimated load currents (\hat{I}_L), control inputs (V_d, V_q), and load current error (e_L = I_L - \hat{I}_L). It is noted that a 80 Ω resistor is given as a balanced resistive load and an unbalanced resistive load, while the following RLC values are used in a nonlinear load circuit shown in Fig. 6: \( L_{load} = 10 \text{ mH}, C_{load} = 680 \mu \text{F}, \) and \( R_{load} = 200 \text{ Ω} \).

**TABLE III**

| SYSTEM PARAMETERS OF A 450 VA UNIT |
|-----------------------------------|
| DG bitterness rated power (V_d)   | 450 VA |
| dc-link voltage (V_d)             | 280 V  |
| Switching & sampling frequency    | 5 kHz  |
| Load output voltage (V_L, rms)    | 110 V  |
| Fundamental frequency (f)         | 60 Hz  |
| Output filter capacitance (C)     | 6.67 μF |
| Output filter inductance (L)      | 10 mH  |

Figs. 11 and 12 show the simulation results of the transient performances under a balanced resistive load. In these figures, the load voltage waveforms are slightly dented during the transients and are resumed to steady state within 0.5 ms. Meanwhile, the experimental results of Figs. 15 and 16 show that the load voltages are restored to steady state within a short time of 0.6 ms.

Figs. 13, 14, 17, and 18 show the steady state performances of the simulation and experimental results under an unbalanced resistive load and a nonlinear load, respectively. In these figures, the distortions of the voltage waveforms are not found. Based on Figs. 11 through 18, it can be seen that the load currents are precisely estimated by the proposed observer in case of four different loads.

Table IV summarizes the steady-state rms values and THDs of the load voltages in both simulation and experimental results under four different loads for a 450 VA unit. It can be observed from Table IV that the steady state errors are smaller than 0.6% (0.34% in simulations and 0.55% in experiments) and the THDs of the load voltage waveforms are lower than 1.2% (0.405% in simulations and 1.15% in experiments).

For further comparison, the feedback linearization for multi-input and multi-output (FL-MIMO) control scheme in [12] is also implemented in both simulation and experiment studies. Table V sums up the steady-state rms values and THDs of the load voltages in simulation and experimental results under four different loads for a 450 VA unit. In this table, the steady-state errors of the FL-MIMO method are as small as those of the proposed method: 0.30% in simulations and 0.70% in experiments. However, the THDs of the FL-MIMO scheme are much higher than those of the proposed scheme: 0.815%/0.405% in simulations and 2.31%/1.15% in experiments. Figs. 19 and 20 show the simulation and experimental results of the FL-MIMO control method under Case 4, respectively. In this paper, the results of Case 1, 2, 3 are not shown because of the limited space. It should be noted that the FL-MIMO control scheme does not need load current information, so the estimated load currents (\( \hat{I}_L \)) and the load current error (\( e_L = I_L - \hat{I}_L \)) are not available.

**TABLE IV**

| LOAD TYPES | LOAD RMS OUTPUT VOLTAGES (V) | THD (%) |
|------------|------------------------------|---------|
| Balanced resistive load | 109.72/109.72/109.72 | 0.094 |
| Unbalanced A&B resistive load | 109.90/109.75/109.52 | 0.080 |
| No load | 109.80/109.76/109.72 | 0.095 |
| Nonlinear load (Crest factor 1.59:1) | 109.52/109.51/109.52 | 0.405 |

**TABLE V**

| LOAD TYPES | LOAD RMS OUTPUT VOLTAGES (V) | THD (%) |
|------------|------------------------------|---------|
| Balanced resistive load | 109.67/109.63/109.72 | 0.46 |
| Unbalanced A&B resistive load | 109.85/109.64/110.22 | 0.43 |
| No load | 110.17/109.83/110.24 | 0.51 |
| Nonlinear load (Crest factor 1.52:1) | 109.87/109.39/109.64 | 1.15 |

From all simulation and experimental results, it can be concluded that the proposed control technique can attain exceptional voltage regulation performance such as more stable output voltage and lower THD than the FL-MIMO control method under various load types.
Fig. 11. Simulation results of the proposed control scheme under Case 1 for a 450 VA unit (Balanced resistive load: 0% to 100%).

Fig. 12. Simulation results of the proposed control scheme under Case 2 for a 450 VA unit (Balanced resistive load: 100% to 0%).

Fig. 13. Simulation results of the proposed control scheme under Case 3 for a 450 VA unit (Unbalanced resistive load: phase C opened).

Fig. 14. Simulation results of the proposed control scheme under Case 4 for a 450 VA unit (Nonlinear load with crest factor 1.59:1).
Fig. 15. Experimental results of the proposed control scheme under Case 1 for a 450 VA unit (Balanced resistive load: 0% to 100%). (a) Load output voltages ($V_L$) and inverter phase currents ($I_i$). (b) Load phase currents ($I_L$) and estimated load currents ($\hat{I}_L$). (c) Control inputs ($v_{di}, v_{dq}$) and load current error ($e_{LA}$).

Fig. 16. Experimental results of the proposed control scheme under Case 2 for a 450 VA unit (Balanced resistive load: 100% to 0%). (a) Load output voltages ($V_L$) and inverter phase currents ($I_i$). (b) Load phase currents ($I_L$) and estimated load currents ($\hat{I}_L$). (c) Control inputs ($v_{di}, v_{dq}$) and load current error ($e_{LA}$).
Fig. 17. Experimental results of the proposed control scheme under Case 3 for a 450 VA unit (Unbalanced resistive load: phase C opened). (a) Load output voltages ($V_L$) and inverter phase currents ($I_i$). (b) Load phase currents ($I_L$) and estimated load currents ($\hat{I}_L$). (c) Control inputs ($v_{id}$, $v_{iq}$) and load current error ($e_{LA}$).

Fig. 18. Experimental results of the proposed control scheme under Case 4 for a 450 VA unit (Nonlinear load with crest factor 1.52:1). (a) Load output voltages ($V_L$) and inverter phase currents ($I_i$). (b) Load phase currents ($I_L$) and estimated load currents ($\hat{I}_L$). (c) Control inputs ($v_{id}$, $v_{iq}$) and load current error ($e_{LA}$).

Fig. 19. Simulation results of the FL-MIMO control method under Case 4 for a 450 VA unit (Nonlinear load with crest factor 1.59:1).
In this paper, an adaptive voltage controller was proposed for a three-phase PWM inverter of standalone DGs. Load current information was estimated by a fourth-order optimal observer. The stability of the proposed controller and observer was analytically proven by applying Lyapunov stability theory. This adaptive control strategy can achieve more stable output voltage and lower THD than the FL-MIMO control scheme under sudden load change, unbalanced load, and nonlinear load. The effectiveness and feasibility of the proposed control strategy were verified through various simulation and experimental results.

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