Tracking Of Maximum Electrical Power for a Piezoelectric Energy Harvesting System

Behnam Dadashzadeh, Hadi Fekrmandi

Abstract: Recent global environmental challenges have urged researchers to work on renewable energy resources. One major category of these resources is piezoelectric materials. This paper presents dynamic modeling of a piezoelectric energy harvesting system and then presents two level methodology using artificial neural networks to reach its maximum power output. Simulation results show desirable performance of the system, which leads to output increasing and tracking of maximum power in a limited time.

Index Terms: Energy harvesting, maximum power, neural networks, piezoelectric.

I. INTRODUCTION

Nowadays, renewable energy resources have become a vital necessity regarding energy costs and environmental issues. Piezoelectric materials are energy transducers capable of mechanical energy to electrical and vice versa. Although these materials were discovered a century ago, their capability as an energy source has not yet been utilized properly [1].

Recent advances in design and fabrication of electronic devices have reduced electric power usage that can be reduced to microwatts in some applications. For this sake, researches have paid much attractions to energy resources independent of power transmission network [2].

It is estimated that a person by average walks 150 million steps in his life. Their periodic mechanical loads in streets sidewalks and also high periodic loads of automobiles in streets and highways can be used as a electric power source [3]. To profit piezoelectric materials in highways, they can be used along with a suitable circuit to save energy [1].

Minazara et al [4] used piezoelectric materials to convert mechanical vibrations in a bicycle to electric energy and proposed a suitable position to assemble it. Prasannabalaji et al [5] investigated energy harvesting from stairs while people ascending or descending it. Aditya et al [1] proposed utilizing this method for lighting streets and highways. Kong et al [6] presented a low power system for energy production using piezo and proposed some methods to reduce system losses. They analyzed energy loss sources to increase efficiency and then utilized a flyback converter to implement maximum power tracking. Several research works have presented modeling of piezoelectric energy harvesting systems [8].

In this paper, electrical energy harvesting using piezoelectric materials is modeled. It has two challenges of having low efficiency and fluctuant output. A DC-DC transducer model and the assumed load model are presented. Finally, a two-level algorithm for maximum power tracking of the array using artificial neural networks is presented. The proposed method improves both of the above-mentioned problems. In addition, advantages of this method compared to previous methods is investigated.

II. THE SYSTEM DESCRIPTION

Block-diagram of the overall system for energy harvesting is shown in Fig. 1 whose main components are as follows:

A. Piezoelectric Material

In direct piezoelectric effect, an electric voltage is produced as result of external strain, and in inverse piezoelectric effect, a displacement is generated as a result of applied electric voltage. Piezoelectric materials include piezo-ceramics and piezo-polymers. Mechanical and electrical behavior of piezoelectric material is modeled as (1) for inverse piezoelectric effect and (2) for direct piezoelectric effect [7].

\[ S = s^e T + d E S = s^e T + dE \]  \( (1) \)
\[ D = d T + e^T E S = s^b T + dE \]  \( (2) \)

In these equations, \( S \) is the strain matrix, \( s^e \) is the elasticity matrix at constant electric field, \( T \) is the stress vector, \( d \) is the piezoelectric coupling coefficients matrix, \( E \) is the electric field vector, \( D \) is the electric flux density vector, \( e^T \) is the dielectric matrix at constant mechanical strain. Direct and inverse piezoelectric effects are illustrated in Fig. 2.

![Fig. 1 diagram of electrical energy harvesting system](image)
The output power of a direct piezoelectric system is the multiplication of electric current and voltage that depends on different parameters including dimension and thickness of piezoelectric layers, number of layers, pressure variation or vibrations, temperature variations etc. In addition, I-V characteristic of piezoelectric materials is nonlinear. Total energy of piezoelectric materials includes elastic energy and electric energy as:

\[ dU_p = \frac{1}{2}ST + \frac{1}{2}DE \]  

in which, \( dU_p \) is the energy in unit volume of the piezoelectric material.

To reach the maximum efficiency of the system, maximum point of power characteristic curve has to be obtained and the system state should be maintained around this operation point.

B. DC-DC Converter

To maximize the output power and maintain voltage of piezoelectric arrays in the desired level and to avoid voltage oscillations, we use a power converter with high efficiency. Fig. 3 shows the structure of this converter that has been designed for switching frequency of 10 kHz. To reach this point we should have \( L > 68 \mu H \) and \( C > 147 \mu F \).

\[ D = \frac{V_o - V_i}{V_o} \]  

in which, \( V_i \) is the output voltage of piezoelectric material and \( V_o \) is the output voltage of the converter. By substituting optimal voltage \( V_{MPP} \) that is obtained from the tracking algorithm into (4), the optimal duty cycle \( D_{MPP} \) is derived that generates the maximum output power.

C. Load Model

Since the goal of the system in this paper is lightening of streets and local uses, it is appropriate to reserve the generated power on a battery and use the battery for lightening.
which, $\Delta G$ and $\Delta T$ are variation of vibration and stress in each iteration. Whenever they have more than 25% variation, the algorithm goes to level one and produces P-I curve again.

III. SIMULATION RESULTS

In the simulations of this paper, the array includes two piezoelectric circuits in series. The simulations have executed in two cases. In the first case, the variations of vibration and stress are relatively low while in the second case, their variations are high and the first level will be executed several times.

The artificial neural network is offline such that its bias vectors and weight matrices are calculated firstly by learning. Then the trained network is used for tracking. Estimation error has been assumed less than 0.0002. Also, in DC-DC converter in order to reduce the output current and voltage the parameter have been chosen as $L = 22 \text{ mH}$ and $C = 220\mu\text{F}$.

Percent of tracking error is defined as

$$\%e = \left(1 - \frac{\text{Output Power}}{\text{MPP Power}}\right) \times 100.$$  \hspace{1cm} (5)

**Case 1:**  In this case, the vibration frequency and input stress to piezoelectric arrays are assumed as shown in Fig. 6.

Figs. 7 to 9 show variation of the system output power, voltage, and current in case 1, respectively. According to these figures, the system output approach its maximum value and remain within its vicinity with small fluctuations.

Quantitative results of our maximum power tracking simulation and its comparison to P&O method [10] is summarized in table 1. It shows a good correlation of our results with that reference. Also, the output power of our system converges to the desired value in a very short period of time (0.04 s).

**Table 1** The values of MPP and ANN compared to P&O for case 1

| Time (s) | MPP Voltage (V) | MPP Current (A) | MPP Power (W) | ANN Power (W) | Error percent | P&O Power (W) |
|---------|----------------|----------------|---------------|---------------|---------------|---------------|
| $t < 0.04$ | 17.69 | 1.51 | 26.7 | 25.6 | 4 | 26 |
| $0.04 < t < 0.06$ | 19.51 | 3.01 | 58.72 | 58.71 | 0 | 59 |
| $0.06 < t < 0.08$ | 19.51 | 2.98 | 58.15 | 58.15 | 0 | 58 |
| $0.08 < t < 1$ | 19.51 | 3.04 | 59.30 | 59.30 | 0 | 59 |

**Case 2:** Variation of the vibration frequency and input stress to piezoelectric arrays in this case are shown in Fig. 10 and its output power, voltage and current are illustrated in Figs. 11, 12 and 13, respectively.
maximum power for the proposed algorithm compared to P&O method is shown in Table 2. According to these values the proposed method converges to the maximum power point very fast and it has good correlation with reference [10].

| Time (s) | MPP Voltage (V) | MPP Current (A) | MPP Power (W) | ANN Power (W) | Error percent | P&O Power (W) |
|---------|----------------|----------------|--------------|--------------|--------------|--------------|
| < 0.02  | 18.9           | 1.91           | 36.1         | 36.0         | 0.3          | 36           |
| 0.02 < t < 0.04 | 38.51       | 2.39           | 92.1         | 92.1         | 0            | 92           |
| 0.04 < t < 0.06 | 37.79       | 2.21           | 83.52        | 83.52        | 0            | 83           |
| 0.06 < t < 0.08 | 39.95       | 2.38           | 95.1         | 95.1         | 0            | 95           |
| 0.08 < t < 1    | 19.25       | 1.92           | 36.98        | 36.9         | 0.2          | 37           |

### IV. CONCLUSION

A two-level algorithm was proposed and simulated for maximum power tracking of a piezoelectric array for energy harvesting. The first level included measuring vibration and stress applied to piezoelectric material and obtaining the point of maximum power using P-I curve. The second level included a three-layer artificial neural network to search the real point of maximum power. The ANN uses output of the first level as the start point. The proposed algorithm was applied to an array of piezoelectric devices in two cases with low and high variations of vibration and stress. Simulation results show that the proposed algorithm tracks the point of maximum output power. In addition, they have a very good correlation with previously done P&O method.

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Behnam Dadashzadeh is an assistant professor of mechatronics engineering in the University of Tabriz since 2013. He received his BSc from the University of Tabriz in 2005 and his MSc and PhD from the University of Tehran in 2007 and 2013, all in Mechanical Engineering. He spent 7 months at the University of Calgary and 6 months at Oregon State University working on running robots as a visiting scholar during 2012/2013. His research interests include bipedal running control, mechatronics, mobile robots, and musculoskeletal biomechanics.

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