UDE Based Robust Control of Grid Tied Inverters

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DOI: 10.18100/ijamec.803545

1. Introduction

Grid-tied inverter (GTI) has a very important role in ensuring high quality current injected into the grid, have progressively been adopted in renewable energy systems [1], distributed generation, battery storage systems, and uninterruptible power supplies (UPSs), hybrid electric mobility, smart grids, etc. To obtain pure sine wave, an L grid filter is usually placed as an interface between inverter and power grid to reduce high frequency current harmonics[1]. However, when the grid filter varies, due to temperature, saturation etc., closed loop control performance may be adversely affected and output current is contaminated with harmonics caused by parametric uncertainties. In addition to, the unmodeled dynamics like disturbances and dead-time, can deteriorate the control performance and stability. For the current control of GTI, many strategies have been applied, such as proportional–integral (PI) control [2], proportional–resonant (PR) control [3], and repetitive control (RC) [4], etc. Although these controllers are good to eliminate steady state tracking error, they have lack about robustness.

For robustness concern of the GTI, there have been a number of conventional strategies, such as adaptive control [5], sliding mode control (SMC)[6], disturbance observer based control (DOB)[7], active disturbance rejection control (ADRC) [8] and uncertainty and disturbance estimator (UDE) based control[9]. Among those methods, UDE based control has become very attractive research point because of its gives a new solution for disturbance rejection and also its good reference tracking performance[10].

The main principle of the UDE based control scheme is estimating the lumped terms, including parametric uncertainties and disturbances by using state measurements and a low-pass filter with a appropriate
bandwidth. Then, estimated lumped disturbance could be adopted to the control action to reject against to disturbances. UDE based control doesn’t require an accurate model of the system and provides the decoupled control design for desired model an filter bandwidth [11]. Due to its superior performance, UDE based control scheme was applied to control of piezoelectric stages [12], wind turbines [13], motor drives [14] and power converters [15]. However, to our best knowledge, UDE-based control of GTI has been represented on few studies and it should be developed [16],[17].

In this paper, a UDE-based control scheme is forming PI controller for GTI with L filter is proposed. By using desired model and low-pass filter parameters, a simple and practical PI control approach converted from UDE based control is composed.

2. Modeling of the GTI

Fig.1 Grid Tied Inverter System

The schematic diagram of the grid-tied inverter system studied for this work is depicted in Fig. 1. The control of grid side currents and dc-link voltage of inverter represents the main purpose of this paper. Following [18], differential equations that describe the nonlinear affine form of the dynamics of dc-link voltage and grid-side inverter currents, in the synchronous rotating reference frame (SRF), can be defined as follows:

\[
L \frac{di_d}{dt} = - Ri_d + \omega L i_q + u_d - v_{gd} \tag{1}
\]

\[
L \frac{di_q}{dt} = - Ri_q - \omega L i_d + u_q - v_{gq} \tag{2}
\]

\[\frac{dV_{dc}}{dt} = - \frac{3}{2V_{dc}} [e_d i_d + e_q i_q] \tag{3}\]

Where, \( R \) and \( L \) are grid side filter inductance and resistance respectively and \( C \) represents dc-link capacitor. Angular frequency of the grid voltage is denoted as \( \omega \), which is obtained by phase locked loop (PLL) scheme. Grid voltage \( (e_d, e_q) \), control functions \( (u_d, u_q) \), and grid side currents \( (i_d, i_q) \), are all obtained in dq synchronous rotating frame.

Before designing the proposed UDE-based PI current control strategy, parameter uncertainties of grid currents channels of the dynamic model given in (1)-(3) must be derived as follows:

\[
\frac{di_d}{dt} = - \frac{R}{L} i_d + \omega L i_q + \frac{u_d}{L} - \frac{v_{gd}}{L} + d_{id} \tag{4}
\]

\[
\frac{di_q}{dt} = - \frac{R}{L} i_q - \omega L i_d + \frac{u_q}{L} - \frac{v_{gq}}{L} + d_{iq} \tag{5}
\]

Where the parameters \( R, L \) and \( C \) are nominal values, \( d_{id} \) and \( d_{iq} \) represents lumped disturbances and parametric variations.

3. Based PI Control Law

Dynamic equations of GTI system given in (4)-(5) can be rewritten as the following state space compact form:

\[
x(t) = Ax(t) + Bu(t) + Fx(t) + G + d \tag{6}
\]

With

\[
A = \begin{bmatrix} -\frac{R}{L} & 0 \\ 0 & -\frac{R}{L} \end{bmatrix}, \quad B = \begin{bmatrix} \frac{1}{L} & 0 \\ 0 & \frac{1}{L} \end{bmatrix}, \quad F = \begin{bmatrix} 0 & \omega \\ \omega & 0 \end{bmatrix}, \quad G = \begin{bmatrix} e_d \\ e_q \end{bmatrix}
\]

Where, \( x = [i_d \ i_q]^T \) is state vector, \( u = [u_d \ u_q]^T \) is control input functions, and \( d = [d_{id} \ d_{iq}]^T \) is parametric uncertainty and disturbance vector.

Assume, desired closed-loop dynamics of GTI system can be defined with reference model as

\[
x_d = A_dx_d + B_d c \tag{7}
\]

Where, \( x_d = [I_{dm} \ I_{qm}]^T \) is desired state vector, \( c = [I_d^r \ I_q^r] \) is the reference command input vector. \( A_d \) is desired state matrix, and \( B_d \) is desired control vector. In order to get desired specifications of the closed loop system, \( A_d \) and \( B_d \) matrix coefficients are selected to meet desired bandwidth. Decoupled first order system with grid current bandwidth \( \tau_{id} \) and \( \tau_{iq} \) can be described as

\[
A_d = \begin{bmatrix} -\tau_{id} & 0 \\ 0 & -\tau_{iq} \end{bmatrix} \quad \text{and} \quad B_d = \begin{bmatrix} \tau_{id} & 0 \\ 0 & \tau_{iq} \end{bmatrix}
\]

Control law \( u(t) \) is to ensure that \( x(t) \) asymptotically tracks the desired state \( x_d \) and, ideally tracking error, i.e., \( \epsilon(t) = x_d(t) - x(t) \)

converges to zero. One method to design a control law \( u(t) \) is to satisfy the condition for the error dynamics as

\[
\dot{\epsilon} = A_d \epsilon \tag{9}
\]

By equating (6) and (9) results in

\[
A_d x(t) + B_d c(t) - A x(t) - B u(t) - F x(t) - G = -d = A_d \epsilon \tag{10}
\]
Then, the control law can be obtained as

\[ u(t) = B^{-1}[A_dx + B_d c - Ax - Fx - G - d] \] (11)

Based on (6), uncertainty terms and external disturbances \(d\), which can be defined as

\[ d = z(t) - Ax(t) - Bu(t) - Fx(t) - G \] (12)

Following the control guidelines in [11], \(d\) can be approximated by

\[ \hat{d}(t) = d(t) + g_f(t) \] (13)

where "\*" is the convolution operator and \(g_f(t)\) is the strictly proper low-pass filter which is used to estimate lumped term \(d\). By replacing \(d(t)\) with \(\hat{d}(t)\), the equations (11) becomes

\[ u(t) = B^{-1}[A_dx + B_d c - Ax - Fx - G - d + g_f(t)] \] (14)

Then by substituting (12) into (14) results in

\[ u(t) = B^{-1}[A_dx + B_d c - Ax - Fx - G - \hat{d}(t)] \] (15)

Rearranging control function \(u(t)\) in (15) and taking the Laplace transform, the control law in s-domain can be derived in equation (16). Where \(G_f(s)\) is represented as the Laplace transform of \(g_f(t)\).

Frequency characteristic of \(G_f(s)\) filter needs to have large enough bandwidth, unity steady state gain and zero phase shift over the spectrum of uncertainty term \(d\). An accurate estimation of filter bandwidth is difficult due to deadtime of the inverter and control delay. Hence, first order low-pass filter is often preferred as follows

\[ G_f(s) = \frac{\tau_f}{s\tau_f + 1} \] (17)

Where, \(\tau_f = [\tau_{rd}, 0; 0 \tau_{rq}]\)is bandwidth of the \(G_f(s)\). By substituting (17) into (16) UDE based control action can be obtained as follows

\[ u(s) = B^{-1}[A_dx(s) + B_d c(s) - Ax(s) + Fx(s) + G] - K_pe(s) - K_i e(s)] \] (18)

Where,

\[ K_p = (\tau_f - A_d) \text{ and } K_i = \frac{\tau_f}{s\tau_f}A_d \]

Equation (18) shows that control law consist of PI regulator to make the tracking error zero, feedforward compensator for desired transients and negative model to cancel the known dynamics. From equation (18), PI parameters don’t need to have the exact filter parameters. This allows practically adjusting the two \(\tau_f\) and \(\tau_d\) bandwidths for the PI parameter design problem.

Overall control diagram is shown in Figure 2.

Substituting (16) into the laplace transform of (6), decoupled structure of the system response can be derived as follows:

\[ x(s) = \frac{\tau_d}{s + \tau_d}c + \frac{1}{s + \tau_f} \] (19)

It is clear that, the parameter design problem can be considered as adjustment of the two bandwidths, which are \(\tau_d\) and \(\tau_f\). For fixed value of \(\tau_d\), which is designed according to desired transient specifications, closed loop performance can be adjusted with \(\tau_f\) until to meet desired disturbance attenuation. For larger values of damping \(\tau_d\), the dominant poles move far from the real axis, which can cause to underdamped response with large overshoot.

Besides Fig. 3 shows the closed loop poles of the system (19) for the different bandwidth \(\tau_f\). We can observer that the dominant poles get close to the imaginary axis as the bandwidth of the filter increased. Thus, the time constant of \(G_f(s)\) filter should not choose too small to avoid instability.

4. Simulation Studies

In order to validate the proposed UDE based PI current control method in Fig 4, some of simulations studies were performed on RL filtered GTI system. Electrical parameters of the GTI system are given in table 1. Classical PI control strategy based on synchronous reference is selected as base controller to compare the proposed control approach as shown in Fig 5. Control parameters are summarized in table 2 according to same closed loop performance for feasible comparision. Bandwidth of outer PI loop for dc link voltage regulation was selected as 20 rad/s for both methods.
\[ u(s) = B^{-1} \left[ (A_d x(s) + B_d c(s)) \frac{1}{1-G_f(s)} - (A x(s) + F x(s) + G) - s x(s) \frac{G_f(s)}{1-G_f(s)} \right] \] (16)

Table 1 Electrical parameters for GTI system

| Parameter                  | Value     |
|----------------------------|-----------|
| Filter inductor L          | 10 mh     |
| Filter resistor R          | 3 ohm     |
| DC link capacitor C        | 1 mf      |
| Grid frequency             | 50 hz     |
| DC link voltage reference  | 500 V     |
| Phase-to-neutral voltage   | 100 V     |
| Switching frequency        | 10 khz    |

Table 2 Control parameters

| Parameter                  | Value     |
|----------------------------|-----------|
| \( \tau_{id}, \tau_{iq} \) | (1000, 1000) |
| \( \tau_{f_d}, \tau_{f_q} \) | (3000, 3000) |
| \( K_{p_i}, K_{i_i} \)     | (1, 1000)  |
| \( K_{p, dec}, K_{i, dc} \) | (1, 20)    |

Figure 4. Schematic diagram of GTI system with SRF

Figure 5. Schematic diagram of PI control with SRF

Dynamic response of the proposed control strategy was tested against to reactive power change applied to grid. Figure 6 shows active and reactive power references, besides figure 7 shows injected grid current and voltage. Active power is kept 1 kw whereas reactive power is suddenly changed from 500 Var to 0. As shown in Figure 7, proposed control strategy can response to the reactive power change with fast and zero steady state error.

Proposed and classical PI control performance was compared against to parametric mismatch shown in Fig 8. The simulation was conducted with deviation of L as %150L. It can be observed that a small steady state error with classical PI control and large overshoot. However parametric mismatch has very small effect on the performance of UDE based PI control as shown in Fig 9.

Figure 6. Active and reactive power reference variations

Figure 7. Injected current and grid voltage

Figure 8. Dynamic response of PI control with %150L

Figure 10. shows dynamic response I_q current under %50 L parametric mismatch. Classical PI control has small offset error while tracking reference current, whereas proposed control shows fast transient response and zero steady state error under parametric uncertainties.
This paper proposed a proportional–Integral (PI) control strategy based uncertainty and disturbance estimator (UDE) for three phase GTO systems. With the posposed control method, an improved disturbance attenuation was achieved. Deviations of grid filter parameters and operating conditions make hard to choose control parameter with satisfied performance. This paper presents a simplified parameter selection approach for PI control by using two parameters which are associated with bandwidths of desired closed loop and lumped uncertainty repsectively. Also this strategy enable two degree of freedom control. Simulation studies demonstrate that proposed controller performed better performance than conventional PI controller in terms of robustness and dynamic performance.

5. Conclusion

This paper proposed a proportional-Integral (PI) control strategy based uncertainty and disturbance estimator (UDE) for three phase GTO systems. With the proposed control method, an improved disturbance attenuation was achieved. Deviations of grid filter parameters and operating conditions make hard to choose control parameter with satisfied performance. This paper presents a simplified parameter selection approach for PI control by using two parameters which are associated with bandwidths of desired closed loop and lumped uncertainty respectively. Also this strategy enable two degree of freedom control. Simulation studies demonstrate that proposed controller performed better performance than conventional PI controller in terms of robustness and dynamic performance.

Author's Note

Abstract version of this paper was presented at 9th International Conference on Advanced Technologies (ICAT'20), 10-12 August 2020, Istanbul, Turkey with the title of “UDE Based Robust Control of Grid Tied Inverters”.

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