Control of PMSG based variable speed wind energy conversion system connected to the grid with PI and ADRC approach

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ABSTRACT

This paper presents the modeling and simulation of wind energy Conversion System using the Permanent Magnet Synchronous Generator (PMSG). The objectives are: to extract the maximum power of the wind speed by controlling the electromagnetic torque of the PMSG, to maintain constant the DC-link voltage despite the wind speed variations and to attain the unity power factor. In order to ensure a regulation with high performance and a good robustness against the internal and the external disturbances, a new control strategy called the Active Disturbance Rejection Control (ADRC) is used. Therefore, the Analysis and simulation of the ADRC and PI controllers are developed with MATLAB/Simulink software. The performance of these controllers is compared in term of references tracking, robustness and grid faults.

Keywords: ADRC controller, Linear extended state observer, MPPT, PI controller, PMSG, Wind turbine

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1. INTRODUCTION

In the recent years, wind energy became a famous clean energy source. The wind energy source systems are quickly growing thanks to the innovations and the researches in wind energy technology for electrical power production. Originally, a wind power source was used in standalone applications, however, wind systems connected directly to the grid [1]. Three types of generators are mainly usable in the wind energy conversion system: the squirrel cage induction generator (SCIG), doubly fed induction generator (DFIG) and Permanent Magnet Synchronous Generator (PMSG). For this work, the PMSG is used since it has small size, provides a self excitation and a high power density. In addition, the generator has the capacity to control reactive power, working also without the gearbox due to the higher number of poles for low speed operation [2, 3]. A configuration of a wind power system based on the PMSG is illustrated in Figure 1. The synchronous generator is connected to the grid through a back-to-back converter composed of the generator side converter and the grid-side converter [4].

The last years, many researches have appeared documenting the control of nonlinear systems related to wind energy. In the literature, proportional integral (PI) controllers based on field oriented control (FOC) is made up, this conventional technique presents some shortcomings, such as a low accuracy especially with the disturbance and nonlinearities according to dynamic characteristics of systems [5]. In order to overcome the disadvantages of the conventional PI controller which suffers from many limitations, a new control strategy called Linear Active Disruption Rejection Control (ADRC) founded by Han in 1995 is adopted to
remove disturbances affecting the facility [6,7]. This paper introduced an advanced method as the linear
active disturbance rejection control (ADRC) based on vector control, in order to achieve a maximum power
extraction, to maintain the DC bus at desired voltage value through the DC-link circuit, and to meet power
stable of the wind energy conversion system [8].
In detail, the suggested design techniques propose a comparison between PI and ADRC technique
which have been explored and used recently as a new technology for estimating and compensating
uncertainties and disturbances, is based on Extended state Observer (ESO) which is the main part of
the command. An evaluation is ensured to control the grid and generator side converter in order to regulate
the electromagnetic torque and the stator current of the PMSG. Simulation is made under
MATLAB/Simulink environment with a comparison between both commands. Results provided show clearly
the feasibility and the effectiveness of the proposed two techniques. They present also a good characterist,
excelsent output from the ADRC control comparing with PI command especially in terms of robustness and
reference tracking. The sequential work flow of this paper is as follows: In section 2, complete architecture of
the variable speed wind turbine conversion chain based on the PMSG has been described and the model has
been determined. Section 3 covers both PI and ADRC design, followed by a control of grid side converter,
bus voltage and generator side converter of the PMSG to maximize the production of the wind energy using
respectively both controllers in section 4 and 5. Simulation results and discussion are made in section 6.
Lastly, in section 7, a conclusion has been added to finalize the work.

Figure 1. Architecture of the variable speed wind turbine conversion chain based on the PMSG

2. MODELING OF THE WIND ENERGY CONVERSION SYSTEM BASED ON THE PMSG
2.1. Wind turbine
The turbine transforms the wind energy into a mechanical energy available on a wind turbine rotor
[9,10]. This power is expressed by:

$$ P_t = \frac{1}{2} C_p(\lambda, \beta) \rho \pi R^2 V^3 $$

Where $\rho$ is the air density, $R$ is the turbine radios and $V$ is the wind velocity. The power coefficient
$C_p$ is given by the following expression [11, 12]:

$$ C_p(\lambda, \beta) = C_1 \left( \frac{C_2}{\lambda_1} - C_3 \beta - C_4 \right) e^{\left( \frac{C_5}{\lambda_1} \right)} + C_6 \lambda $$

where:

$$\begin{cases}
\lambda = \frac{\Omega R}{V} \\
\lambda_1 = \frac{1}{1 + 0.085 \beta} - \frac{0.035}{1 + \beta^2}
\end{cases}$$

$C_1=0.5176, C_2=116, C_3=0.4, C_4=5, C_5=21, C_6=0.0068$
The maximum value of power coefficient \( C_p \) is \( C_{p_{\text{max}}} = 0.48 \), is achieved for pitch angle of rotor blades \( \beta \) is set to zero and \( \lambda_{\text{opt}} = 8.1 \), this point corresponds at the maximum power point tracking (MPPT). This model is translated by the following equation [21]:

\[
T_t = T_g + f_v\Omega_g + \frac{d\Omega_g}{dt}
\]  

(4)

Where \( T_g \) and \( T_{\text{em}} \) are respectively the mechanical and the electromagnetic torque of PMSG, \( J \) is the total moment of inertia and \( f_v \) is the friction coefficient of the turbine. The electromagnetic torque reference is determined by the following equation:

\[
T_{\text{em-ref}} = \frac{1}{2\Omega_{\text{opt}}^2} C_{p_{\text{max}}} \rho \pi R^5 \Omega^2
\]  

(5)

The Figure 2 represents the block diagram of the turbine model with MPPT strategy:

![Figure 2. Model of the turbine with MPPT strategy](image)

### 2.2. Model of converters

The generator side converter and grid side converter are controlled by the PWM control. These converters are represented by simple line voltages and the control signals \( S_i \) (6) [8].

\[
\begin{align*}
    v_a &= \frac{2S_1 - (S_2 + S_3)}{3} U_{dc} \\
    v_b &= \frac{2S_2 - (S_1 + S_3)}{3} U_{dc} \\
    v_c &= \frac{2S_3 - (S_2 + S_1)}{3} U_{dc}
\end{align*}
\]  

(6)

### 2.3. Modeling of the PMSG

The electrical voltages of the PMSG are given by the following equations:

\[
\begin{align*}
    v_{ds} &= R_s i_{ds} + L_d \frac{di_{ds}}{dt} + e_{ds} \\
    v_{qs} &= R_s i_{qs} + L_q \frac{di_{qs}}{dt} + e_{qs}
\end{align*}
\]  

(7)

Where the direct and the quadrature e.m.f components are expressed as follow:
\[
\begin{aligned}
\{ e_{ds} &= -\omega_s L_q i_{qs} \\
 e_{qs} &= \omega_s L_d i_{ds} + \omega_s \Phi_f 
\}
\end{aligned}
\] (8)

Where:
- \( L_d, L_q \) are d and q axis inductances (H);
- \( R_s \) is the stator resistance (Ω);
- \( i_{ds}, i_{qs} \) are the d and q axis machine current (A);
- \( \Phi_f \) is the flux linkage established by the permanent magnets in the stator windings (Wb);
- \( \omega_s \) is the angular frequency of the stator voltage (rad/s);

The expression of the electromagnetic torque is also expressed as a function of currents “(9)”:
\[
T_{em} = \frac{2}{p} \Phi_f i_{qs} + \frac{2}{p} (L_d - L_q) i_{ds} i_{qs}
\] (9)

p: Pairs of poles
These equations have been grouped to form a simplified model of PMSG as depicted in Figure 3.

![Figure 3. Simplified Theoretical Model of PMSG](image)

### 2.4. Modeling of RL grid filter and DC link

The electrical voltages of the grid-side are given in the (d, q) reference frame by the following equations:
\[
\begin{aligned}
\{ v_{md} &= R_s i_{dg} + L_g \frac{di_{dg}}{dt} + e_{dg} \\
v_{mq} &= R_s i_{qg} + L_g \frac{di_{qg}}{dt} + e_{qg}
\}
\end{aligned}
\] (10)

Where the direct and the quadrature e.m.f components are expressed as follow:
\[
\begin{aligned}
\{ e_{dg} &= -\omega_s L_d i_{qg} + i_{dg} \\
e_{qg} &= \omega_s L_q i_{dg}
\}
\end{aligned}
\] (11)

The active and reactive power supplied to the network can be expressed as:
\[
\begin{aligned}
\{ P_g &= v_{dg} i_{dg} + v_{qg} i_{qg} \\
Q_g &= v_{qg} i_{qg} - v_{dg} i_{dg}
\}
\end{aligned}
\] (12)

The grid voltage vector is oriented on d-axis, then:
\begin{align}
\begin{cases}
    v_{dg} = V_g \\
    v_{qg} = 0
\end{cases} \quad (13)
\end{align}

Thus:
\begin{align}
\begin{cases}
    P_g = v_{dg}.i_{dg} \\
    Q_g = -v_{dg}.i_{dg}
\end{cases} \quad (14)
\end{align}

The dc-link capacitor is interface between generator side converter and grid side converter; By neglecting the converters losses, the state equation of the dc-link voltage are expressed as follow:
\begin{align}
V_{dc} = \frac{1}{C} \int i_c \, dt = \frac{1}{C} \int (i_1 - i_2) \, dt \quad (15)
\end{align}

where
c: the DC link Capacitor.

3. SYNTHESIS OF PI AND ADRC CONTROLLERS

3.1. PI controller
The proportional-Integral controller is a combination of both actions proportional and integral in order to cancel the static error. The structure of a parallel PI controller system is represented in Figure 4 [10, 11, 16]. The derivative action of PID controller is excluded because it is characterized by amplifying the effect of system noise.

\begin{figure}[h]
\centering
\includegraphics[width=\textwidth]{figure4.png}
\caption{Structure of PI controller system for the PMSG}
\end{figure}

3.2. Linear ADRC controller
The mathematic expression of the first order for a time-varying dynamic system with single input \( u \) and single-output \( y \) is given as follow [13-16].
\begin{align}
\frac{dy}{dt} = f(y, d, t) + b_0 u \quad (14)
\end{align}

where:
f(y, d, t) : the effect of internal and external disturbances,
b_0 : Represents parameter gain to estimate .
d : The external disturbance.

The mathematical system as follow describes the process [19-21]:
\begin{align}
\begin{cases}
    \dot{x}_1 = x_2 + b_0 u \\
    \dot{x}_2 = f \\
    y = x_1
\end{cases} \quad (15)
\end{align}

\begin{align}
\begin{cases}
    \dot{\hat{x}}_1 = \hat{x}_2 + \beta_1 (y - \hat{\xi}_1) + b_0 u \\
    \dot{\hat{x}}_2 = \beta_2 (y - \hat{\xi}_2)
\end{cases} \quad (16)
\end{align}

Where the vector of the observer gain is expressed by:
\begin{align}
[\beta_1] = \begin{bmatrix} -2S_{ESO} \\ S_{ESO} \end{bmatrix} \quad (17)
\end{align}
The pole of the observer SESO is determined by the technique of placement of the poles. Therefore, the control plant can be ensured by a simple proportional $K_p$ (18). The input signal reference denoted $r$ [20, 21].

$$u_0 = K_p(r - y) = K_p(r - \hat{x}_1)$$

(18)

where:

$K_p = SCL$. 
SCL is the pole of desired closed loop.
SESO = 3~7 SCL
The only setting parameter is SCL.

Figure 5 represent the Structure of ADRC controller and the ESO.

![Figure 5. Structure of ADRC controller and the ESO](image)

4. CONTROL OF THE WIND SYSTEM BY PI CONTROLLER
4.1. Control of the generator side converter
The stator current is aligned on the q-axis (isd=0). Consequently, the electromagnetic torque is controlled by the q-axis current $i_{qs}$: The expression of the electromagnetic torque (9) become:

$$T_{em} = \frac{3}{2} p \Phi_i i_{qs}$$

(19)

Thus:

$$i_{qs-ref} = \frac{3}{2 p \Phi_i} T_{em-ref}$$

(20)

The open loop transfer function is:

$$G(s) = \left( k_p + k_i \right) \left( \frac{1}{R_s + s L_d} \right) = \frac{s + \frac{k_i}{k_p}}{\frac{R_s}{k_p} + s + \frac{k_i}{L_d}}$$

(21)

We use the method of poles compensation in order to eliminate the zero present on the transfer function [11, 12]. We pose:

$$\frac{k_i}{k_p} = \frac{R_s}{L_d}$$

(22)
Thus:

\[ G(s) = \frac{k_p + \frac{1}{\tau}}{s} = \frac{1}{\tau s} \]  

(23)

Where \( \tau \) is response time:

\[ \tau = \frac{l_d}{k_p} \]  

(24)

In closed loop we will have:

\[ F(s) = \frac{1}{1 + \tau s} \]  

(25)

Therefore, the parameters \( k_p \) and \( k_i \) of PI controller are given by:

\[
\begin{cases}
  k_p = \frac{1}{\tau} L_d \\
  k_i = \frac{1}{\tau} R_g
\end{cases}
\]  

(26)

We chose: \( \tau = 10 \) ms

4.2. Control of the grid side converter and DC link voltage

The open loop transfer function for the grid filter controlled by PI is:

\[ G(s) = \left( k_p + \frac{k_i}{\tau} \right) \left( \frac{1}{\hat{R}_g + j\omega_L} \right) \]  

(27)

Therefore, the parameters of PI controller are:

\[
\begin{cases}
  k_p = \frac{1}{\tau} L_g \\
  k_i = \frac{1}{\tau} R_g
\end{cases}
\]  

(28)

The deference between the active power generated by the wind generator \( P_m \) and the delivered power to grid \( P_g \) is stored in the DC-link capacitor, the structure of DC link voltage control is shown in Figure 6. The converters losses are neglected, therefore the equation of the dc-link voltage is expressed by:

\[ P_{DC} = P_m - P_g \]  

(29)

Figure 6. Structure of DC link voltage control

Figure 7 shows the PI control structure applied to the generator and grid side converter.
CONTROL OF THE WIND SYSTEM BY ADRC CONTROLLER

5.1. Control of the generator side converter

The currents of the stator are rearranged as follow:

\[
\begin{align*}
\frac{dl_{sd}}{dt} &= -\frac{R_s}{l_{sd}} I_{sd} + \omega_s \frac{l_{sq}}{l_{sd}} l_{sq} + \frac{1}{l_{sd}} V_{sd} \\
\frac{dl_{sq}}{dt} &= -\frac{R_s}{l_{sq}} I_{sq} - \omega_s \frac{l_{sd}}{l_{sq}} l_{sd} - \frac{1}{l_{sq}} \phi_f + \frac{1}{l_{sq}} V_{sq}
\end{align*}
\]  

(30)

These expressions can be written in the following form:

\[
\frac{dl_{sd}}{dt} = f(I_{sd}, d, t) + b_0 u(t)
\]  

(31)

Where:

\[
\begin{align*}
f(I_{sd}, d, t) &= -\frac{R_s}{l_{sd}} I_{sd} + \omega_s \frac{l_{sq}}{l_{sd}} l_{sq} \\
u(t) &= V_{sd} \quad \text{and} \quad b_0 = \frac{1}{l_{sd}}
\end{align*}
\]  

(32)

Where:

\[
\frac{dl_{sq}}{dt} = f(I_{sq}, d, t) + b_0 u(t)
\]  

(33)

In the same way:

\[
\begin{align*}
f(I_{sq}, d, t) &= -\frac{R_s}{l_{sq}} I_{sq} - \omega_s \frac{l_{sd}}{l_{sq}} l_{sd} - \frac{1}{l_{sq}} \phi_f \\
u(t) &= V_{sq} \quad \text{and} \quad b_0 = \frac{1}{l_{sq}}
\end{align*}
\]  

(34)

5.2. Control of the grid side converter and DC link voltage

5.2.1. The currents of the grid filter

The currents of the grid filter are rearranged as follow:

\[
\begin{align*}
\frac{dl_{dg}}{dt} &= -\frac{1}{l_{dg}} V_{dg} - \frac{R_g}{l_{dg}} I_{dg} + \omega_s \frac{l_{dq}}{l_{dg}} l_{dq} + \frac{1}{l_{dg}} V_{md} \\
\frac{dl_{dq}}{dt} &= -\frac{1}{l_{dq}} I_{dq} - \frac{R_g}{l_{dq}} I_{dq} - \omega_s \frac{l_{dg}}{l_{dq}} l_{dg} + \frac{1}{l_{dq}} V_{mq}
\end{align*}
\]  

(35)
These expressions can be written in the following form:

$$\frac{dl_d}{dt} = f(l_{dq}, d, t) + b_0 u(t)$$  \hspace{1cm} (36)

Where:

$$\begin{cases} f(l_{dq}, d, t) = -\frac{1}{Lg} V_{dq} - \frac{R_g}{Lg} i_{dq} + \omega_s \frac{l_d}{L_d} i_{dq} \\ u(t) = V_{nd} \quad \text{and} \quad b_0 = \frac{1}{Lg} \end{cases}$$  \hspace{1cm} (37)

Where:

$$\frac{dl_q}{dt} = f(l_{qg}, d, t) + b_0 u(t)$$  \hspace{1cm} (38)

In the same way:

$$\begin{cases} f(l_{qg}, d, t) = -\frac{1}{Lg} l_{qg} - \frac{R_g}{Lg} l_{qg} - \omega_s \frac{l_d}{L_d} l_{qg} \\ u(t) = V_{mq} \quad \text{and} \quad b_0 = \frac{1}{Lg} \end{cases}$$  \hspace{1cm} (39)

5.2.2. DC bus voltage control

The power on the DC link Capacitor can be given by:

$$P_{dc} = CV_{dc} \frac{dv_{dc}}{dt} = V_{dc}(i_1 - i_2)$$  \hspace{1cm} (40)

When the losses in the RL filter, the capacitor and in the two power converters are neglected, the powers across the DC bus is the difference between the generator power $P_m$ and grid power $P_g$:

$$P_{dc} = P_m - P_g$$  \hspace{1cm} (41)

Or:

$$CV_{dc} \frac{dv_{dc}}{dt} = V_{dc} i_1 - \frac{2}{3} V_{dc} l_{dq}$$  \hspace{1cm} (42)

$$\frac{dv_{dc}}{dt} = \frac{2V_{dc}}{c} i_1 - \frac{3V_{dc}}{c} i_{dq}$$  \hspace{1cm} (43)

Taking $A = V_{dc}^2$:

$$\frac{dA}{dt} = \frac{2\sqrt{A}}{C} i_1 - \frac{3V_{dc}}{C} i_{dq}$$  \hspace{1cm} (44)

Thus:

$$\begin{cases} f(A, d, t) = \frac{2\sqrt{A}}{C} i_1 \\ u(t) = i_{dq} \quad \text{and} \quad b_0 = -\frac{3V_{dc}}{C} \end{cases}$$  \hspace{1cm} (45)

Figure 8 shows the ADRC control structure applied to the generator and grid side converter.
6. SIMULATION RESULTS AND DISCUSSION

As shown in Figure 9, the simulation was carried out with MATLAB/SIMULINK in order to validate the control strategy studied in this work. The system consists of several blocks, for example the turbine model with its wind profile, the model inverters with its parameters, and controllers based on the ADRC in Figure 10 and PI approach. All parameters are given in Appendix. A random wind profile is shown in Figure 11. To extract the maximum wind energy of the wind speed, an MPPT strategy is adopted. In order to maintain the DC-link voltage constant, a control of the grid side converter is necessary. This technique is based on the control of direct and quadratic grid currents, and ensures also an exchange of active and reactive powers between the stator of the PMSG and the grid. To attain the unity power factor, it’s necessary to regulate the grid reactive power to its desired value. In Figure 12, the rotor speed track the profile of the wind which allows the efficiency of the MPPT strategy.
6.1. Test of reference tracking

In Figure 15, the reference direct current $I_{sd-ref}$ is fixed at zero in order to get the unity power factor for the generator side converter (GSC). Figures 13 to 17 illustrate respectively the electromagnetic torque, the stator current, reactive power of grid and DC link voltage variations obtained by using the PI control and the linear ADRC controller. These parameters converge and tracks perfectly as their references ($\text{Tem-ref}$, $I_{sd-ref}$, $I_{sq-ref}$, $Q_g-ref$ and $V_{dc-ref}$), but with a remarkable static error and an important response time for the PI controllers. We can also notice that the response of these parameters is slow and presents some overshoots shown clearly in zoom figures. The main importance factor to analyze the performance of the ADRC controllers, according to fast variation of the references is described in Table 1. It shows a very good performance for the tracking test with high accuracy against to wind speed variation, fast dynamic response, a good stability comparing to PI methods, simplicity of design and implementation.
Figure 14. q-axis stator current

Figure 15. d-axis stator current

Figure 16. Reactive power of grid

Figure 17. Vdc link voltage
Table 1. The system responses Parameters

| Type of Controller | PI    | ADRC |
|--------------------|-------|------|
| Rise Time (s)      | 0.1   | 0.06 |
| Settling time(s)   | 0.15  | 0.07 |
| Overshoot (%)      | 1     | 0    |
| Steady state error (%) | 5 | 0.02 |

6.2. Test of robustness

In order to investigate the robustness of the proposed ADRC control algorithm, two cases were selected in which we have changed the internal parameter of the PMSG. In the first one, an increase of the 30% of the stator resistance nominal value is applied. Figure 18 and 19 shows results of a comparison between ADRC and PI controllers. It can be noticed that the characteristics have been regulated to its reference value. ADRC controllers present excellent performances with good efficiency, smaller overshoot in the reactive power of grid and DC bus voltage, fast response and neglected oscillation in the regulation of the direct stator current to zero.

![Figure 18. Electromagnetic torque of PMSG](image)

![Figure 19. d-axis stator current](image)

In the second case, an increase of the stator inductance nominal value with 20% is applied. Figures 20 and 21 illustrate respectively, the electromagnetic torque, the direct stator current. It is noted that the whole characteristics is regulated to its set value, and this results obtained by ADRC controllers are clearly more efficient than the classical PI.

![Figure 20. Electromagnetic torque of PMSG](image)

![Figure 21. d-axis stator current](image)

6.3. Operation with grid faults (grid voltage dip)

A symmetrical grid voltage dip is applied to evaluate the performances of our wind energy system controlled by ADRC strategy. Figure 22 shows that the voltage sag occurs at t=5s. DC bus voltage is controlled by ADRC and PI algorithm. As shown in Figure 23, the amplitude voltage oscillations is very...
remarkable and present more than 1% comparing with the rated voltage in ADRC methods. If the voltage sag was very dip, a PI controller presents more oscillations which converge to unstable system.

Figure 22 Grid voltage

Figure 23 Vdc link voltage

7. CONCLUSION

In this work, a wind turbine conversion system using a PMSG connected to the grid were studied under two cases: normal and grid faults (voltage dip). To evaluate the performances of our system, a conventional PI and the active disturbance rejection control (ADRC) were compared. Simulations under Matlab/Simulink environment shows that the proposed ADRC methods gives very satisfactory characteristics with good efficiency, fast tracking and robustness for internal parametric variations of the PMSG, and external disturbances compared to the conventional PI controller even with the voltage dips effect.

APPENDIX

Table 2. PMSG Parameters [8]

| Parameter | Value |
|-----------|-------|
| Rated power | 6 kW |
| Pole pair number | 5 |
| Stator resistance $R_s$ | 0.425 $\Omega$ |
| Inductance $L_d$ | 0.0084 H |
| Inductance $L_q$ | 0.0084 H |
| Rotor Flux $\Phi_f$ | 0.433 Wb |
| Moment of inertia $J$ | 0.01197 kg.m² |
| DC link voltage $U_{dc}$ | 400 V |

Table 3. Turbine Parameters [8]

| Parameter | Value |
|-----------|-------|
| Density of Air | 1.225 kg.m³ |
| Total moment of inertia $J_T$ | 0.41 kg.m², 0.02 kg.m² |
| Optimal tip speed ratio $\lambda_{opt}$ | 8.1 |
| Maximal power coefficient $C_{p_{max}}$ | 0.48 |
| Turbine diameter $D$ | 2 m |

Table 4. Grid and DC link Parameters [8]

| Parameter | Value |
|-----------|-------|
| Capacitor of the dc-link | 0.41 kg.m², 10 mF |
| Grid frequency | 50 Hz |
| Grid inductance | 1 mH |
| Grid resistance | 0.01 $\Omega$ |

Table 5. ADRC Controller Parameters

| Parameter | Value |
|-----------|-------|
| Parameter gain $b_0=1/L_s$ | 119.0476 |
| controller gain $K_p=-S_{cl}$ | 400 |
| pole of ESO $S_{cl}=-3S_{cl}$ | -1200 |
| Extended state observer gains (ESO) $\beta_1=2400$ $\beta_2=1440000$ |

Table 6. PI Controller Parameters
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