IJISET - International Journal of Innovative Science, Engineering & Technology, Vol. 2 Issue 3, March 2015.
www.ijiset.com
ISSN 2348 – 7968

Dynamic Performance Improvement of Hydrogenerator Power System based on H^∞ MOCs Using Measurement Feedback

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Abstract
Design and analysis of the disturbance attenuation control of a 117 MVA hydrogenerator unit, supplying power through a set-up transformer and a transmission line to an infinity grid, is presented. A discrete multirate output controller (MOC) having multirate sampling period for three different state feedback measurements is designed, based on the H^∞ optimization criteria. The control is designed in order to achieve a discrete closed loop system of the open discrete linearized unit model. The performance of the new governor is shown by simulation results for two different operating cases of active and reactive power delivered at generator terminals.

Keywords: *Digital multirate control, H^∞-control, disturbance attenuation, hydrogenerator system.*

1. Introduction

The H^∞-control problem for discrete-time and sampled-data singlerate and multirate systems has successfully been treated in the past in [1-13]. Generally speaking, when the state vector is not available for feedback, the H^∞-control problem is usually solved in both the continuous and the discrete-time cases, by the use of dynamic measurement feedback approach. This approach, however, requires the solution of two coupled algebraic Riccati equations, which is, in general, a hand task on the basis of these two Riccati equations, it is possible to compute a dynamic controller that achieves the desired design requiments.

In [14-16] is presented for the solution of the H^∞-disturbance attenuation problem. This technique is based on multirate-output controllers and contain a multirate sampling period to each system measured output. The technique proposed in [15], in order to solve the sampled-data H^∞-disturbance attenuation problem relies mainly on the reduction, under appropriate conditions, of the original H^∞-disturbance attenuation problem, to an associated discrete H^∞-control problem for which a fictitious static state feedback controller is to be designed, even though some state variables are not available for feedback. Another key feature of the approach proposed in [15] is the ability of choosing, under appropriate conditions, the dynamics of the multirate-output controllers arbitrarily.

In [17], a successful governor based on H^∞ for MOC using a lot of state feedback measurements is presented.

In the present work, the design of the governor for the disturbance attenuation of an hydrogenerator power unit is developed, by using the same methodology as in the case of [17], but improved in the aspect of using much less state feedback measurements, for the same case study power unit. Feedback measurements consist of (a) the torque angle, (b) the machine speed and (c) the exciter output voltage. The linearized, continuous, 6th-order SIMO open-loop model representing a practical power system with impulse disturbances (composed of a 117 MVA hydrogenerator supplying power to an infinite grid through a proper connection network [19]) is used. The digital controller, which leads to the associated designed discrete closed-loop power system model, achieved enhanced dynamic stability characteristics. This is accomplished by applying the presented multirate-output controller technique, based on H^∞ optimization control.

2. Notation

i	instantaneous value of the current
v	instantaneous value of the voltage
v_o	infinite bus voltage
ψ	flux-linkage
R_a	stator resistance
R	resistance
x	reactance
δ	torque angle, in rad.
ω	generator speed (ω_o=synchronous speed) rad/sec.
H	inertia constant in sec.
i_t	generator terminal current
v_t	generator terminal voltage
E_{fd}	exciter output voltage
V_{ref}.	Reference voltage
P_t, Q_t	active and reactive power delivered at generator terminals

ISSN 2348 – 7968

K_e exciter amplifier gain
τ_e exciter amplifier constant, in sec.
x_{ad}, x_{aq} magnetizing reactance in d- and q-axis, respectively
x_{ld}, x_{lq} linkage reactances in d- and q-axis, respectively
R_T, X_T transformer resistance and reactance
R_L, X_L transmission line resistance and reactance
R_e, X_e external system resistance and reactance
Δ linearized quantity
o.p. operating point

Subscripts
d, q direct-and quadrature-axis quantities
f field winding quantities
D, Q d- and q-axis damper quantities

3. Overview of Relevant Mathematical Considerations

The general description of the controllable and observable continuous, linear, time-invariant, multivariable MIMO dynamical open-loop system expressed in state-space form is

$$\dot{x}(t) = Ax(t) + Bu(t)$$
$$y(t) = Cx(t) \qquad (1)$$

where: $\mathbf{x}(t) \in \mathbf{R}^n$, $\mathbf{u}(t) \in \mathbf{R}^m$, $\mathbf{y}(t) \in \mathbf{R}^p$ are state, input and output vectors respectively; and **A**, **B** and **C** are real constant system matrices with proper dimensions.

The associated general discrete description of the system (1) is as follows

$$\mathbf{x}(k+1) = \mathbf{A}\mathbf{x}(k) + \mathbf{B}\mathbf{u}(k)$$
$$\mathbf{y}(k) = \mathbf{C}\mathbf{x}(k) \qquad (2)$$

where: $\mathbf{x}(k) \in \mathbf{R}^n$, $\mathbf{u}(k) \in \mathbf{R}^m$, $\mathbf{y}(k) \in \mathbf{R}^p$ are state, input and output vectors respectively; and **A**, **B** and **C** are real constant system matrices with proper dimensions.

4. Overview of H$^\infty$-Control Technique Using Multirate-Output Controllers (MOCs)

Consider the controllable and observable continuous linear state-space system model of the general form

$$\dot{\mathbf{x}}(t) = \mathbf{A}\mathbf{x}(t) + \mathbf{B}\mathbf{u}(t) + \mathbf{D}\mathbf{q}(t), \quad \mathbf{x}(0) = \mathbf{0} \qquad (3a)$$
$$\mathbf{y}_m(t) = \mathbf{C}\mathbf{x}(t) + \mathbf{J}_1\mathbf{u}(t),$$
$$\mathbf{y}_c(t) = \mathbf{E}\mathbf{x}(t) + \mathbf{J}_2\mathbf{u}(t) \qquad (3b)$$

where: $\mathbf{x}(t) \in \mathbf{R}^{\mathbf{n}}$, $\mathbf{u}(t) \in \mathbf{R}^{\mathbf{m}}$, $\mathbf{q}(t) \in \mathbf{L}_2^d$, $\mathbf{y}_{\mathbf{m}}(t) \in \mathbf{R}^{p_1}$, $\mathbf{y}_{\mathbf{c}}(t) \in \mathbf{R}^{p_2}$ are the state, input, external disturbance, measured output and controlled output vectors, respectively. In eq. 3, all matrices have real elements and appropriate dimensions. Now follows a useful definition.

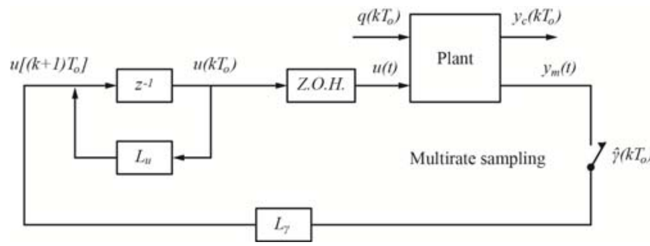

Fig. 1. Control of linear systems using MOCs.

Definition. For an observable matrix pair $(\mathbf{A},\mathbf{C})$, with $\mathbf{C}^T = [\mathbf{c}_1^T \ \ \mathbf{c}_2^T \ \ \cdots \ \ \mathbf{c}_{p_1}^T]$ and $\mathbf{c}_i$ with i=1, …,p_1, the *i*th row of the matrix **C**, a collection of p_1 integers $\{n_1, n_2, \cdots, n_{p_1}\}$ is called an *observability index vector* of the pair $(\mathbf{A},\mathbf{C})$, if the following relationships simultaneously hold

$$\sum_{i=1}^{p_1} n_i = n \quad ,$$

$$\operatorname{rank}\left[\mathbf{c}_1^T \ \cdots \ (\mathbf{A}^T)^{n_1-1}\mathbf{c}_1^T \ \cdots \ \mathbf{c}_{p_1}^T \ \cdots \ (\mathbf{A}^T)^{n_{p_1}-1}\mathbf{c}_{p_1}^T\right] = n$$

Next, the multirate sampling mechanism [14] is applied to system (3).

Assuming that all samplers start simultaneously at t = 0, a sampler and a zero-order hold with period T_0 is connected to each plant input $u_i(t)$, i=1,2,…,m, such that

$$\mathbf{u}(t) = \mathbf{u}(kT_0), \ t \in [kT_0, (k+1)T_0) \qquad (4)$$

while the ith disturbance $q_i(t)$, i=1,…,d, and the ith controlled output $y_{c,i}(t)$, i=1,…,p_2, are detected at time kT_0, such that for $t \in [kT_0, (k+1)T_0)$

$$\mathbf{q}(t) = \mathbf{q}(kT_0), \ \mathbf{y}_c(kT_0) = \mathbf{E}\mathbf{x}(kT_0) + \mathbf{J}_2(kT_0) \qquad (5)$$

The ith measured output $y_{m,i}(t)$, i=1,…,p_1, is detected at every T_i period, such that for $\mu = 0,...,N_i - 1$

$$y_{m,i}(kT_0 + \mu T_i) = \mathbf{c}_i\mathbf{x}(kT_0 + \mu T_i) + (\mathbf{J}_1)_i\mathbf{u}(kT_0) \qquad (6)$$

where $(\mathbf{J}_2)_i$ is the ith row of the matrix $\mathbf{J}_2$. Here $N_i \in \mathbf{Z}^+$ are the output multiplicities of the sampling and $T_i \in \mathbf{R}^+$ are the output sampling periods having rational ratio, i.e. $T_i = T_0 / N_i$ with i=1,…,p_1.

The sampled values of the plant measured outputs obtained over $[kT_0, (k+1)T_0)$ are stored in the N^*-dimensional column vector given by

$$\hat{\gamma}(kT_0) = [\, y_{m,1}(kT_0) \ \cdots \ y_{m,1}(kT_0 + (N_1 - 1)T_1)$$
$$\cdots \ y_{m,p_1}(kT_0) \ \cdots \ y_{m,p_1}[kT_0 + (N_{p_1} - 1)T_{p_1}]\,]^T \qquad (7)$$

(where $N^* = \sum_{i=1}^{p_1} N_i$), that is used in the MOC of the form

$$\mathbf{u}[(k+1)T_0] = \mathbf{L}_{\mathbf{u}}\mathbf{u}(kT_0) - \mathbf{L}_\gamma\hat{\gamma}(kT_0) \qquad (8)$$

ISSN 2348 – 7968

where $\mathbf{L}_u \in \mathbf{R}^{mxm}$, $\mathbf{L}_\gamma \in \mathbf{R}^{mxN^*}$.

The H^∞-disturbance attenuation problem treated in this paper, is as follows: Find a MOC of the form (4), which when applied to system (3), asymptotically stabilizes the closed-loop system and simultaneously achieves the following design requirement

$$\left\|\mathbf{T}_{\mathbf{q}\mathbf{y}_c}(z)\right\|_\infty \le \gamma \tag{9}$$

for a given $\gamma \in \mathbf{R}^+$, where $\left\|\mathbf{T}_{\mathbf{q}\mathbf{y}_c}(z)\right\|_\infty$ is the H^∞-norm of the proper stable discrete transfer function $\mathbf{T}_{\mathbf{q}\mathbf{y}_c}(z)$, from sampled-data external disturbances $\mathbf{q}\,(kT_0) \in \ell_2^d$ to sampled-data controlled outputs $\mathbf{y}_c(kT_0)$, defined by

$$\begin{aligned}\left\|\mathbf{T}_{\mathbf{q}\mathbf{y}_c}(z)\right\|_\infty &= \sup_{\mathbf{q}(kT_0)\in l_2} \frac{\left\|\mathbf{y}_c(kT_0)\right\|_2}{\left\|\mathbf{q}(kT_0)\right\|_2} \\ &= \sup_{\theta\in[0,2\pi]} \sigma_{max}\left[\mathbf{T}_{\mathbf{q}\mathbf{y}_c}(e^{j\theta})\right] = \sup_{|z|=1} \sigma_{max}\left[\mathbf{T}_{\mathbf{q}\mathbf{y}_c}(z)\right]\end{aligned} \tag{10}$$

where, $\sigma_{max}\left[\mathbf{T}_{\mathbf{q}\mathbf{y}_c}(z)\right]$ is the maximum singular value of $\mathbf{T}_{\mathbf{q}\mathbf{y}_c}(z)$, and where was used the standard definition of the ℓ_2-norm of a discrete signal $\mathbf{s}(kT_0)$

$$\left\|\mathbf{s}(kT_0)\right\|_2^2 = \sum_{k=0}^{\infty} \mathbf{s}^T(kT_0)\mathbf{s}(kT_0) \tag{11}$$

Our attention will now be focused on the solution of the above H^∞-control problem. To this end, the following assumptions on system (3) are made:

Assumptions:

a) The matrix triplets $(\mathbf{A},\mathbf{B},\mathbf{C})$ and $(\mathbf{A},\mathbf{D},\mathbf{E})$ are stabilizable and detectable.

b)

$$\text{rank}\begin{bmatrix}\mathbf{A} & \mathbf{D}\\ \mathbf{C} & \mathbf{0}_{p_1xd}\end{bmatrix} = n+d,\quad \text{rank}\begin{bmatrix}\mathbf{A} & \mathbf{B} & \mathbf{D}\\ \mathbf{C} & \mathbf{0}_{p_1xm} & \mathbf{0}_{p_1xd}\end{bmatrix} = n+m+d$$

c) $\mathbf{J}_2^T[\mathbf{E}\quad \mathbf{J}_2] = [\mathbf{0}_{m\times n}\quad \mathbf{I}_{m\times m}]$

d) There is a sampling period T_0, such that the open-loop discrete-time system model in general form becomes

$$\begin{aligned}\mathbf{x}[(k+1)T_0] &= \mathbf{\Phi}\mathbf{x}(kT_0) + \hat{\mathbf{B}}\mathbf{u}(kT_0) + \hat{\mathbf{D}}\mathbf{q}(kT_0)\\ \mathbf{y}_c(kT_0) &= \mathbf{E}\mathbf{x}(kT_0) + \mathbf{J}_2\mathbf{u}(kT_0)\end{aligned} \tag{12}$$

where $\mathbf{\Phi} = \exp(\mathbf{A}T_0)$, $(\hat{\mathbf{B}},\hat{\mathbf{D}}) = \int_0^{T_0}\exp(\mathbf{A}\lambda)(\mathbf{B},\mathbf{D})d\lambda$

is stabilizable and observable and does not have invariant zeros on the unit circle.

From the above it follows that the procedure for H^∞-disturbance attenuation using MOCs essentially consists in finding for the control law a fictitious state matrix $\mathbf{F}$, which equivalently solves the problem and then, either determining the MOC pair $(\mathbf{L}_\gamma, \mathbf{L}_u)$ or choosing a desired $\mathbf{L}_\mathbf{u}$ and determining the $\mathbf{L}_\gamma$. As it has been shown in [2], matrix $\mathbf{F}$ takes the form

$$\mathbf{F} = \left(\mathbf{I} + \hat{\mathbf{B}}^T\mathbf{P}\hat{\mathbf{B}}\right)^{-1}\hat{\mathbf{B}}^T\mathbf{P}\mathbf{\Phi} \tag{13}$$

where $\mathbf{P}$ is an appropriate solution of the following Riccati equation

$$\begin{aligned}\mathbf{P} &= \mathbf{E}^T\mathbf{E} + \mathbf{\Phi}^T\mathbf{P}\mathbf{\Phi} - \mathbf{\Phi}^T\mathbf{P}\hat{\mathbf{B}}\left(\mathbf{I} + \hat{\mathbf{B}}^T\mathbf{P}\hat{\mathbf{B}}\right)^{-1}\hat{\mathbf{B}}\mathbf{P}\mathbf{\Phi}\\ &+ \mathbf{P}\hat{\mathbf{D}}_\gamma\left(\mathbf{I} + \hat{\mathbf{D}}_\gamma^T\mathbf{P}\hat{\mathbf{D}}_\gamma\right)\hat{\mathbf{D}}_\gamma^T\mathbf{P}\ ,\ \hat{\mathbf{D}}_\gamma = \gamma^{-1}\hat{\mathbf{D}}\end{aligned} \tag{14}$$

Once matrix $\mathbf{F}$ is obtained the MOC matrices $\mathbf{L}_\gamma$ and $\mathbf{L}_\mathbf{u}$ (in the case where $\mathbf{L}_\mathbf{u}$ is free), can be computed according to the following mathematical expressions

$$\begin{aligned}\mathbf{L}_\gamma &= [\mathbf{F}\quad \mathbf{0}_{m\times d}]\tilde{\mathbf{H}} + \mathbf{\Lambda}\left(\mathbf{I}_{N^*\times N^*} - [\mathbf{H}\quad \mathbf{\Theta}_\mathbf{q}]\tilde{\mathbf{H}}\right)\\ \mathbf{L}_\mathbf{u} &= \left\{[\mathbf{F}\quad \mathbf{0}_{m\times d}]\tilde{\mathbf{H}} + \mathbf{\Lambda}\left(\mathbf{I}_{N^*\times N^*} - [\mathbf{H}\quad \mathbf{\Theta}_\mathbf{q}]\tilde{\mathbf{H}}\right)\right\}\mathbf{\Theta}_\mathbf{u}\end{aligned} \tag{15}$$

where $\tilde{\mathbf{H}}[\mathbf{H}\quad \mathbf{\Theta}_\mathbf{q}] = \mathbf{I}$ and $\mathbf{\Lambda} \in \mathbf{R}^{mxN^*}$ is an arbitrary specified matrix. In the case where $\mathbf{L}_u = \mathbf{L}_{u,sp}$, we have

$$\mathbf{L}_\gamma = [\mathbf{F}\quad \mathbf{L}_{\mathbf{u},sp}\quad \mathbf{0}_{m\times d}]\hat{\mathbf{H}} + \mathbf{\Sigma}\left(\mathbf{I}_{N^*\times N^*} - [\mathbf{H}\quad \mathbf{\Theta}_\mathbf{u}\quad \mathbf{\Theta}_\mathbf{q}]\hat{\mathbf{H}}\right)$$

where $\hat{\mathbf{H}}[\mathbf{H}\quad \mathbf{\Theta}_\mathbf{u}\quad \mathbf{\Theta}_\mathbf{q}] = \mathbf{I}$ and $\Sigma \in \mathbf{R}^{mxN^*}$ is arbitrary.

The resulting closed-loop system matrix $(\mathbf{A}_{cl/d})$ takes the following general form

$$\mathbf{A}_{cl/d} = \mathbf{A}_{ol/d} - \mathbf{B}_{ol/d}\mathbf{F} \tag{16}$$

where **cl** = closed-loop, **ol** = open-loop and **d** = discrete.

5. Modeling and Simulations of Hydrogenerator

The system under study, Fig. 2, is composed of a 117 MVA hydrogenerator connected to an infinite grid through a step-up transformer and a double-circuit transmission line. The data of the system of Fig. 2 [20] and various operating points being considered are given in Appendix B.

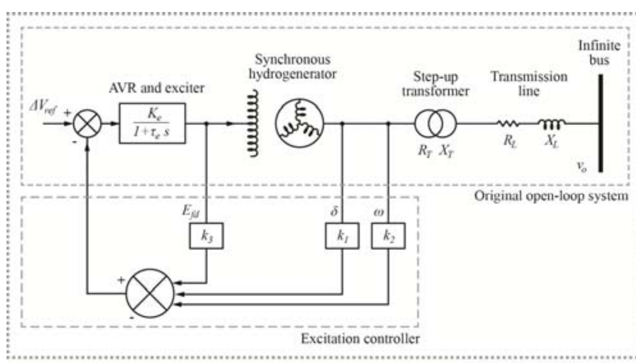

Fig. 2. Simplified representation of hydrogenerator system supplying power to an infinite grid.

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In such power system it is customary to start from the standard Park's non-linear equations [18] and after a process of linearization with respect to a nominal operating point (ie op #1) in this case [19-20] to represent the system in state space form as in eq.1:

$$\mathbf{x} = \begin{bmatrix} \Delta\delta & \Delta\omega & \Delta\Psi_f & \Delta\Psi_D & \Delta\Psi_Q & \Delta E_{fd} \end{bmatrix}^T$$

$$\mathbf{u} = \Delta\mathbf{V}_{\mathbf{ref.}},\ \ \mathbf{q} = \mathbf{u},\ \ \mathbf{y_m} = \begin{bmatrix} \Delta\delta & \Delta\omega & \Delta E_{fd} \end{bmatrix}^T,\ \ \mathbf{y_c} = \mathbf{x},$$

$$\mathbf{E} = \mathbf{I}_{6x6},\ \ \mathbf{J}_1 = \mathbf{0}_{6x1},\ \ \mathbf{J}_2 = \mathbf{0}_{6x1}.$$

The matrices **A**, **B**, **C** and **D** are given in Appendix B.

As it can be easily checked, Table 1, the above linear state space model is unstable, since matrix **A** has two unstable complex eigenvalues at $\lambda_{1,2}$ =0.0931±j7.7898. Note also that, the states ψ_f, ψ_D and ψ_Q are not measurable quantities.

The eigenvalues of the original continuous open-loop power system models and the simulated responses of the output variables $(\Delta\delta,\ \Delta\omega,\ \Delta E_{fd})$, are shown in Table 1 and Fig. 3, respectively.

Table 1. Eigenvalues of original open-loop power system models.

Original open-loop power system model	λ	-25.6139 0.0931+7.7898i 0.0931-7.7898i -8.1191+6.2036i -8.1191-6.2036i -6.4021

As it can be easily checked the above linear state space model is unstable, since matrix **A** has two untestable complex eigenvalues at $\lambda_{1,2}$=0.0931±j7.7898.

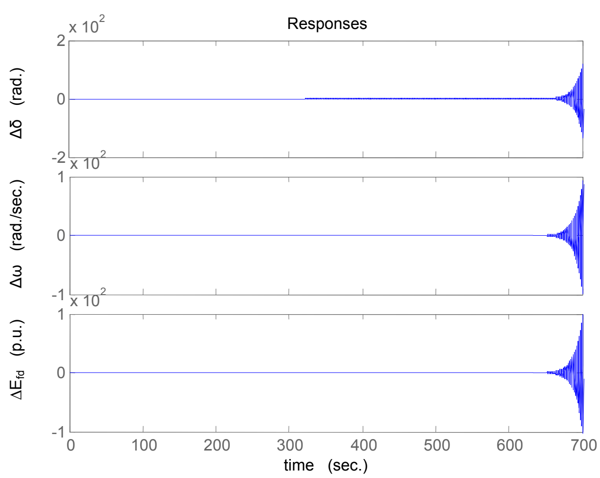

Fig.3. Responses of the output variables of the original continuous open-loop power system model to step input change: $\Delta V_{ref.}$=0.05 p.u.

The computed discrete linear open-loop power system model, based on the associated linearized continuous open-loop system model described in Appendix B of [20], is given below in terms of its matrices with sampling period T_0 = 0.6 sec.

$$\mathbf{A}_{ol/d} = \begin{bmatrix} 0.0231 & -01272 & 0.3562 & 0.3147 & 0.2002 & 0.0007 \\ 7.7655 & 0.0231 & 5.7998 & -0.3735 & 3.8922 & 0.0678 \\ -0.2046 & -0.0094 & -0.1403 & 0.0305 & -0.0682 & -0.0018 \\ -0.0569 & 0.0208 & -0.1036 & -0.0529 & -0.0410 & -0.0006 \\ 0.1264 & 0.0169 & 0.0546 & -0.0500 & 0.0574 & 0.0011 \\ 1.7000 & -1.0058 & 4.1128 & 2.5976 & 1.8849 & 0.0170 \end{bmatrix}$$

$$\mathbf{B}_{ol/d} = \begin{bmatrix} -2.6892 & 0.6720 & 1.7210 & 1.5366 & 0.5357 & -7.3228 \end{bmatrix}^T$$

$$\mathbf{C}_{ol/d} = \mathbf{C} = \begin{bmatrix} 1 & 0 & 0 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 1 \end{bmatrix},\ \ \mathbf{D}_{ol/d} = \mathbf{B}_{ol/d}$$

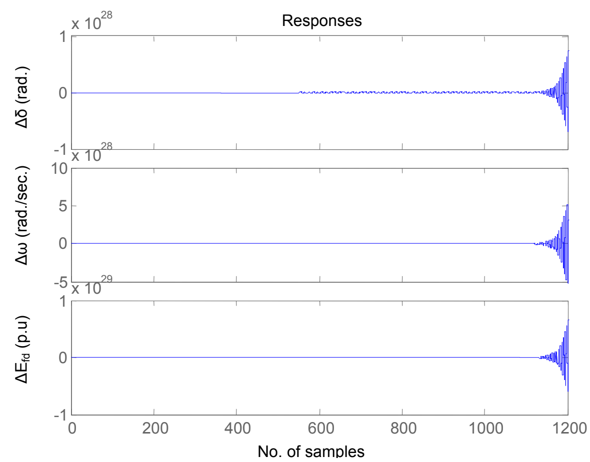

Fig. 4. Responses of Δδ, Δω, ΔE_{fd} of the discrete open-loop system model subject to step change ΔV_{ref}= 0.05 p.u.

Based on Fig. 1, the H^{∞}-control using MOCs (§4), and the computed discrete linear open-loop model of the power system under study, and the discrete closed-loop power system model were designed considering with γ = 20.5 the feedback gain computed as:

a) Model system for the case study o.p. #1:
   L_u = 2.3283e-09
   L_γ = [-0.1855 0.0907 -0.3847 -0.2225 -0.2212 -0.0019]

Then it is examined the applicability of the controller as it is designed above in a different operating point of the power system, op # 2: v_t = 1 p.u., P_t = 1.1 p.u. and Q_t = 0.5 p.u., in order to show if there is improvement of the dynamic behavior of the hydrogenerator system. The closed loop system is determined respectively using the feedback vector, as resulted from the application of $\mathbf{H}^{\infty}$ method to the 6^{th}-order open loop system, as determined at the operating point o.p. # 1.

The feedback gain computed as:

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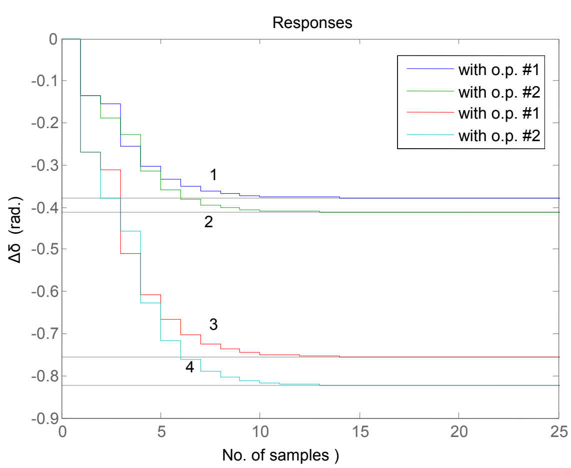
b) Model system for the case study o.p. #2 (and with feedback gain of the model o.p. #1)
$L_u = 2.3757e\text{-}11$
$L_\gamma = [-0.6093\ 0.0589\ -0.5309\ 0.1790\ -0.0450\ -0.0018]$

The numerical values of the matrices referring to the discrete closed-loop power system models of the above two cases are not included here due to space limitations.
The magnitude of the eigenvalues of the discrete original open-loop and designed closed-loop power system models are shown in Table 2. By comparing the eigenvalues of the designed closed-loop power system models to those of the original open-loop power system model the resulting enhancement in dynamic system stability is judged as being remarkable.

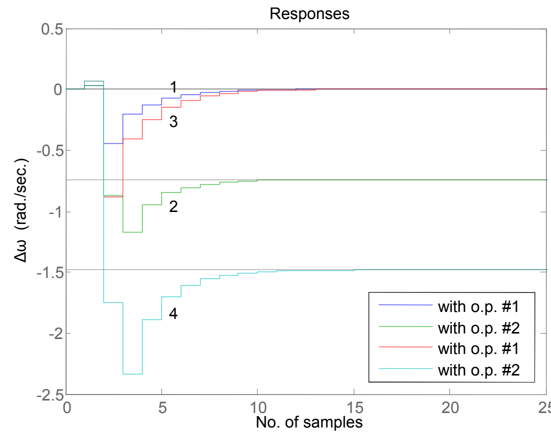
Table 2. Magnitude of eigenvalues of discrete original open-loop and designed closed-loop power system models.

Original open-loop power system model		$\lvert\lambda\rvert$	1.0575 1.0575 0.0215 0.0 0.0077 0.0077
Designed closed-loop power system model	for o.p. #1	$\lvert\hat{\lambda}\rvert$	0.5965 0.1258 0.1258 0.0433 0.0 0.0016
	for o.p. #2	$\lvert\hat{\lambda}\rvert$	0.5572 0.2057 0.2057 0.1032 0.0139 0.0066

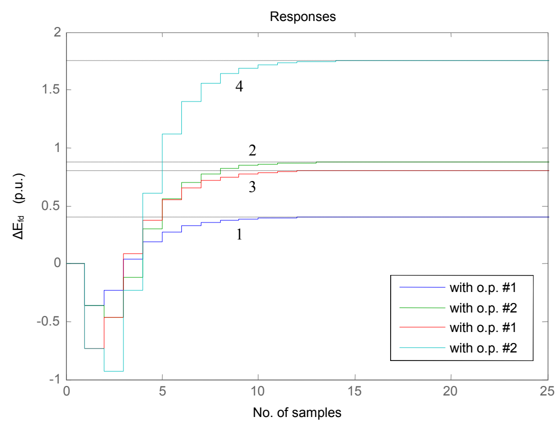
The responses of the output variables ($\Delta\delta$, $\Delta\omega$, ΔE_{fd}) of the designed closed-loop power system models for zero initial conditions and unit step input disturbance are shown in Fig. 5, respectively.



(A)



(B)



(C)

Fig. 5. A,B,C: Responses of $\Delta\delta$, $\Delta\omega$, ΔE_{fd}, of the discrete closed loop system:
1,3: for o.p. #1, for step input change $\Delta V_{ref.} = 0.05$ p.u. and $\Delta V_{ref.} = 0.10$ p.u. respectivly.
2,4: with o.p. #2, for step input change $\Delta V_{ref.} = 0.05$ p.u. and $\Delta V_{ref.} = 0.10$ p.u. respectivly.

From Fig. 5 it is clear that the dynamic stability characteristics of the designed discrete closed-loop system-models are far more superior than the corresponding ones of the original open-loop model, which attests in favour of the proposed H^∞-control technique.
It is to be noted that the solution results of the discrete system models, i.e. eigenvalues, eigenvectors, responses of system variables etc., for zero initial conditions were obtained by special m-files which were build, customized and executed in MATLAB®.

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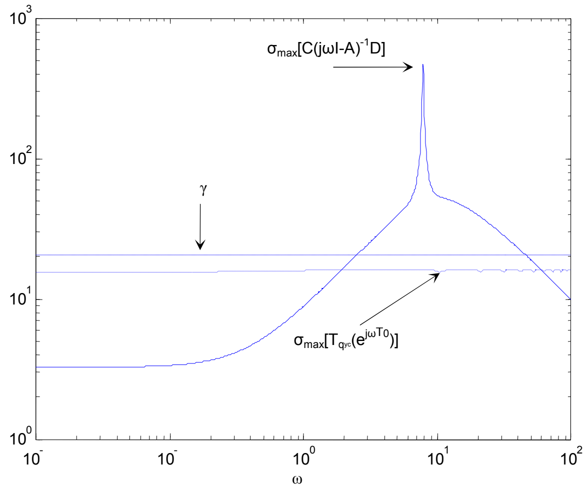

Fig. 6. The maximum singular value of $T_{qy_c}(z)$ over ω, for the o.p. #1

In Fig. 6, the maximum singular value of $T_{qyc}(z)$ is depicted, as a function of the frequency ω.
Clearly, the design requirement $\left\| T_{qy_c}(z)_\infty \right\| \le 20.6$, is satisfied. Moreover, as it can be easily checked the poles of the closed loop system, lie inside the unit circle. Therefore, the requirement for the stability of the closed-loop system is also satisfied.
Not that, the H^∞-norm of the open-loop system transfer function between disturbances and controlled outputs has the value $\left\| C(j\omega I - A)^{-1} B \right\|_\infty = 471.3$ while the minimum achievable disturbance attenuation level is γ_∞ =15.69

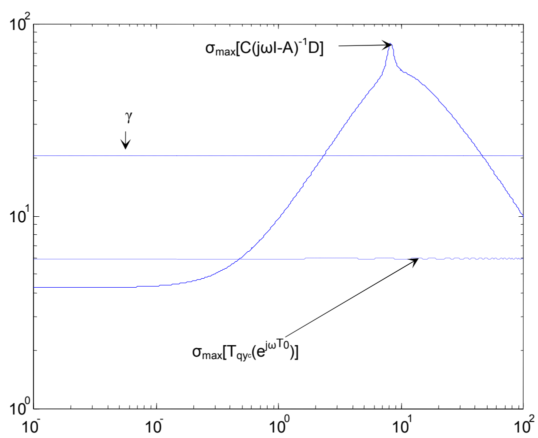

Fig. 7. The maximum singular value of $T_{qy_c}(z)$ over ω, for o.p. #2

In Fig. 7, the maximum singular value of $T_{qyc}(z)$ is depicted, as a function of the frequency ω.
Clearly, the design requirement $\left\| T_{qy_c}(z)_\infty \right\| \le 20.6$ is satisfied. Moreover, as it can be easily checked the poles of the closed loop system, lie inside the unit circle. Therefore, the requirement for the stability of the closed-loop system is also satisfied.
Not that, the H^∞-norm of the open-loop system transfer function between disturbances and controlled outputs has the value $\left\| C(j\omega I - A)^{-1} B \right\|_\infty = 79.5$ while the minimum achievable disturbance attenuation level is γ_∞ =5.99

6. Conclusions

A governor control system for an hydrogenerator power system has been designed using H^∞ optimization control and multirate output controllers (MOCs) via only a few state feedback measurements. The significance of the work is to systematically show how the H^∞ control theory combined with MOCs can be used for digital systems in order to overcome the limitation of many state feedback measurements and to design an implementable MOCs.

Appendix A

Numerical values of the system parameters (p.u. values on generator ratings, the time constants and the inertia constant of the generator and prime-mover are in sec.)**.**

Principal system data

MVA = 117	x_f = 0.221	AVR and exciter
kV = 15.75	x_D = 0.992	K_e =50.0
RPM = 125	x_Q = 0.551	τ_e = 0.05
x_d = 0.935	R_f = 0.0006	Transformer and
x_q = 0.574	R_D = 0.014	double-circuit
x_{ad} = 0.827	R_Q = 0.008	transmission line:
x_{1d} = 0.095	R_a = 0.002	R_e =0.015
x_{aq} =0.475	H = 3.0 in sec	X_e = 0.40
x_{1q} = 0.076		

Table 3. The operating points (o.p.) of the hydrogenerator system selected in this study

	v_t (p.u.)	P_t (p.u.)	Q_t (p.u.)
o.p. #1	1.0	1.1	0.5
o.p. #2	1.0	0.5	0.58

Appendix B

Numerical values of matrices **A**, **B,** **C** and **D** of the original continuous 6th-order system

$$\mathbf{A} = \begin{bmatrix} 0 & 1 & 0 & 0 & 0 & 0 \\ -72.654 & 0 & -19.926 & -46.354 & -41.242 & 0 \\ -0.066 & 0 & -0.641 & 0.493 & 0.003 & 0.228 \\ -3.586 & 0 & 11.494 & -19.56 & 0.13 & 0 \\ -2.051 & 0 & -0.032 & -0.074 & -7.867 & 0 \\ 125.886 & 0 & -176.154 & -409.789 & 264.883 & -20 \end{bmatrix}$$

$$B = \begin{bmatrix} 0 & 0 & 0 & 0 & 0 & 1000 \end{bmatrix}^T$$

$$\mathbf{C} = \begin{bmatrix} 1 & 0 & 0 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 1 \end{bmatrix} \qquad \mathbf{D=B.}$$

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