

Implementation of Control Network for PV Interconnected Three Phase Ups Systems Operating Under Highly Non Linear Loads

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Abstract- This paper presents the design of a PV interconnection system based three-phase uninterruptible power supply (UPS) systems that are operating under highly nonlinear loads. The classical high-performance sinusoidal pulse width modulation (SPWM) control method is quite effective in controlling the RMS magnitude of the UPS output voltages. However, it is not good enough in compensating the harmonics and the distortion caused specifically by the nonlinear currents drawn by the rectifier loads. This study proposes a new design strategy that overcomes the limitations of the classical RMS control. It adds inner loops to the closed-loop control system. Simulink is used to analyze, develop, and design the controller using the state-space model of the inverter. By the implementation of PV system based inverter we are analyzing the efficiency of proposed model of SPWM. Simulation performance is evaluated for a three-phase 10 kVA transformer isolated UPS under all types of load conditions. In conclusion, the simulation results demonstrate that the controller successfully achieves the steady-state RMS voltage regulation specifications as well as the total harmonic distortion and the dynamic response requirements of major UPS standards.

Index Terms- PV system, Inverter, nonlinear load, sinusoidal pulse width modulation (PWM) control, uninterruptible power supply (UPS).

INTRODUCTION

The increased use of rectifiers in critical loads employed by the information technologies, and medical and military equipment mandate the design of uninterruptible power supplies (UPS) with high-quality outputs [1]–[3].

The highly nonlinear currents drawn especially by high-power single-phase rectifier loads greatly distort the UPS outputs. The distorted UPS voltages cause

generation of low dc voltage at the output of the rectifier loads, which causes high current flow, increased power losses, and possibly the malfunction of the critical load or the UPS.

The distortion is resulted mainly by the voltage drop across the inductive element of the LC filter due to the non sinusoidal current at the output of the inverter [4]–[6]. In a UPS system the inverter is responsible for synthesizing sinusoidal voltages from a dc source through the pulse width modulation (PWM) of the dc voltage, for the selected switching frequency and the power level, an optimum filter with a smallest inductance can be designed, but the distortion cannot be completely avoided, and the regulations and the customer specifications may not be satisfied.

The solution to this problem is to design a proper inverter controller such that it generates a control signal with multiple functionalities. Moreover, the dead-beat control method [13] and the predictive and repetitive control methods [4]–[12] have been widely investigated and proposed among researchers. In addition, the iterative [12] and adaptive learning control methods [13], the H-infinity control method [4], [5], the feedback linearization method [6], and recently the multi sampled control approach to improve the control performance [7] have been studied and evaluated. High-quality output voltages with substantially low total harmonic distortion (THD) and fast dynamic response have been demonstrated with these methods. However, the disadvantages such as implementation complexity and the problems caused by highly unbalanced loading may limit some of the benefits of these methods. The stationary or synchronous-frame space-vector PWM (SVPWM)-based controllers are the primary choice of many researchers and the

applications currently used in industry, today [4], [7]. The controller performance is evaluated experimentally using a three-phase 10 KVA transformer isolated UPS. A THD equal to 3.8% at the output voltage is achieved even under the worst nonlinear load. The load consists of three single-phase rectifiers connected between each line and the neutral and absorbing power equal to the rated power of the UPS with a crest factor up to 3. In conclusion, the simulation results demonstrate that the proposed controller successfully achieves the steady-state RMS voltage regulation specification as well as the THD and the dynamic response requirements of major UPS standards.

However, the classical sinusoidal PWM (SPWM) method is still preferred by many manufacturers because of its implementation simplicity, easy tuning even under load, flexibility, and most importantly the advantages of controlling each phase independently. Although the classical SPWM method is quite effective in controlling the RMS magnitude of the UPS output voltages, it is not good enough in compensating the harmonics and the distortion caused specifically by the nonlinear loads [8], [9]. It uses a droop strategy to cancel the power transfer at the harmonic frequencies and therefore eliminate the distortion at the output voltage caused by the voltage drop across the inverter impedance due to the harmonic currents.. However, the significance of the proposed multi loop controller compared to other methods is as Follows:

[1] The execution time is less and allows higher switching frequencies. The complex control

algorithms take longer execution times and may limit the upper boundary of the switching frequency where you have actually some allowance for higher switching frequency operation [36]. Examples to the complex controllers are the repetitive, predictive, and harmonic droop controllers.

- [2] The cost is low. Some control algorithms require precise floating point calculations either because they depend on a precise model or they use frequency- dependent sensitive controller gains. In brief, the precision dictates use of high-performance floating point expensive microcontrollers.
- [3] The easy tuning even under load: Some are robust to this kind of tuning and some may not. This feature is preferred by some manufacturers. The easy tuning of the proposed method under load is verified during the experimental studies.
- [4] The flexibility: It means that you can modify your controller and optimize it according to the customer specifications at the time of installation or later in use. The optimization may include obtaining the lowest THD or the best tracking of the RMS value or the fastest dynamic response. So, the controller should be flexible anytime to do any of the aforementioned optimizations without significantly affecting the others. We have also verified this feature experimentally.
- [5] The scalability: It means that the controller is easy to design and tunable for any power level.

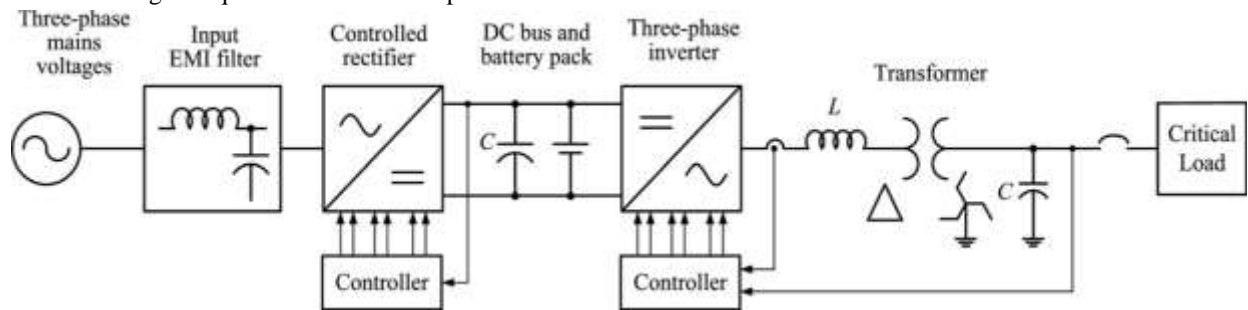


Fig.1. Single-line diagram of a typical three-phase four-wire transformer isolated UPS system

II. SYSTEM DESCRIPTION

The single-line diagram of a typical three-phase four-wire transformer isolated UPS system is given in Fig.1. The three phase thyristor based controlled

Rectifier converts the mains voltages into a constant dc and also provides standalone charge to the batteries. Then, a six-switch PWM voltage source inverter (VSI) creates balanced three-phase sinusoidal voltages across the load terminals at the

utilization frequency and magnitude. The LC low-pass filter removes the harmonics generated by the PWM switching. The Δ-winding of the transformer blocks the third harmonic currents at the inverter side, and the zigzag winding provides a neutral point and zero phase difference for the load-side voltages. The load can be a three-phase or a single phase load ranging from linear to nonlinear load with a crest factor up to 3. The UPS uses a digital controller implemented in a fixed-point DSP controller.

$$\begin{bmatrix} v_{12} \\ v_{23} \\ v_{31} \end{bmatrix} = \begin{bmatrix} (2L + L_{lk1}) + \frac{L_{lk2}L_{lk1}}{L_{lk1} + L_{lk2}} & -L & -L \\ -L & (2L + L_{lk1}) + \frac{L_{lk2}L_{lk1}}{L_{lk1} + L_{lk2}} & -L \\ -L & -L & (2L + L_{lk1}) + \frac{L_{lk2}L_{lk1}}{L_{lk1} + L_{lk2}} \end{bmatrix} \frac{d}{dt} \begin{bmatrix} i_{12} \\ i_{23} \\ i_{31} \end{bmatrix} + \frac{L_{lk2}}{L_{lk1} + L_{lk2}} \begin{bmatrix} i'_{12} \\ i'_{23} \\ i'_{31} \end{bmatrix} \quad (1)$$

III. ANALYSIS OF THE UPS INVERTER POWER STAGE

This section obtains the state-space model of the inverter stage of a three-phase UPS in order to design the controller for the inverter. The developed model is also used to study the controller performance for the lowest THD of the output voltage while maintaining the stability and a good dynamic response under all load conditions. The model is developed based on the circuit schematic given in Fig. 2.

As shown in Fig. 2, an insulated gate bipolar transistor (IGBT)-based three-phase inverter is used to produce pulse-width modulated voltages across the terminals labeled as 1, 2, and 3. Moreover, L is the external filter inductor used to reduce ripple at the line current, L_{lk1} is the primary side leakage, and L_μ is the magnetizing inductance of the transformer; then L_{lk2} is the secondary side leakage inductance, C_{is} is the filter capacitor, and finally R_l is the load

resistance (the prime symbol represents the parameters referred to the Δ-side of the transformer). Writing the voltage equations at the Δ-side of the transformer yields the following sets of equations for the line-to-line voltages across the inverter terminals, (1) as shown at the bottom of the page. Similarly, writing the current equations yields the following sets of equations for the derivative of the transformer secondary currents: side, and the zigzag winding provides a neutral point and zero phase difference for the load-side voltages. The load can be a three-phase or a single phase load ranging from linear to nonlinear load with a crest factor up to 3. The UPS uses a digital controller implemented in a fixed-point DSP controller.

$$\frac{d}{dt} \begin{bmatrix} i'_{12} \\ i'_{23} \\ i'_{31} \end{bmatrix} = \frac{L_{\mu}}{L'_{lk2} + L_{\mu}} \frac{d}{dt} \begin{bmatrix} i_{12} \\ i_{23} \\ i_{31} \end{bmatrix} - \frac{1}{L'_{lk2} + L_{\mu}} \begin{bmatrix} v'_{12} \\ v'_{23} \\ v'_{31} \end{bmatrix} \quad (2)$$

Likewise, the following sets of equations are obtained for the derivative of the referred output voltages based on the output parameters:

$$\frac{d}{dt} \begin{bmatrix} v'_{oa} \\ v'_{ob} \\ v'_{oc} \end{bmatrix} = \frac{1}{C'} \begin{bmatrix} i'_{12} \\ i'_{23} \\ i'_{31} \end{bmatrix} - \frac{1}{R'C'} \begin{bmatrix} v'_{oa} \\ v'_{ob} \\ v'_{oc} \end{bmatrix} \quad (3)$$

In addition, the inverter terminal voltages given in (1) can also be written in terms of the moving average of the switching functions, the modulation ratio m_a, and the dc bus voltage V_{dc}. The moving average of the switching functions is actually equal to the control signals that are applied to the comparators to generate the PWM signals for the inverter switches.

Consequently, the following sets of equations give the averaged model of the PWM generator and the three-phase inverter operation [37]:

$$\begin{bmatrix} v_{12} \\ v_{23} \\ v_{31} \end{bmatrix} = m_a \frac{V_{dc}}{2} \begin{bmatrix} 1 & -1 & 0 \\ 0 & 1 & -1 \\ -1 & 0 & 1 \end{bmatrix} \begin{bmatrix} u_{cont_a} \\ u_{cont_b} \\ u_{cont_c} \end{bmatrix} \quad (4)$$

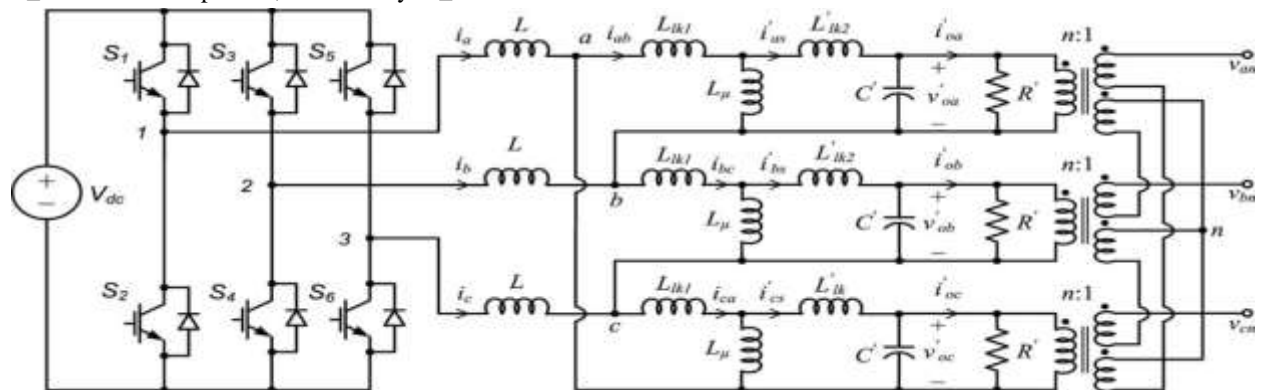


Fig.2. UPS inverter stage including the Δ-zigzag transformer equivalent circuit and the resistive load

Where $u_{cont\ abc}$ represents the control signals produced by the controller for each inverter leg. The modulation ratio m_a is equal to the peak of the control signal U_{cont} divided by the peak of the triangular carrier waveform V_{tri} . Although the parameter V_{tri} is always constant; V_{dc} may be changing depending on the grid conditions. It is relatively constant when grid is okay due to the controlled rectifier, but it is varying when grid is gone and the inverter works from the battery pack. These conditions are studied during the performance testing of the controller.

Deriving the derivative of the delta winding currents from (1) first, and then using them in (2), and also using (4) for the inverter terminal voltages, the following sets of the state-space equations are obtained. These equations are based on selecting the referred transformer secondary currents and the output voltages as the state variables and the control signals as the inputs

$$\frac{d}{dt} \begin{bmatrix} i'_{sa} \\ i'_{sb} \\ i'_{sc} \\ v'_{sa} \\ v'_{sb} \\ v'_{sc} \end{bmatrix} = \begin{bmatrix} 0 & 0 & 0 & A_{14} & A_{15} & A_{16} \\ 0 & 0 & 0 & A_{24} & A_{25} & A_{26} \\ 0 & 0 & 0 & A_{34} & A_{35} & A_{36} \\ \frac{1}{C} & 0 & 0 & -\frac{1}{RC} & 0 & 0 \\ 0 & \frac{1}{C} & 0 & -\frac{1}{RC} & 0 & 0 \\ 0 & 0 & \frac{1}{C} & 0 & 0 & -\frac{1}{RC} \end{bmatrix} \begin{bmatrix} i'_{sa} \\ i'_{sb} \\ i'_{sc} \\ v'_{sa} \\ v'_{sb} \\ v'_{sc} \end{bmatrix} + \begin{bmatrix} B_{11} & B_{12} & 0 \\ 0 & B_{22} & B_{23} \\ B_{31} & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} u_{cont,a} \\ u_{cont,b} \\ u_{cont,c} \end{bmatrix} \quad (5)$$

$$\begin{bmatrix} v_{an} \\ v_{bn} \\ v_{cn} \end{bmatrix} = \begin{bmatrix} 0 & 0 & 0 & 1/n & 0 & -1/n \\ 0 & 0 & 0 & -1/n & 1/n & 0 \\ 0 & 0 & 0 & 0 & -1/n & 1/n \end{bmatrix} \begin{bmatrix} i'_{sa} \\ i'_{sb} \\ i'_{sc} \\ v'_{sa} \\ v'_{sb} \\ v'_{sc} \end{bmatrix} + \begin{bmatrix} 0 & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} u_{cont,a} \\ u_{cont,b} \\ u_{cont,c} \end{bmatrix} \quad (6)$$

Defining the parameters L_1, L_2 , and L_3 as given next allows compact entries of the matrices A and B

$$L_1 = 2L + L_{lk1} + \frac{L'_{lk2}L_{\mu}}{L'_{lk2} + L_{\mu}}, L_2 = \frac{L_{\mu}}{L'_{lk2} + L_{\mu}}$$

$$L_3 = \frac{1}{L'_{lk2} + L_{\mu}}$$

TABLE I MAJOR UPS DESIGN SPECIFICATIONS

Output power	10 kVA, 0.85 power factor
Output voltage (RMS)	220 ±2.2 V line-to-neutral
Output voltage THD (%)	< 3% under the linear full load < 5% under the nonlinear full load
Transient response	Comply to the IEC standards

Using the aforementioned definitions together with L, the terms A_{ij} and B_{ij} become

$$A_{14} = A_{25} = A_{36} = -L_3 - \frac{L_2^2(L - L_1)}{(2L - L_1)(L + L_1)} \quad (7)$$

$$A_{15} = A_{16} = A_{24} = A_{26} = A_{34} = A_{35} = \frac{LL_2^2}{(2L - L_1)(L + L_1)} \quad (8)$$

$$B_{11} = B_{22} = B_{33} = \frac{L_2V_{dc}}{2V_{tri}(L + L_1)}$$

$$B_{12} = B_{23} = B_{31} = -B_{11} \quad (9)$$

We also need to determine the current through the external filter inductors at the inverter output (i_a, i_b , and i_c) since they are used as the feedback in the closed-loop control system. These currents are the transformer delta winding currents converted into the line currents. The following sets of equations yield the derivatives of the delta winding currents:

$$\frac{d}{dt} \begin{bmatrix} i_{ab} \\ i_{bc} \\ i_{ca} \end{bmatrix} = \begin{bmatrix} O_{11} & O_{12} & O_{13} \\ O_{21} & O_{22} & O_{23} \\ O_{31} & O_{32} & O_{33} \end{bmatrix} \begin{bmatrix} v'_{ga} \\ v'_{gb} \\ v'_{gc} \end{bmatrix} + \begin{bmatrix} G_{11} & G_{12} & 0 \\ 0 & G_{22} & G_{23} \\ G_{31} & 0 & G_{33} \end{bmatrix} \begin{bmatrix} u_{cont,a} \\ u_{cont,b} \\ u_{cont,c} \end{bmatrix} \quad (10)$$

The entries O_{ij} and G_{ij} in the aforementioned matrices are found using

$$O_{11} = O_{22} = O_{33} = -\frac{L_2(L - L_1)}{(2L - L_1)(L + L_1)} \quad (11)$$

$$O_{12} = O_{13} = O_{21} = O_{23} = O_{31} = O_{32} = \frac{LL_2}{(2L - L_1)(L + L_1)} \quad (12)$$

$$G_{11} = G_{22} = G_{33} = \frac{V_{dc}}{2V_{tri}(L + L_1)} \quad (13)$$

$$G_{12} = G_{23} = G_{31} = -G_{11}$$

The state-space model of the proposed inverter design is given in the next section after the design parameters are determined based on the given specifications.

IV. DESIGN OF THE INVERTER POWER STAGE

The specifications used for the design of the inverter power stage are given in Table I. The design process initially assumed a resistive load and used the classical methods and the rule of thumbs suggested in the power electronics literature. However, this design did not give a good performance under nonlinear loads. Then, it is improved via simulation studies until the desired performance is achieved for all load cases.

The improvements included determination of the proper dc bus voltage, switching frequency,

transformer parameters, and the element values of the LC filter.

Our preliminary design goal is to maintain the THD always below 4% under the worst case. The worst case is defined as the instant dc bus voltage is at the minimum while the UPS is delivering the rated nonlinear load.

The simulation studies have shown that if the controller goes into over modulation region, the THD specification cannot be satisfied. Therefore, the nominal dc bus voltage is maintained at 405 V when grid is okay and it is allowed to reduce down to 300 V when grid is gone and the UPS operates from the battery pack. One string of the battery pack consists of 30 pieces of 12 V lead-acid batteries connected in series.

Simulation studies, it has been realized that the output impedance of an inverter plays an important role in reducing the THD of the output voltage. And the results show that the THD of the voltage can be improved if the output impedance is reduced [5] or the impedance is modified to become even more capacitive in nature [6]. Our approach to design the LC filter is to start first with finding practically the smallest inductance value, and then finding the capacitance value based on filtering requirement of the switching frequency ripple at the output voltage. Generally, the inductance is selected based on the current ripple, size, and dynamic response criteria. Since we want the smallest inductance, we base our inductor design on the ripple requirement. The current through the inductor also flows through the IGBTs of the three-phase inverter at every switching cycle. So, based on our experience, allowing 30% ripple at the current is considered a good compromise between the size and the efficiency requirements.

More than 30% ripple allows smaller inductance but causes larger turn-off switching losses.

Hence, the inductance is calculated based on the fore mentioned ripple specification, and then the capacitance value is calculated in such a way that the LC filters produces 30 dB attenuation at the switching frequency. So, using the aforementioned criteria, the filter inductance is found as 1010 μH at the inverter side and the capacitor is 120 μF placed at the load side. The calculated inductance yields around 30% current ripple at the inverter line currents at the full linear load and a corner frequency of 352 Hz for the LC filter. As shown in Fig. 3, an external inductor equal to 30 μH is added at each line to arrive at the required filter inductance value. Finally, the test loads are designed as three different Y connected loads: the first one represents a linear light load at 338 W, the second one is the linear load at 8.5 kW, and the last one is the nonlinear rectifier load at 10 kVA. The nonlinear load, which consists of three full-bridge rectifiers connected between each phase and the neutral. The rectifier load resistor is selected as 33 Ω to dissipate total 6.6 kW equal to 66% of the rated three-phase output power, and the series input resistor is selected as 0.58 Ω to dissipate total 400 W equal to 4% of the rated output power. Additionally, the selected rectifier parameters generate a current waveform with a crest factor of 3 when tested with good mains voltages. The value of crest is important since the specification of products requested by many customers today require the UPS to handle loads up to 3 crest factor while allowing a THD no more than 5%. Finally, the schematic of the inverter with the parameter values optimized for all load conditions is shown in Fig. 3.

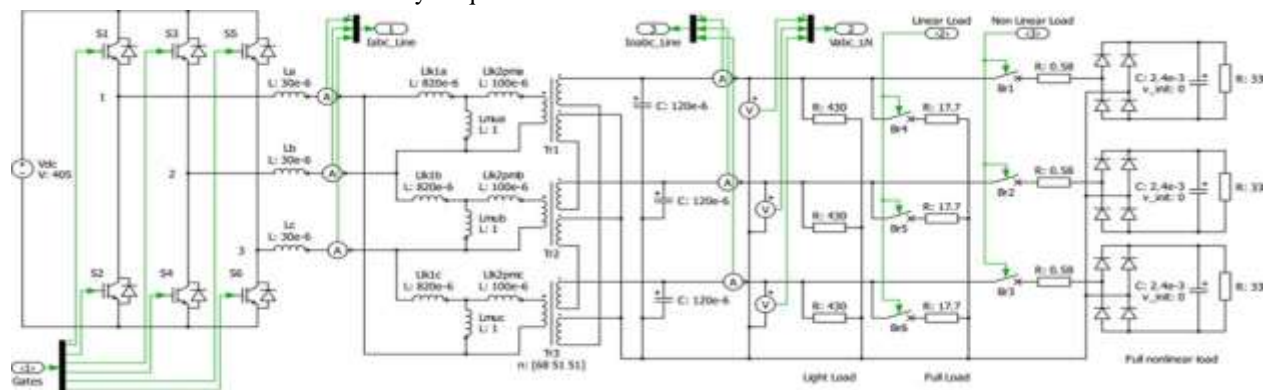


Fig.3. PLECS model of the designed inverter power stage including delta-zigzag transformer, the LC filter, the measurements, and the linear and nonlinear loads.

V.STATE-SPACE MODEL OF THE INVERTER POWER STAGE

The state-space model of the plant (three-phase inverter) is needed to develop and test the controller performance So, using $L = 30 \mu\text{H}$, $L_{\mu} = 1 \text{ H}$, $L_{lk1} = 820 \mu\text{H}$, $L_{lk2} = 100 \mu\text{H}$, $C_{\mu} = 202 \mu\text{F}$, $V_{dc} = 405 \text{ V}$, $V_{tri} = 2487$, $R_{\mu} = 10 \Omega$ for full load and $R_{\mu} = 255 \Omega$ for the light load case in (5) through (13), the state-space model of the plant is obtained as shown in Fig. 4. The peak of the carrier waveform is obtained based on the type of the selected DSP and the switching frequency. The details of the controller are discussed in the next section.

VI.CONTROLLER DESIGN

This section presents the design of the proposed inverter controller. The controller is based on the multiloop SPWM method as shown in Fig. 5, which is also shown as a block in Fig. 4. The controller topology is very similar to the classical state-feedback multiloop controllers [8], [9], except that all the loops are combined (instead of cascade connection) before they are applied to the PWM generator. This feature basically adds the relative benefits of each loop and creates a more effective multiloop strategy. In order to facilitate the understanding of the proposed controller, the reasoning behind the selected control topology can be explained as follows.

The control system shown in Fig. 5 consists of one outer voltage loop and three inner loops. The outer loop is the main voltage loop, which regulates the fundamental frequency component of the output voltage and its steady-state RMS value using a PI compensator; for that reason, it has slower dynamics. The first of the inner loops is the voltage reference feed forward loop which provides fast transient response but less benefit to the compensation of the harmonic distortions. The second inner loop is the voltage loop where the measured ac output voltages are instantaneously compared to the reference ac voltages created by the main loop and the error (Error1) is found; then the loop is compensated using a PD controller.

This loop is responsible for correcting the phase shift and improving the waveform quality of the output voltages. The simulation results confirm that the gain K_{p2} controls the THD of the voltages effectively and improves the waveform quality. The dynamic characteristic of this loop is relatively fast since there is no integrator. Actually, the fast dynamic with high gain is desired since it generates the corrective control actions to compensate for the distortion caused by the nonlinear currents, but this feature easily pushes the system into instability. One solution to this problem is to add a derivative control; however, it provides a minor help to stabilizing the system. The more effective solution is to add an ac current inner loop which provides the feedback about the voltage drop across the inductive

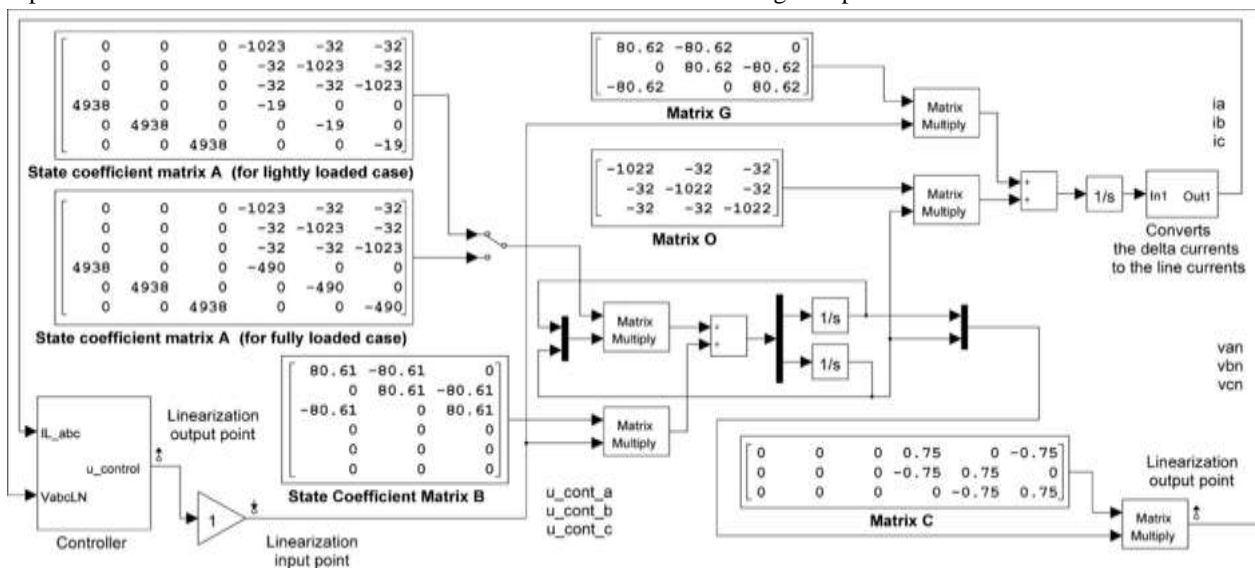


Fig. 4. State-space model of the inverter power stage (the plant) including the closed-loop control system and the controller built in Simulink

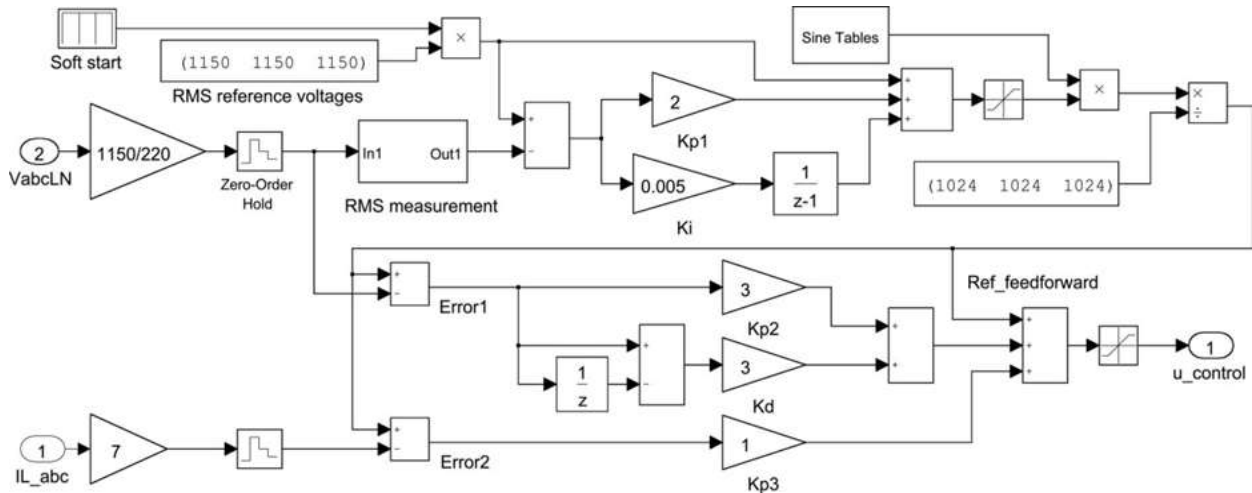


Fig.5. Simulink model of the proposed multiloop controller

Element of the LC filter, which makes the part of the compensation against the harmonic distortions at the voltage. In this loop, the measured inductor currents are instantaneously compared to the reference currents created by the main loop and the resulted error (Error2) is combined to the main control output after it is multiplied by the gain $Kp3$, as shown in Fig. 5. Our studies have shown that the ac current loop with the gain $Kp3$ stabilizes the control system effectively. In addition, the inductor currents that are measured for the closed-loop control are also used for overload protection and current limiting purposes. So, the cost of the current transformers is justified in this design.

The advantage of the multiloop control system proposed here is that the loops can be optimized for the best performance relatively independent of each other. For example, the outer voltage loop is tuned first for the best voltage regulation, and then the inner loops can be optimized relatively independently for the best THD of the output voltage while effectively managing and maintaining the stability. The controller parameters are determined as follows. Based on the steady-state voltage regulation and transient response specifications given in Table I, first the gains of the main voltage loop are determined as $Kp1 = 2$ and $Ki = 0.05$, as shown in Fig. 5. Then, the $Kp2 = 3$ is determined for the practical lowest THD while Kd and $Kp3$ are adjusted to maintain a stable operation. The proper gains for Kd and $Kp3$ are obtained using the control design tool for the lightly loaded case in The model shown in Fig. 4. The lightly loaded case is the worst case in terms of the stability. Fig. 6 shows the results of the

step response analysis and also illustrates the steps of the process how the controller parameters are determined

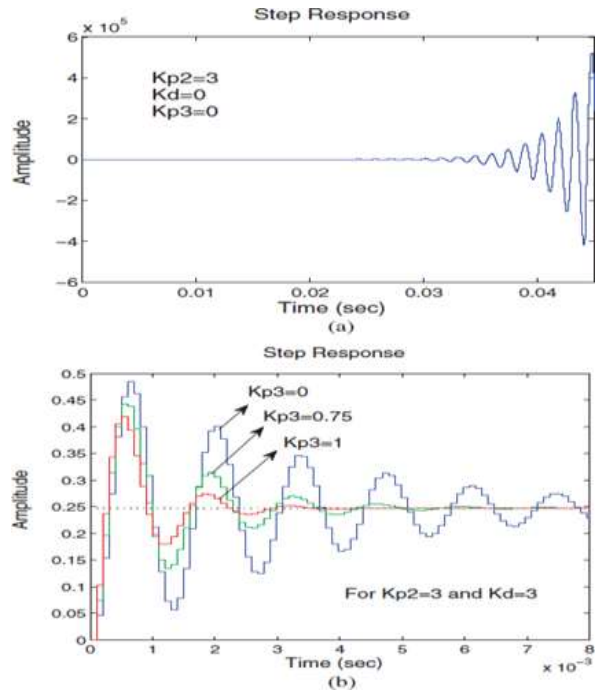


Fig. 6. Step response analysis of the closed-loop control system: (a) for $Kp2 = 3$, $Kd = 0$, and $Kp3 = 0$; (b) for $Kp2 = 3$, $Kd = 3$, $Kp3 = 0$ (blue), $Kp3 = 0.75$ (green), and $Kp3 = 1.0$ (red).

When only the ac inner voltage loop is active, that is, $Kp2 = 3$, $Kd = 0$, and $Kp3 = 0$, as mentioned before, the system is unstable as seen in Fig. 6(a). On the other hand, the derivative control where $Kp2 = 3$, $Kd = 3$, and $Kp3 = 0$ stabilizes the system, but not very effectively [the blue waveform in Fig. 6(b)]. However, a more effective stable operation is

obtained when the third loop (the inner ac current loop) is activated. Fig. 6(b) shows the results for $K_p2 = 3$, $K_d = 3$, and $K_p3 = 0.75$ as the green waveform, and for $K_p2 = 3$, $K_d = 3$, and $K_p3 = 1$ as the red waveform. Consequently.

The high switching frequency allows a larger voltage loop bandwidth which enables the controller to produce corrective actions to compensate for the fast changing oscillations at the voltage waveform effectively. Therefore, the switching frequency should be optimized based on the acceptable THD versus the switching losses and the efficiency. Based on the simulation results, it is found that 10.05 KHz is the optimum switching frequency for the given application (10 kVA three- phase UPS using the PWM switching method).

VII.SIMULATION RESULTS

Proposed Multiloop Controller

The simulations are done in the MATLAB/Simulink environment using the Simulink and PLECS model of the inverter and the controller as shown in Fig. 8. The results are evaluated based on steady-state error, transient response, and the THD of the output voltage. Fig. 9 shows the RMS value and the percent THD of the output voltage versus three different loads. According to Fig. 9, when the linear load at 8.5 kW is applied, the controller achieves 0.3% THD, and similarly when the nonlinear load at 10 kVA is applied, the controller achieves 3.1% THD. In addition, the RMS voltages are very well regulated at 220 V for each phase with an excellent transient response for the linear load but a fair response for the nonlinear load case. The transient response from no-load to the rated nonlinear load is oscillatory and it takes 1.1 s; however, the maximum fluctuation in the RMS voltage is less than 10% of the nominal (198–242 V). We consider this as an expected behavior for the nonlinear load case since the capacitor of the rectifier is made fairly large to get the desired crest in current; additionally, it is all empty before the load is applied. At the instant, the rectifier loads are switched in, a very large inrush current flows into these capacitors. So, it is this current that causes the oscillatory behavior. As mentioned before, the nonlinear load is a full-bridge diode rectifier load

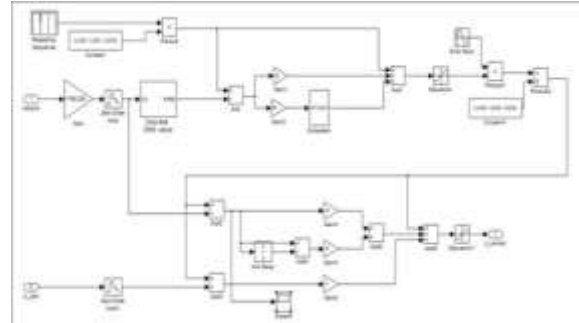


Fig.7. Proposed multiloop inverter controller implemented in the

The simulated load consists of a light load, the linear full load, and the nonlinear full load. placed between each phase and the neutral as shown in Fig. 3.

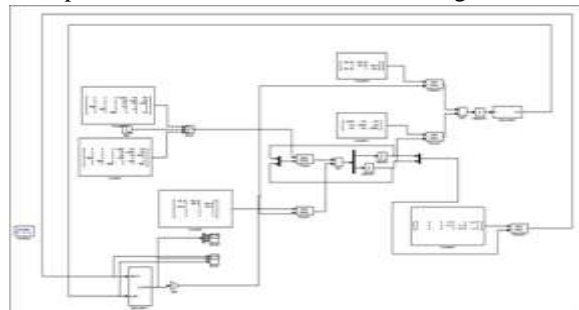


Fig.8. Simulink model of the inverter system

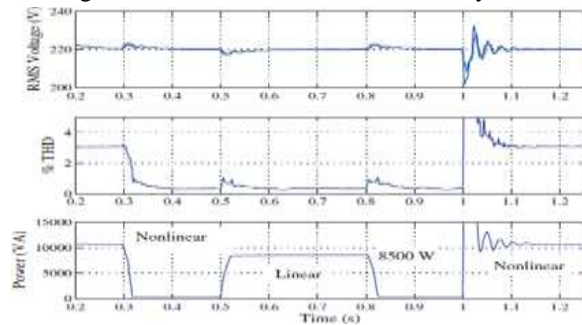


Fig.9. RMS fluctuations (top trace) and the profile of the percent THD of the output voltages (second trace) versus the load delivered by the inverter (bottom trace).

The simulated load consists of a light load, the linear full load, and the Non linear full load.

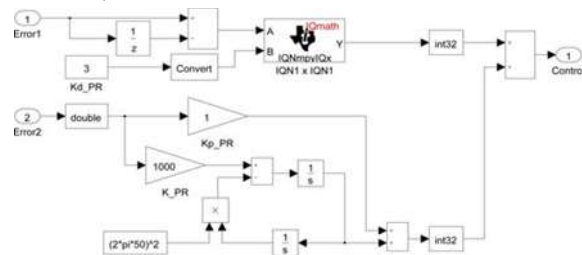


Fig.10. Inner loops of the control system: the PR controller is combined with the derivative controller

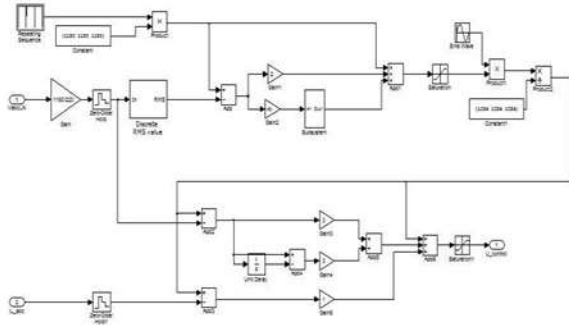


Fig.11. Inner loops of the control system: the PR controller is combined into the proposed multiloop controller.

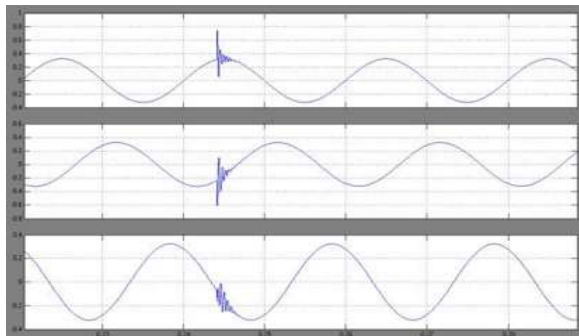


Fig.12. three-phase controlled output voltages

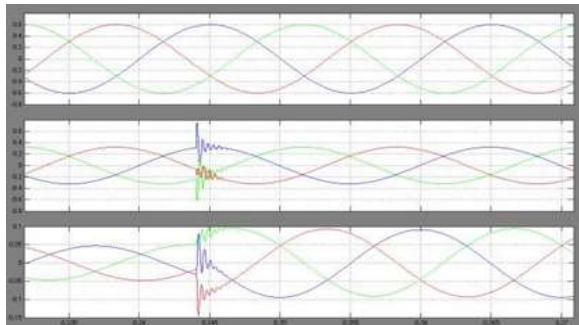


Fig.13. Three-Phase Output Voltages (Upper) And The Load Currents (Down) And Control Voltages (Middle)

A UPS system rated at 10 kVA, 50 Hz, 380 V was built and tested to evaluate the performance of the controller and the design. The implemented system uses the component values given in the PLECS simulation model of the converter shown in Fig. 3 (in Section IV) for the inverter part and the values given in Fig. 7 (in Section VI) for the controller part.

In Fig. 12, we compare the results of the multiloop design against the single-loop (only the RMS control) design in order to demonstrate the performance of the proposed multiloop controller. Fig. 13 compares the measured three-phase output voltages and the current of one phase for two loading conditions: the linear

full load and the nonlinear full load. Fig. 12 and 13 show the results when only the RMS control is used (single-loop), for this case the control achieves 1.96% THD for the linear and 9.68% THD for the nonlinear load. It is clear that the RMS control alone cannot achieve an acceptable THD under nonlinear loading at the rated UPS output power.

The waveforms in Fig. 12 show the results when the proposed multiloop controller is used for the same loading conditions. In this case, the controller achieves 1.11% THD for the linear load and 3.8% THD for the nonlinear load. The crest factor of the current in Fig. 13 is measured as 2.8.

VIII.SIMULINK RESULTS OF PV BASED INVERTER

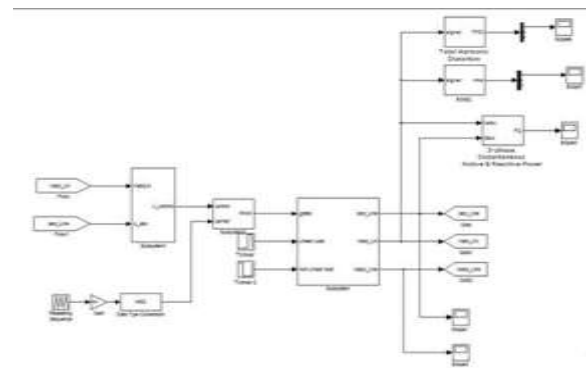


Fig.14.Simulink Model of Proposed Inverter

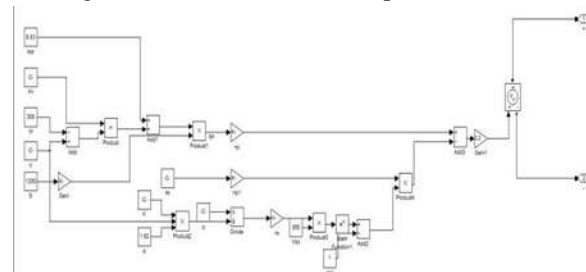


Fig.15.PV Simulink Model

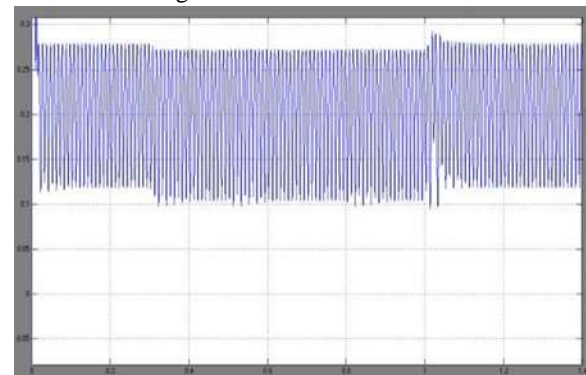


Fig.16.TH D of Output Voltage

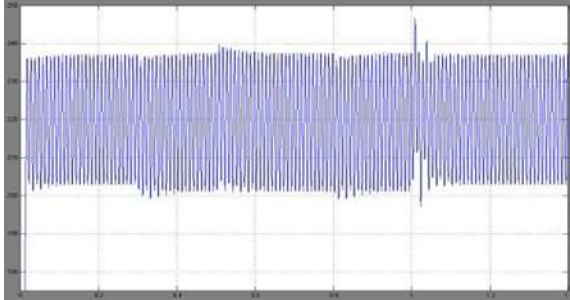


Fig.17.RMS Value of Output Voltage



Fig.18.The Load Delivered By The Inverter Consists Of A Light Load, The Linear Full Load, And The Nonlinear Full Load.

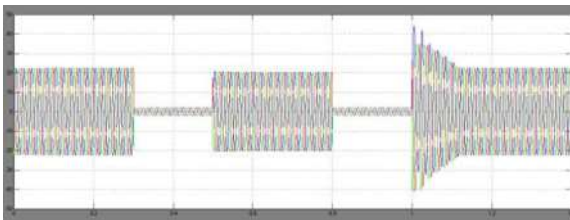


Fig.19.Inverter Input Reference Currents



Fig.20.Inverter Output Currents

IX.CONCLUSION

This paper presents the analysis and design of a high performance SPWM controller for three- phase pv interconnected UPS systems powering highly nonlinear loads. Although the classical SPWM method is very successful in controlling the RMS magnitude of the UPS output voltages, it cannot effectively compensate for the harmonics and the distortion caused by the nonlinear currents drawn by the rectifier loads. Therefore, this paper proposes a new strategy with a new design that overcomes the limitations of the classical RMS control. It adds inner

loops to the closed loop control system effectively that enables successful reduction of harmonics and compensation of distortion at the voltages.

The controller performance is evaluated experimentally using a three-phase 10 kVA transformer isolated UPS. A THD equal to 3.8% at the output voltage is achieved even under the worst nonlinear load. The load consists of three single-phase rectifiers connected between each line and the neutral and absorbing power equal to the rated power of the UPS with a crest factor up to 3. In conclusion, the simulation results demonstrate that the proposed controller successfully achieves the steady-state RMS voltage regulation specification as well as the THD and the dynamic response requirements of major UPS standards.

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