

Design and Analysis of Adaptive Power System with Fuzzy Control of Dynamic Loads

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ABSTRACT- In this paper we are analysis the Adaptive Power System (APS), which is utilized for the elimination of the negative impacts which is present for the large dynamic loads. Therefore in this paper we are implementing the fuzzy control for the better performance when comparing with the other controller. Because the fuzzy controller is the most suitable for the human decision-making mechanism, providing the operation of an electronic system with decisions of experts. The Navy's future and near-term high-energy sensors and energy weapons will consume a large portion of the resources of the intended ship platform. In this non linear system fuzzy control is utilized for the reduction of uncertain effects in the system control and improve the efficiency. The APS has used to maintain generator/prime-mover reliability, and also it is used to improve sensor/weapon performance or improve metrics such as system weight, cooling demands, and ship fueling costs. Therefore by utilizing the simulation results we can verify the proposed method.

Index Terms—AC/DC converter, active filter, buck converter, control loops, DC/DC converter, dynamic power profile, EMI, electromagnetic load torque, harmonics, power factor, power quality, fuzzy control.

INTRODUCTION

The APS is similar to the active filter concept whereby the active filter provides the current needed to maintain the quality of the load current required by the upstream power system. Duty cycles can vary from small to continuous and, for some cases, the peak power demands can be above the capability of the ship power plant.

The Adaptive Power System (APS) concept presented in this paper can be an enabling technology for sensors or weapons with large dynamic loads, which without the APS would be incompatible with the upstream shipboard generator and distribution bus. The APS consists of energy storage, a bidirectional current source, and innovative control techniques. These innovative control techniques increase the energy storage utilization, thus minimizing the energy storage size. A block diagram of a conventional shipboard power system is shown in the Figure 1. Conventional systems have focused heavily on providing well-regulated voltages and

clean power to the corresponding load. If the voltage dynamics seen at the load are to be minimized, the output impedance of each converter stage is minimized by using small series inductance values, large shunt capacitance values, and control loops with high bandwidths. However, to prevent the mid to low frequency load dynamics this type of system is presented from propagating back to the distribution bus and generator.

When compared with the passive filter method (brute-force method) the APS can support the pulsed load at a fraction of the size and weight needed. If using the active load method without excessive power dissipation as would exist (throw-away method), and for some specific applications without timeline restrictions as would be needed if using a refresh or recharging type system (restricted-timeline method).

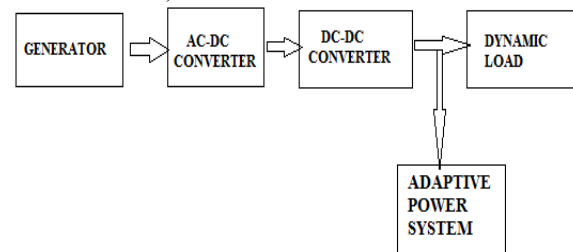


Fig. 1. A block diagram of a notional power system with the APS attached

The time limit for the enhanced operation is limited by the APS size, the size of the energy storage needed to provide the delta power, and the maximum average power allowed. This maximum allowed average power determines the corresponding duty cycle of this enhanced operation and hence the quickest allowed recharge time of the APS energy storage. Consequently, a new approach is needed to manage the load dynamics of emerging Navy systems

The new Adaptive Power System (APS) specifically addresses this need. The APS can be used to efficiently mitigate bus disturbances and reduce stress to the shipboard gensets by converting the dynamic power load seen by the shipboard power system into an equivalent rolling time average – essentially serving as an active low pass filter to the

load dynamics. As shown in Figure 1, the APS can be added to an existing system. The APS consists of energy storage, a passive power filter, a bi-directional current source, and innovative control loops, as shown in Figure 2.

The bi-directional current source efficiently delivers the pulsed power demand from the APS energy storage to the desired sensor or weapon system, thus providing a buffer to the upstream power equipment.

The APS is similar to the active filter concept whereby the active filter provides the current needed to maintain the quality of the load current required by the upstream power system. Active filters have been used for years in alternating current (AC) power systems to reduce the current harmonics and improve the power factor presented to the source when the loads are nonlinear and electrically noisy [10]–[12].

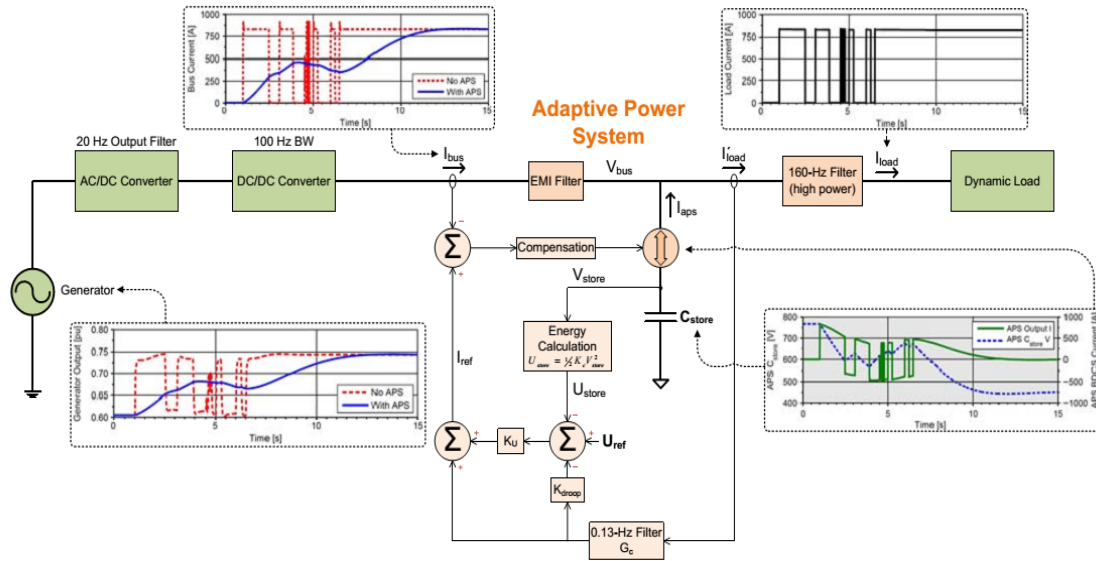


Fig. 2. An overview of the functionality of the APS system.

With the proper use of control loops and energy storage, the APS can reduce the rate at which the power demand on the generator changes, thus limiting the dynamics and spectral content seen by the generator - transforming a weapon or sensor system that had otherwise been incompatible with the platform's power system into one that is now feasible.

ADAPTIVE POWER SYSTEM (APS)

A. Overview

The goal of the APS is to minimize bus disturbances and stress to prime-power equipment by converting the dynamic power load into an equivalent rolling average of the power demand. The APS is designed to meet the proposed requirement as shown in Figure 3.

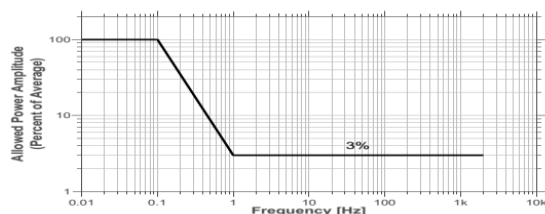


Fig. 3. The power ripple filtering requirement of the APS

The APS implementation must also not interfere with maintaining a stiff voltage (tightly regulated voltage) to the load. The top-level components of the APS include the energy storage capacitance and two control loops. One loop controls the APS output current to provide the required dynamic current to the load using the energy from the storage capacitance, and the other loop maintains the voltage across the energy storage capacitance to within the allowed rating.

Figure 2 provides the detail voltage and current waveforms for the APS as well as the generator power waveform during the application of a dynamic load profile.

Operation of the Adaptive Power System is as follows:

- The current provided from the upstream power system is regulated by the APS to be equal to the filtered (0.13 Hz) current profile of the load demand. The compensation block regulates I_{bus} to be equal to I_{ref} by controlling the output current of the bi-directional current source (BDCS); see the bus-

current and BDCS-current waveforms in Figure 2. The BDCS is a DC/DC converter that can process power in both directions – it can both absorb and deliver power.

• Hence, the AC component or dynamics of the load profile is not part of I_{bus} but is provided by the energy-storage capacitance via the BDCS.

• The energy-storage capacitance value is selected to be large enough to provide the source and sink currents to support the pulsed load demand. The value for the energy-storage capacitance is minimized by allowing the voltage across C_{store} to vary significantly, where $U_{delivered} = 1/2 C_{store}(V_{t20} - V_{t2+})$, minimizing the energy storage capacitance required.

– This provides significant weight and size savings compared to using an in-line high-powered low-pass filter (brute-force method).

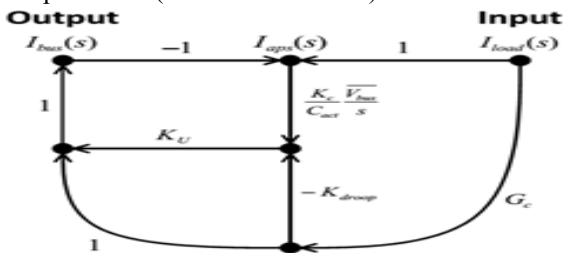


Fig. 4. Signal flow graph of APS for low frequency energy loop design where $I_{bus} = I_{ref}$ and $I_{load} = I_{load}$.

– The voltage variation across C_{store} is also decoupled from the load, allowing tight regulation of the bus voltage seen by the load to be maintained. $U_{delivered}$ is the energy delivered or absorbed by the storage capacitance, and V_{t0} and V_{t+} are the corresponding voltages across the energy-storage capacitance just prior to the load disturbance and after the energy-storage capacitance has delivered or absorbed the desired energy.

B.APS Requirements for Notional System

To demonstrate the APS functionality and performance, a top-level design and simulation for a notional 300-kW system was performed. For this specific system the APS interfaces with the 375-VDC bus, as shown in Figure 1. The system was designed to support the following load and input-output performance specifications:

- Duty Cycle of Load: 0 to continuous
- Average Load Power: 0 to 300 kW
- Peak Load Power: 0 to 300 kW
- Input Voltage: 4160 VAC per MIL-STD-1399-680
- Input Interface Power Ripple Requirements: Figure 3

- Voltage Transients at the 375-V Bus Load Interface: maintain to better than $\pm 5\%$

C.APS Design Details for Notional System Control Loop Bandwidth Considerations:

Figure 5 provides the schematic details for the APS. The bi-directional current source is a modular design consisting of thirty-eight 8-kW modules.

To simplify the analysis, the preceding assumptions have been used, and therefore this signal flow graph is only valid for low frequencies. In Figure 4, I_{bus} is the controlled upstream bus current coming from the 375-V converter, I_{load} is the current to the load before the 160-Hz filter, and G_c is the transfer function of the 0.13-Hz filter, which has been selected to be a second order filter defined as

$$G_c = \frac{\omega_c^2}{s^2 + (2\zeta\omega_c)s + \omega_c^2} \quad (1)$$

where ω_c is the corner frequency (in rad/s) and ζ is the damping ratio. In this example, ζ is equal to 0.9.

In addition, K_u is the energy-loop gain that determines the energy outer loop bandwidth, K_{droop} is the gain of the energy droop compensation (in J/A), C_{act} is the actual capacitance of C_{store} (in Farads), and K_c is the capacitance value (in Farads) used in converting the measured capacitor bank voltage, V_{store} , to energy,

the transfer function $\frac{I_{bus}(s)}{I_{load}(s)}$ can be determined as follows:

$$\frac{I_{bus}(s)}{I_{load}(s)} = \sum_{k=1}^N \frac{P_k \Delta_k}{\Delta} \quad (2)$$

where N is the total number of forward paths, P_k is the gain of the k th forward path, Δ is the determinant, and Δ_k is the cofactor of path k . The gain of forward paths are defined as

$$P_1 = G_c, \quad (3)$$

$$P_2 = -k_{droop} K_U G_c, \quad (4)$$

$$P_3 = k_u \frac{k_c \bar{V}_{bus}}{c_{act} s}, \quad (5)$$

where the bar over V_{bus} indicates a constant average value. There is only one loop in Figure 4, which is defined as

$$L = -k_u \frac{k_c \bar{V}_{bus}}{c_{act} s}, \quad (6)$$

TABLE I
size and weight of the aps system

Component	Value	Size (ft ³)	Weight (lbs.)
Module			
L _{of} + R _{1of}	10 μH + 1 mΩ	0.001	0.15
C ₂ *	3.3 μF	--	--
RC ₂ branch*	0.91 Ω + 68 μF	--	--
L _{sw} + R _{sw}	0.1 mH + 6 mΩ	0.004	1.4
C _{store}	86.7 mF	2.1	169.2
Heat Sinks	-	0.1	4
Miscellaneous	-	0.1	10
Total Modules			38
EMI Filter			
L ₁ + R ₁	25 μH + 0.3 mΩ	0.12	49
C ₁	94 μF	0.01	1
RC ₁ branch	0.31 Ω + 1.9 mF	0.03	5
Low-Pass Filter			
L _f + R _{fs}	25 μH + 0.3 mΩ	0.12	49
C _f	40 mF	0.13	21.9
C _s + R _s	0.2 F + 25 mΩ	1.25	217.7
R _{fp} *	33 mΩ	--	--
Grand Total		93.0	7364

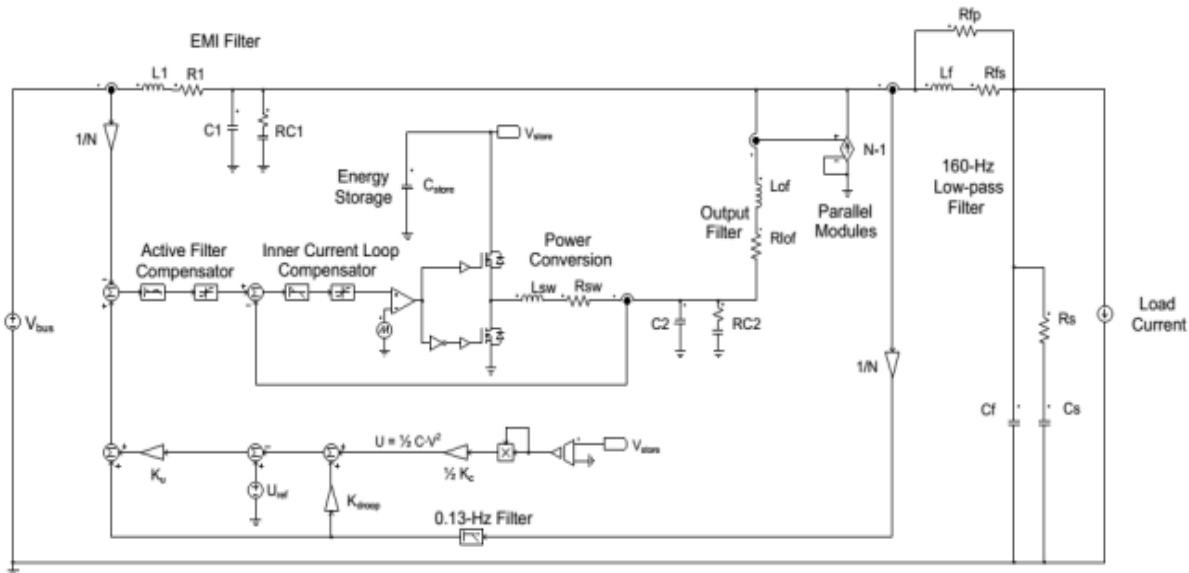


Fig. 5. The high-level schematic of an APS system used for simulation, where N is the total number of parallel modules (N=38)

The determinant is then

$$\Delta = 1 - L = 1 + k_u \frac{k_c V_{bus}}{c_{act} s} \quad (7)$$

Because the loop, L, touches all the forward paths, the cofactor for each forward path is simply defined by

$$\Delta_1 = \Delta_2 = \Delta_3 = 1 \quad (8)$$

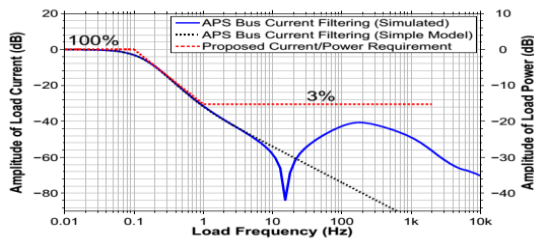


Fig. 6. The bus current filtering performance of the APS with the proposed requirement overlaid (for

example, a 100 kW average load is allowed 3 kW peak ripple at 1 Hz). Because the bus voltage is approximately constant, current filtering directly relates to power filtering.

Figure 6 demonstrates that this equation's predictions (black dashed line) are nearly identical to the detailed simulation results (solid blue line) up to 4 Hz, at which point interactions with the current control-loop compensator begins to appear. Figure 6 provides the time-constant requirement via the frequency-domain specification needed to determine the storage-capacitance nominal value, Cdesign.

This results since K droop's units are Joules/Ampere. Knowing the amount of energy used,

$$U_{total} = I_{loadmax} K_{droop} \quad (9)$$

along with the maximum available energy for use

$$U_{max} = \frac{1}{2} C_{design} (V_{max}^2 - V_{min}^2) \quad (10)$$

the corresponding capacitance value can be solved for

$$C_{design} = \frac{2I_{loadmax} K_{droop}}{(V_{max}^2 - V_{min}^2)} \quad (11)$$

Here, $I_{loadmax}$ is the designed maximum load current of the module, V_{max} is the maximum allowed capacitor voltage, V_{min} is the minimum allowed capacitor voltage.

Table II provides a summary of predicted component losses. The MOSFETs used in the implementation of the BDCS are silicon carbide devices. Silicon carbide devices are selected because of the inherently low drain to source parasitic capacitance, which is crucial to minimizing the switching losses when operating at the high voltage levels with hard switching.

TABLE II
POWERLOSSES OF THEAPS SYSTEM

Single Module Losses	
Max FET (two Cree SiC FETs)	91.9 W
Switching Inductor	32.0 W
Output Filter Inductor	0.5 W
C_{store} Leakage and Balance Resistors	2.6 W
<hr/>	
Total Module Losses	127.0 W
Number of Modules	38
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Total BDCS Converter Losses	4826 W
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Other Losses	
EMI or Low Pass Filter	210 W
Low Pass Filter Damping	2 W
Miscellaneous & Margin	1512 W
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Total System Losses	6550 W

PROPOSED REQUIREMENTS

The Navy's MIL-STD-1399-680 addresses pulse loading requirements, but only deals with pulses that occur infrequently – less than once every 45 seconds [14]. A requirement is needed that protects the genset and distribution bus against the dynamics resulting from frequent and repetitive pulsing loads but which is not as restrictive as the present requirement of only allowing a single pulse once every 45 seconds. Meeting the following requirement would provide this protection, and with the use of the APS, this requirement is feasible to implement, even for systems with large dynamic power profiles.

Proposed Pulsed Load Requirement:

The combined three-phase peak power ripple as seen by the shipboard generator(s) at any single frequency generated by the load shall be less than the limits defined by Figure 3. The resulting

allowed load profile proposed in Figure 3 has been matched to the generator and prime mover performance. Typical gensets' response times to a significant load change are on the order of 1.0 to 1.5 sec [15], [16]. If the rise and fall times for power changes (ramp rate) seen by the generator are controlled to be slower than the genset's response times, the generator and prime-mover control loops will be able to maintain the voltage and speed regulation, bus disturbances will be kept to a minimum for such a slow-changing power profile, and sub-synchronous resonances will not be excited because the disturbances are at lower frequencies.

FUZZY LOGIC CONTROLLER

In FLC, basic control action is determined by a set of linguistic rules. These rules are determined by the system. Since the numerical variables are converted into linguistic variables, mathematical modeling of the system is not required in FC.

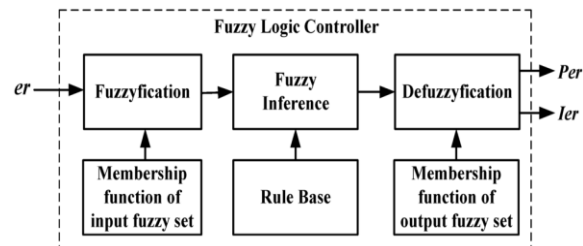


Fig.7.Fuzzy logic controller

The FLC comprises of three parts: fuzzification, interference engine and defuzzification. The FC is characterized as i. seven fuzzy sets for each input and output. ii. Triangular membership functions for simplicity. iii. Fuzzification using continuous universe of discourse. iv. Implication using Mamdani's, 'min' operator. v. Defuzzification using the height method.

TABLE III: Fuzzy Rules

e	e	NB	NM	NS	ZE	PS	PM	PB
NB	NB	NB	NB	NB	NB	NM	NS	ZE
NM	NB	NB	NB	NB	NM	NS	ZE	PS
NS	NB	NB	NM	NS	NS	ZE	PS	PM
ZE	NB	NM	NS	ZE	ZE	PS	PM	PB
PS	NM	NS	ZE	PS	PS	PM	PB	PB
PM	NS	ZE	PS	PM	PM	PB	PB	PB
PB	ZE	PS	PM	PB	PB	PB	PB	PB

Fuzzification: Membership function values are assigned to the linguistic variables, using seven fuzzy subsets: NB (Negative Big), NM (Negative Medium), NS (Negative Small), ZE (Zero), PS (Positive Small), PM (Positive Medium), and PB (Positive Big). The Partition of fuzzy subsets and the shape of membership $CE(k)$ $E(k)$ function adapt the shape up

to appropriate system. The value of input error and change in error are normalized by an input scaling factor. In this system the input scaling factor has been designed such that input values are between -1 and +1. The triangular shape of the membership function of this arrangement presumes that for any particular $E(k)$ input there is only one dominant fuzzy subset. The input error for the FLC is given as

$$E(k) = \frac{P_{ph(k)} - P_{ph(k-1)}}{V_{ph(k)} - V_{ph(k-1)}} \quad (12)$$

$$CE(k) = E(k) - E(k-1) \quad (13)$$

Inference Method: Several composition methods such as Max-Min and Max-Dot have been proposed in the literature. In this paper Min method is used. The output membership function of each rule is given by the minimum operator and maximum operator. Table 1 shows rule base of the FLC.

Defuzzification: As a plant usually requires a non-fuzzy value of control, a defuzzification stage is needed. To compute the output of the FLC, „height“ method is used and the FLC output modifies the control output. Further, the output of FLC controls the switch in the inverter. In UPQC, the active power, reactive power, terminal voltage of the line and capacitor voltage are required to be maintained. In order to control these parameters, they are sensed and compared with the reference values. To achieve this, the membership functions of FC are: error, change in error and output

The set of FC rules are derived from

$$u = -[\alpha E + (1-\alpha) * C] \quad (14)$$

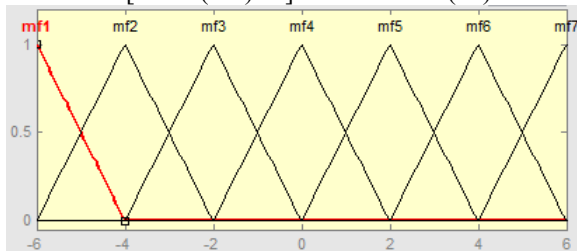


Fig 8 input error as membership functions

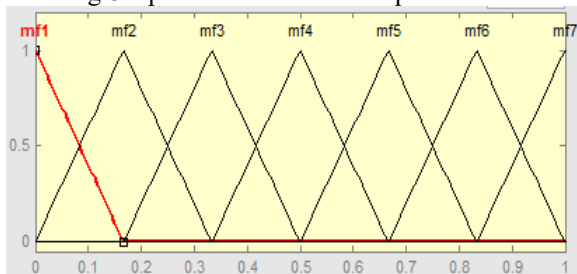


Fig 9 change as error membership functions

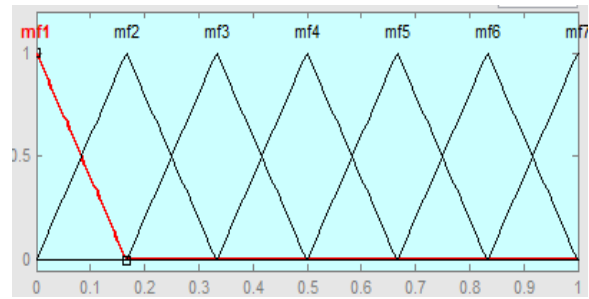


Fig.10 output variable Membership functions

Where α is self-adjustable factor which can regulate the whole operation. E is the error of the system, C is the change in error and u is the control variable.

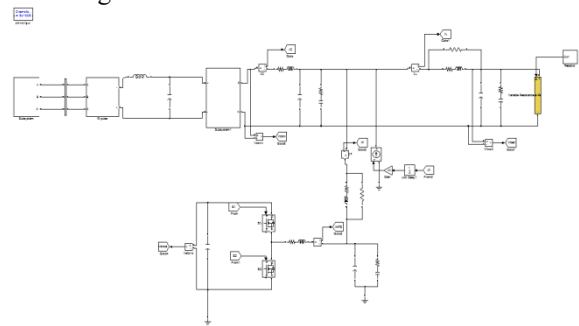


Fig11. Block diagram of simulation

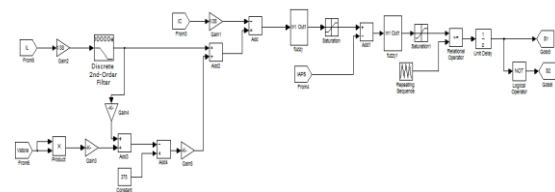


Fig 12. Control block diagram of simulation

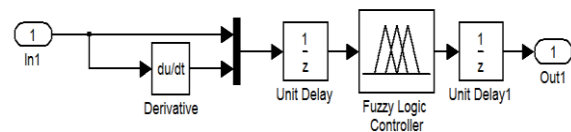
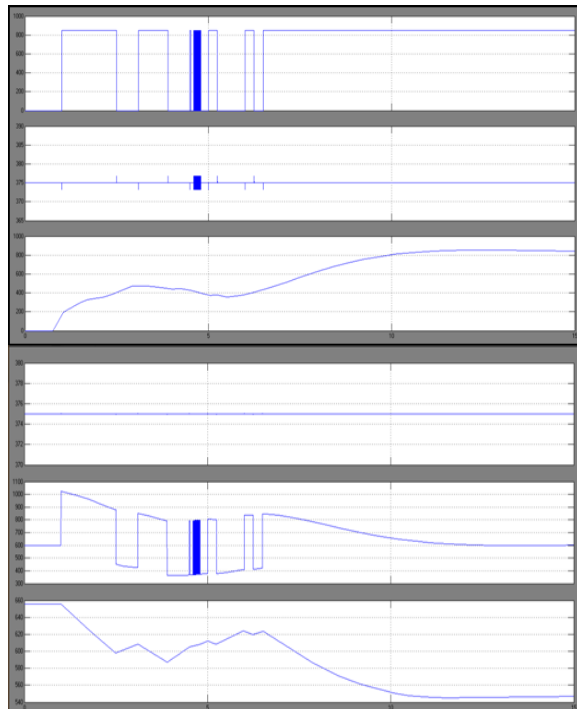


Fig13. Block diagram of fuzzy logic controller

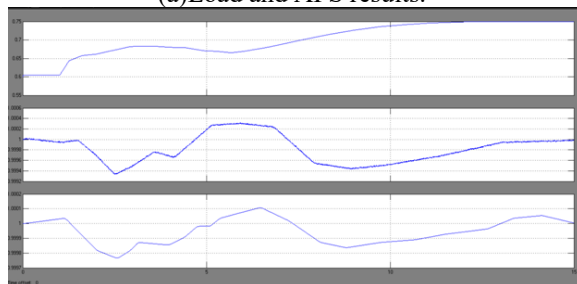
B. Simulation results for Notional System

The DC/DC converter voltage control loop is set at 100 Hz. To demonstrate the effectiveness and benefits of the APS, Figures 14(a) and 14(b) provide simulation results for various waveforms in the system when a dynamic load is applied both with and without use of the APS.

The load profile chosen in Figures 14(a) and 14(b) not only contains varying duty cycles but also simulates the extreme stressing condition.



(a) Load and APS results.



(b) Generator results.

Fig. 14. Simulation results of the first load profile.

Figure 14(a) also shows the voltage waveform of the storage capacitor and the current waveform of the bi-directional current source, demonstrating the APS's capability of providing the dynamic demand of the load resulting in the generator only having to provide the rolling average of the load power profile.

IV. CONCLUSION

In this project we are developing the Adaptive Power System (APS) concept presented can be an enabling technology for sensors or weapons with large dynamic loads, which without the APS would be incompatible with the upstream shipboard generator and distribution bus. In FLC, basic control action is determined by a set of linguistic rules. These rules are determined by the system. The APS consists of energy storage, a bidirectional current source, and

innovative control techniques. The APS has used to maintain generator/prime-mover reliability, and also it is used to improve sensor/weapon performance or improve metrics such as system weight, cooling demands, and ship fueling costs. By using the fuzzy controllers for a nonlinear system allows for a reduction of uncertain effects in the system control and improve the efficiency. The APS design is presented along with simulation results verifying the concept. By using the simulation results we can analyze the proposed method.

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