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# Improved hardware implementation of a TSR based MPPT algorithm for a low cost connected wind turbine emulator under unbalanced wind speeds

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## ABSTRACT

This paper presents the design, modeling, and the experimental build of a 1.5 kW relatively low-cost wind turbine emulator (WTE), based on the variable speed wind power system concept with partly rated power converters. The turbine simulator is composed of a controlled DC motor (DCM) in order to manage the static-dynamic behavior of a real wind turbine, including an ideal gearbox. This emulator is integrated into a connected wind energy conversion system chain (WECS), based on the double fed induction generator (DFIG) configuration. The latter ensures the electromechanical conversion. It allows the transfer of active and reactive power to the power grid during hypo and hyper synchronous modes. The aerodynamic emulation principle requires controlling the DC armature current with a PI controller. This leads to an electrical drive that applies a shaft torque identical to the wind turbine transmission drive train. The current reference is calculated as function of the static settings of the wind turbine and real wind speed data gives different operating points. In addition, this paper also proposes to test the TSR (Tip Speed Ratio) based MPPT algorithm to extract the maximum available power on the emulator by adjusting the rotational speed according to the actual given wind speed data. The MPPT, the DC motor control and the DFIG power control algorithms are implanted in C language, using dSPACE DS1104 control board, meanwhile simulations are done using MATLAB/Simulink. The experimental and simulation results show the effectiveness of using the controlled DC motor to emulate the wind turbine and also the great performances of the proposed MPPT structure to achieve the extraction of the maximum instantaneous power available on the drive shaft.

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## 1. Introduction

In recent decades, looking for alternative energies has become very demanding, given the increased risk of excessive use of fossil fuels and their negative impact, on nature and human life [1]. According to the global wind energy congress GWEC, wind power is one of the fastest-growing renewable energy technologies, where the rate of the cumulative global capacity of wind power production in the global market is now over 651 GW, an increase of 10 percent compared to 2018, with new installations surpassing the 60 GW over 2019 [2]. This is mainly due to its high techno-economic benefit and its renewable alternative source, environmentally friendly, as well as for solar energies [3,4].

Academic research in the renewable energy field considerably evolved, thanks to the great importance given by the energy policy of many governments around the world [5]. The subject of this paper comes within the framework of the projects at the Laboratoire d'Automatique de Tlemcen (LAT) concerns the design, implementation and intelligent management of an energy production system which is composed of two wind turbine emulator (double fed induction generator (DFIG) and synchronous generator (SG)), and a photovoltaic system [6–8].

This work is a continuation of a series of research projects in the renewable energy field at our laboratory. The lab aims to develop and study smart distributed renewable energy micro-power plants. The project includes four types of micro-power plants: 1.5 kW Double Fed Induction Generator Based Wind Turbine Emulator, 1.5 kW Synchronous Generator Based Wind Turbine Emulator, Photovoltaic system with Grid Tie

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Inverters and finally, a 250 W Photovoltaic micro-power plant connected through a self-made single phase Grid Tie Inverter. The main goal of this work is the development of a low-cost experimental bench for the emulation of a wind energy conversion chain based on a Double Fed Induction Generator (DFIG) [9], with the use of a DC motor controlled in current for the mechanical emulation of a real wind turbine. This system manages several scenarios and operating points in both hyposynchronous and hypersynchronous modes [10]. We can test different control laws (linear / non-linear) on both machines. Thus, it is useable as an education tool for training and for PhD research at an affordable cost, in the field of renewable energy.

In the literature, the DC motor is the most chosen in the wind turbine hardware emulation for the mechanical inertia driving [11]. Thanks to its linear model which ensures the proportionality between the armature current and the torque, simple torque and speed control are easy to implement with enough precision and performance [12,13].

Currently, the Double Fed Induction Generator DFIG represents one of the best high techno-economic solutions for the wind power exploitation in most wind farms around the world. It is less expensive compared to the synchronous machine [14]. Moreover, it allows direct connection of the stator to the grid and the control of the power transfer by acting on the rotor currents using an inverter / rectifier connected to the rotor [15].

This paper is organized as follows: We will first give in section II a detailed description of the overall proposed structure of this wind energy conversion system with a presentation of all the associated hardware elements of the experimental bench (machines, power electronic converters, measurements, software...). The modeling of a horizontal axis wind turbine is discussed in section III. Then, the proposed WTE with its associated MPPT algorithm is detailed in sections IV and V. The DPC based DFIG is established in the section VI. The tests results and the interpretations are given in section VII. Finally, the last section concludes the paper. YouTube videos related to the implementation and experiments can be found on:

[<https://www.youtube.com/watch?v=gXJHaHWJdk0>].

#### Nomenclature

DFIG	Double fed induction generator
DCM	DC Motor
WECS	Wind energy conversion system
WTE	Wind turbine emulator
MPPT	Maximum power point tracking
TSR	Tip speed ratio
$T_{DFIG}$	DFIG electromagnetic torque
$T_{DCM}$	DC Motor torque
$I_{DCM}$	DC Motor armature current
$T_t$	Turbine torque
$H_s$	High-speed shaft
$L_s$	Low-speed shaft
$J$	Moment of inertia
$f$	Viscous friction coefficient
$V$	Wind speed, m/s
$C_p$	Power coefficient
$R$	Blade radius, m
$G$	Gear box ratio

Greek letter

$\beta$	Blade pitch angle
$\lambda$	Tip speed ratio
$\Omega_m$	Mechanical speed
$\rho$	Air density
$\omega$	Angular speed

## 2. Experimental hardware description

Figure 1 shows the overall structure of the experimental hardware of the wind turbine emulator [16,17], which is constituted of a DC motor of 1.5 kW mechanically coupled with the DFIG shaft. The DFIG stator is connected to the grid through an autotransformer TRT 8A-400V 6 kVA for voltage adaptation and the transfer of the generated stator active and reactive power. The used power electronics equipment consisting of a SEMIKRON Semiteach box which contain a 6-IGBT's inverter with SKHI22 drivers that drives the DFIG rotor, this inverter is called the Machine Side Converter (MSC) that imposes the current references for reaching the desired DFIG active and reactive power using the rotor-flux vector control [18].

The Semiteach has also a diode-based 3-phases rectifier, which represents the point of divergence from other known grid connected DFIG based wind turbine structures, where IGBT's controlled rectifiers are used as a Grid Side Converter (GSC). In our application, for economic reasons, we minimize equipment costs. This allows us sharing the same DC bus for both the DC motor and the DFIG and using only one DSP control board to control both motors. Hence, when the induction machine is in hyper-synchronous speed operating mode, the rotor is generating active power and this power is absorbed by the chopper to drive the DC motor. The rectifier is connected to the grid through a second autotransformer TRT-13A 10 kVA. Semiteach's fourth IGBT leg is used as a chopper for the DCM control [19]. The inverter has also filtering capacitors on the DC link and a big heat sink.

To control both the DFIG and the DC motor, we use a dSPACE DS1104 single board control solution. It generates 7 PWM signals, 6 of them to control the 3-legs IGBT's machine side inverter to impose the DFIG rotor currents and one PWM signal for the DC chopper for imposing the calculated reference current. The Simple and Full PWM signals are issued by the TMS320F240 slave Digital Signal Controller of the dSPACE DS1104 board. In order to use this feature, we reprogrammed the firmware of the slave F240 DSC, leading to an optimum use of hardware and reducing the overall cost. We use the ADCs for the following measures: 2 rotor phase currents and the DC motor current using LEM LA55 Hall effect sensors ( $I_{dr}$ ,  $I_{qr}$  and  $I_{DCM}$  measurement), 2 stator phase voltages and the DC bus voltage using LEM LV25-P Hall effect sensors ( $V_{sa}$ ,  $V_{sb}$  and  $V_{DC}$  measurement). This uses 6 analog inputs over the 8 available ADC of the board, where 4 of them are multiplexed. The mechanical speed and the rotor angle are measured thanks to an incremental encoder with the help of the index signal and interrupt service routine to compute the absolute position of the rotor. The Control Desk™ running on the DS1104 host PC permits the visualization of the system variables in real time and the input of the reference values.

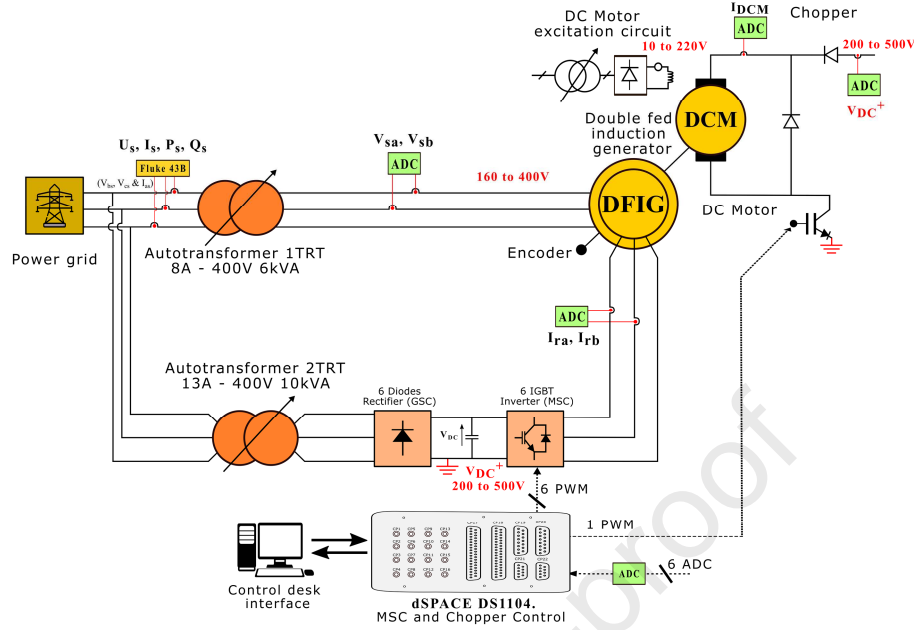


Fig. 1 - The experimental hardware structure of the WTE.

### 3. Modeling and control of WTE

In this section, we will give the model of a fixed pitch wind turbine with horizontal axis, the static-dynamic model will be used to produce a DC motor torque identical to an aerodynamic torque at the steady-state conditions depends on the wind speed and turbine characteristics [20]. The wind turbine model can be divided into two parts [21].

#### 3.1 Wind turbine static model

The kinetic energy of a column of wind of density  $\rho$ , driven by a velocity  $V$ , of length  $x$ , of cross section  $S$  as shown in Figure 2 [22].

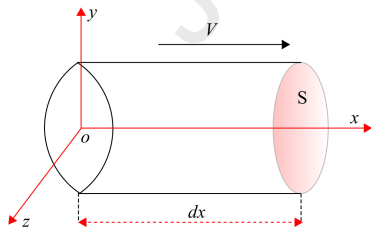


Fig. 2 - Representation of a wind column.

The kinetic energy of this air column is [23]:

$$dE = \frac{1}{2} dm V^2 \quad (1)$$

Where  $dm = \rho S dl$  is mass of the wind column with  $V = \frac{dl}{dt}$ . So, the expression is simplified as:

$$\frac{dE}{dt} = \frac{1}{2} \rho S V^3 dt \quad (2)$$

Thus, we deduce the expression of the available power as [24]:

$$P_m = \frac{dE}{dt} = \frac{1}{2} \rho S V^3 \quad (3)$$

The static model of the wind turbine is mainly characterized by the wind speed  $V$ , the blade pitch angle  $\beta$  and the power coefficient  $C_p$  [9]. The kinetic energy of wind captured by the blades in an air surface  $S$  transformed into mechanical energy is given by:

$$P_m = \frac{1}{2} \rho S V^3 C_p \quad (4)$$

Where  $S$  is the surface of the air column running through the turbine blades of a radius  $R$ , and  $\rho$  is the air density in ( $kg/m^3$ ). The efficiency of each wind turbine is evaluated by the power coefficient value, this value depends mainly on the blade pitch angle  $\beta$  and the value of the tip-speed ratio (TSR)  $\lambda$ . The power coefficient value is limited to 0.59, called Betz's limit. This theory states that a wind turbine can never convert more than 59% of the kinetic energy contained in the wind into a mechanical energy [25]. The commonly used approximation expression of the power coefficient  $C_p$  given as:

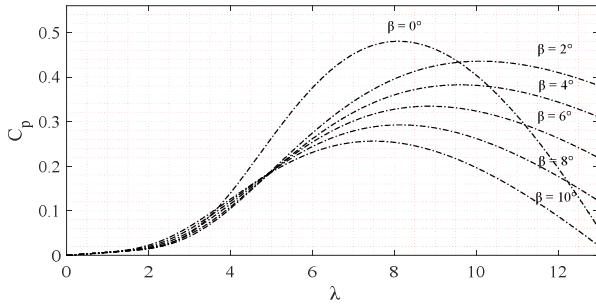
$$\left\{ \begin{array}{l} C_p = 0.5176 \left( \frac{116}{\lambda_i} - 0.4\beta - 5 \right) \exp \left( \frac{-21}{\lambda_i} \right) + 0.0068\lambda \\ \frac{1}{\lambda_i} = \frac{1}{\lambda + 0.08\beta} - \frac{0.035}{\beta^3 + 1} \end{array} \right. \quad (5)$$



The tip speed ratio  $\lambda$  is the ratio between the turbine mechanical speed  $\Omega_t$  and the wind speed, is defined as [26]:

$$\lambda = \frac{\Omega_t R}{V} \quad (6)$$

Figure 3 shows the variation of the power coefficient  $C_p$  as a function of the speed ratio  $\lambda$ , for some pitch angle values [27]. Each curve has its own maximum which corresponds to the maximum power that can be extracted from wind energy. This maximum is strongly influenced by the wind speed, since  $\lambda$  is a consequence of  $V$ . Therefore, variable speed wind turbines are more efficient than fixed speed wind turbines for extracting maximum power from wind [28].



**Fig. 3 -** Power coefficient characteristics.

The aerodynamic torque available on the wind turbine shaft can be expressed as [3]:

$$T_t = \frac{1}{2\Omega_t} \rho A V^3 C_p \quad (7)$$

### 3.3 Wind turbine dynamic model

Figure 4 illustrates the mechanical model of our WTE system, based on the simplified two-mass model, which is usually the most used in the literature to represent the forces applied to the transmission drive train of the wind power system [29].

**Fig. 4 -** Two mass schematic model of WTE drive train.

The dynamics of the low and high-speed shaft can be described by [30]:

$$\begin{cases} J_t \frac{d\Omega_t}{dt} = T_t - f_t \Omega_t - T_{Ls} \\ J_g \frac{d\Omega_m}{dt} = T_{Hs} - f_m \Omega_m - T_m \end{cases} \quad (8)$$

Where:

$\Omega_m, \Omega_t$ : The mechanical high/low-speed shaft respectively.

$T_{Hs}, T_{Ls}$  is the torque of the high/low-speed shaft respectively.

$J_t, J_g$ : Wind turbine inertia,  $J_g$ : Inertia of the generator.

$f_m, f_t, f_g$ : The viscous frictions of the generator, wind turbine and the gearbox respectively.

$d_m, d_g, d_t$ : The stiffness coefficients of the generator, wind turbine and the gearbox respectively.

The stiffness coefficients  $d_g, d_t$  and  $d_m$  are generally low, so they can be neglected [11]. Hence, torque equations are:

$$\begin{cases} \frac{dT_{Ls}}{dt} = d_g(\Omega_t - \Omega_m) - f_g \left( \frac{d\Omega_t}{dt} - \frac{d\Omega_m}{dt} \right) \\ \frac{dT_{Hs}}{dt} = d_g(\Omega_m - \Omega_t) - f_g \left( \frac{d\Omega_m}{dt} - \frac{d\Omega_t}{dt} \right) \end{cases} \quad (9)$$

The transmission ratio  $G$  for an ideal gearbox is given by [31]:

$$G = \frac{T_{Ls}}{T_{Hs}} = \frac{\Omega_m}{\Omega_t} \quad (10)$$

The equivalent inertia of the WTE can be expressed by:

$$J = \frac{J_t}{G^2} + J_m \quad (11)$$

Figure 5 shows the equivalent mechanical model of the implanted emulator, including the opposing torques of the both machines applied on the common shaft [32]. The transmission system can be represented also by a one-mass model having an inertia equivalent to the assembly DC motor/generator and an equivalent coefficient of friction.

**Fig. 5 -** Mechanical model of the WTE.

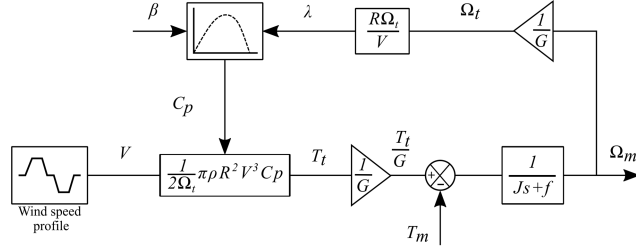
However, the stiffness coefficients  $d_g, d_t$  and  $d_m$  are generally low, so they can be neglected [33]. Hence, the fundamental mechanical equation of the emulator in the electrical generator side is giving as:

$$J \frac{d\Omega_m}{dt} = T_{DCM} - T_m \quad (12)$$

The equivalent inertia  $J$  applied on the high-speed shaft (generator side) is becomes as:

$$J = J_{DCM} + J_m \quad (13)$$

The overall wind turbine model, including its both static-dynamic parties can be generalized in figure 6 [6].



**Fig. 6** - Overall model of a variable-speed WTE.

### 3.3 Wind speeds distribution based on Weibull model

The Weibull function makes possible to characterize the frequency distribution of wind speeds over a given period in different locations [34]. However, in most cases, this distribution is used for a one-year period. It is defined by the following equation [35]:

$$f(V) = \frac{k}{c} \left( \frac{V}{c} \right)^{k-1} \exp \left( - \left( \frac{V}{c} \right)^k \right) \quad (14)$$

Where  $f(V)$  is the Weibull probability density function (PDF).  $c$  is the scaling factor. It is related to the average wind speed by the form factor  $k$ .  $k$  is the Weibull shape factor. The latter describe the distribution of wind speed. Thus, the cumulative distribution function (CDF) is obtained by integrating the Weibull probability density function [36]:

$$P(V) = 1 - \exp \left( - \left( \frac{V}{c} \right)^k \right) \quad (15)$$

The mean wind speed can be expressed by:

$$\bar{V} = \frac{1}{n} \sum_{i=1}^n V_i \quad (16)$$

In order to analyses the distribution of the wind speed according to the Weibull law, it's required to estimate the Weibull shape factor  $k$  and the scaling factor  $c$ . Weibull shape factor  $k$  is estimated using [37]:

$$k = \left( \frac{\sigma}{\bar{V}} \right)^{-1.086} \quad (17)$$

Where  $\sigma$  is the standard deviation of wind speed.

$$\sigma = \sqrt{\frac{1}{n-1} \sum_{i=1}^n (V_i - \bar{V})^2} \quad (18)$$

So, scaling factor  $c$  is:

$$c = \frac{\bar{V}}{\Gamma \left( 1 + \frac{1}{k} \right)} \quad (19)$$

where  $\Gamma$  is the gamma function.

### 3.4 Rayleigh distribution

Rayleigh probability density is a particular case of Weibull's law when  $k=2$  [38]. Thus, the scaling factor  $c$  is determined as follow:

$$c = \frac{2\bar{V}}{\sqrt{\pi}} \quad (20)$$

The probability density function becomes:

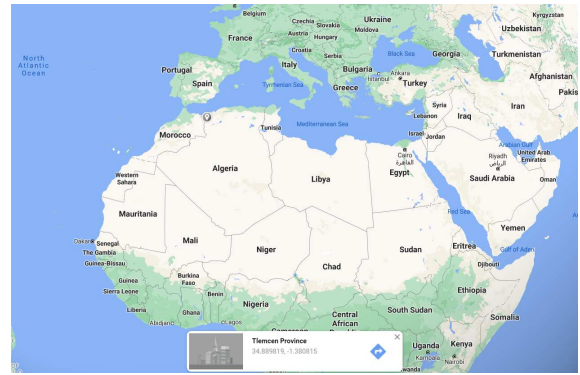
$$f(V) = \frac{\pi}{2} \frac{V}{\bar{V}^2} \exp \left( - \left[ \frac{\pi}{4} \left( \frac{V}{\bar{V}} \right)^2 \right] \right) \quad (21)$$

While the cumulative distribution function is:

$$P(V) = 1 - \exp \left( - \left[ \frac{\pi}{4} \left( \frac{V}{\bar{V}} \right)^2 \right] \right) \quad (22)$$

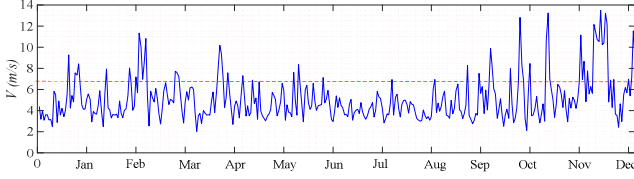
The main advantage of Rayleigh's law is its simplicity. The Rayleigh law now depends only on the mean value of the wind speed.

The site chosen for our study is the current location of our laboratory at Tlemcen in North Africa (Fig. 7). the wind measurements over a year are taken from NASA Power data [39].



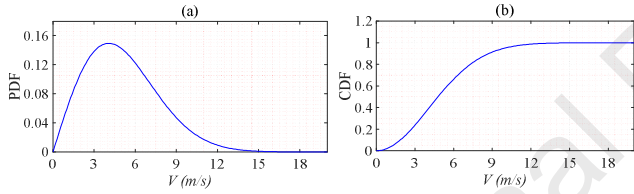
**Fig. 7** - location of the studied site.

Figure 8 shows the average wind speed over Tlemcen at 50 m altitude during 2020 [40]. Mainly, this speed varies between 2.5 m/s and 7.5 m/s around an average value of 5.1 m/s. It is noted that the mean value of wind speed is high during autumn, reaching sometimes 13.75 m/s.



**Fig. 8** - Wind speed Data at Tlemcen in 2020.

Figure 9 presents the Rayleigh probability distributions function PDF and Rayleigh cumulative distributions function CDF for all speed ranges. Rayleigh PDF seems to give a reasonable fit to the measured wind speed data, because most of wind speeds are in the range of 3-7 m/s during all the year (Figure 9.a), as well as the cumulative distribution function which increases strongly in this range (Figure 9.b). Therefore, we can classify it as a normal distribution. This last can judge the efficiency of the Rayleigh distribution.

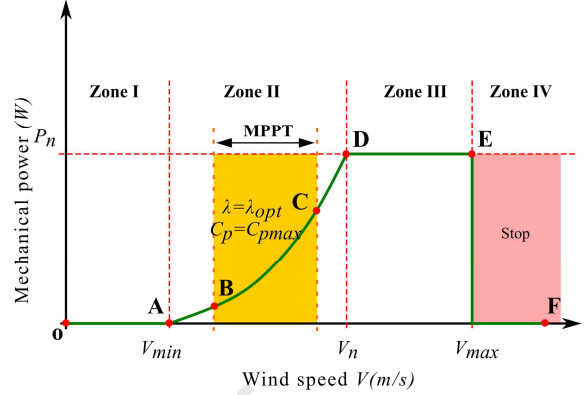


**Fig. 9** - a) Rayleigh probability distributions function PDF, b) Rayleigh cumulative distributions function CDF.

The wind speed data analyzed above was incorporated into the lab setup, applying a similar curve distribution to generate aerodynamic drive torque. The time interval has been reduced to one minute while maintaining the same speed distributions.

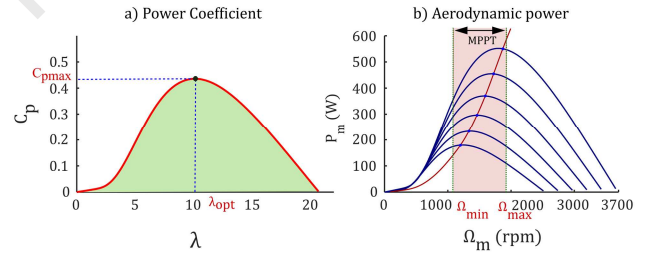
#### 4. TSR Based MPPT algorithm structure

Mainly, the operating ranges of the variable speed wind turbine can be divided into three basic regions as shown figure 10 [41]. The MPPT operation part included in zone II Between (B-C), is the most important part of the WTE, considering the evolution of energy production according to the development on the wind speeds. The MPPT in this stage has the role of maintaining  $C_p$  in a maximum value ( $C_p = C_{pmax}$ ) by adjusting the rotor rotational speed according to the wind speed change, hence, the tip speed ratio keeps its optimum value ( $\lambda = \lambda_{opt}$ ). Besides, the mechanical speed is controlled at the optimum turbine rotational speed for each captured wind speed, hence, the generated electromagnetic torque become linked into this speed, consequently, the quadrature rotor current of the generator  $I_{qr}$  [42].



**Fig. 10** - Operational range of a variable speed based WTE.

The TSR structure is the most used MPPT algorithms, thanks to its efficiency, especially the simplicity of implementation [43]. The principle is to keep the tip speed ratio (TSR) to an optimum value  $\lambda_{opt}$  that corresponds the maximum of  $C_{pmax}$  (Fig. 11.a), hence the maximum of the extracted power. Therefore, it is necessary to maintain the WTE rotational speed at this operating point by adjusting the generator speed with a speed control loop [44].



**Fig. 11** - TSR principle based MPPT algorithm.

The WTE output mechanical power available on the DFIG-DCM common shaft at different wind speeds, therefore, the WTE rotational speed (Fig. 11.b) [45]. The red line intersection points with the curves present the maximum power that needs to be extracted to achieve optimum operating point. Therefore, we apply TSR based MPPT algorithm to extract as much power as possible in the limited region colored, the interval of this limitation is chosen to be adaptable with the controller performances, also the hardware protection against overvoltage. For our emulator, we set  $\beta$  at  $2^\circ$  which corresponds to a maximum power coefficient  $C_{pmax}$  of 0.43 for an optimum tip speed ratio  $\lambda_{opt}$  of 10.22 [46]. The optimal speed reference is expressed as:

$$\Omega_i^* = G \frac{\lambda_{opt}}{R} V \quad (22)$$

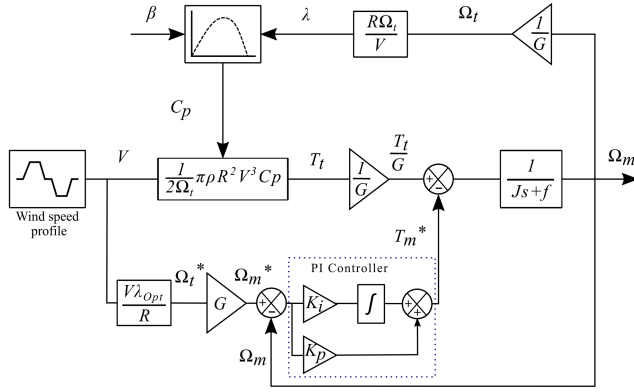


Fig. 12 - TSR based MPPT algorithm block diagram.

The block diagram of the TSR based MPPT algorithm is given by Figure 12 [47]. The PI regulator is used to reduce the error between the optimal speed reference calculated in Eq (22) and the actual speed. This algorithm requires the accurate measurement of wind speed using an anemometer, this latter has an additive cost and it becomes a disadvantage for small turbine, add to that the inconvenience of the limited operating area.

## 5. The proposed WTE

The principle of emulating a wind turbine is to create aerodynamic torque from the controlled DC motor [19]. Figure 13 shows the proposed structure of the proposed WTE that is implanted at our laboratory [32]. The controlled DC motor provides a variable output torque, which we consider equal to an adapted aerodynamic torque via an ideal gearbox [48].

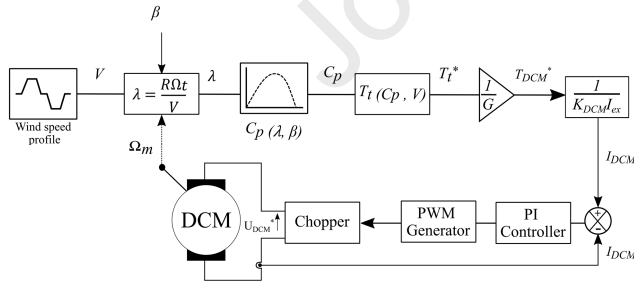


Fig. 13 - Overall diagram of the wind turbine emulator.

Equation (23) indicates the proportionality between the armature current and the DC motor torque [49]:

$$T_{DCM} = K I_{DCM} \quad (23)$$

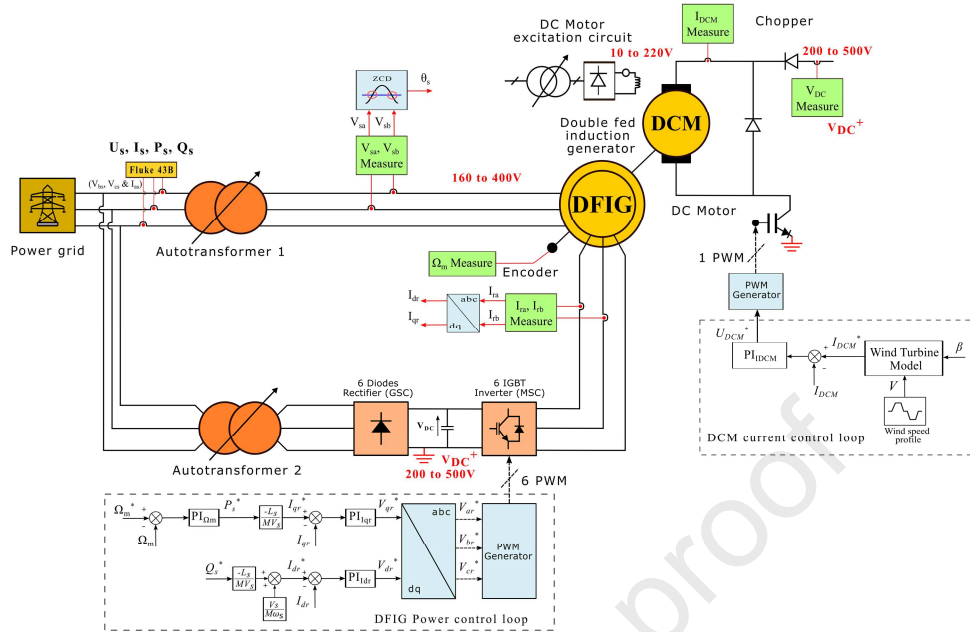
Where  $K$  is the product of the electromotive force coefficient  $K_{DCM}$  and the excitation current  $I_{ex}$ . Therefore, while keeping this coefficient constant, controlling the torque, is done by acting on the armature current [50]. The reference current  $I_{DCM}^*$  is calculated when applying a wind speed profile on the static-dynamic model of the wind turbine. Thus, the armature current follows the shape of the wind speed curve. So are the torque  $T_{DCM}^*$  and the supply voltage  $U_{DCM}^*$  [7]. The calculated reference current formula which relates the typical wind speed to the armature current is expressed as follows:

$$I_{DCM}^* = \frac{\rho \pi R^2 C_p}{2 G K \Omega_m} V^3 \quad (24)$$

The proposed wind speed values interval allows testing transient of the transfer of the generated power between the power grid and the DFIG stator-rotor during operating modes: hyper synchronous, and hypo synchronous mode [51].

## 6. DFIG integrated into WTE

The next part consists of keeping the mechanical training structure and adding the control algorithm of the MSC in order to produce active and reactive power (Fig. 14) [17,33]. Therefore, the MPPT control loop is cascaded with the  $I_{qr}$  PI controller, consequently, the speed loop determines the desired reference of the active power  $P_s^*$ .



**Fig. 14 - Overall scheme of the proposed WTE.**

In order to integrate the MSC control part, the generator model is presented. The DFIG simplified  $dq$  model is written as [51,52]:

$$\begin{cases} V_{dr} = R_r I_{dr} + \sigma L_r \frac{dI_{dr}}{dt} - \omega_r \sigma L_r I_{qr} \\ V_{qr} = R_r I_{qr} + \sigma L_r \frac{dI_{qr}}{dt} + \omega_r \sigma L_r I_{dr} + \omega_r \frac{M V_s}{\omega_s L_s} \end{cases} \quad (25)$$

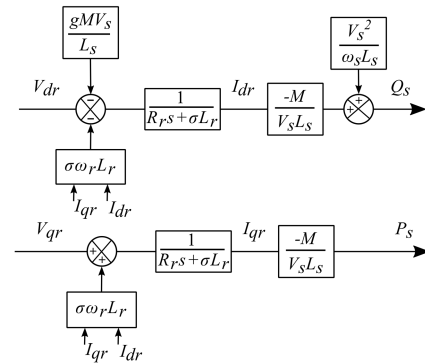
Where  $\sigma = 1 - \frac{M^2}{L_s L_r}$  is the leakage coefficient,  $R_r$  is the resistance of the rotor,  $L_s$  and  $L_r$  are the stator and the rotor inductances.  $M$  is the stator-rotor mutual inductance [53]. The DFIG stator active and reactive power is expressed according of the direct and quadrature rotor currents as [14]:

$$\begin{cases} P_s = -\frac{MV_s}{L_s} I_{qr} \\ Q_s = -\frac{MV_s}{L_s} I_{dr} + \frac{V_s^2}{\omega_s L_s} \end{cases} \quad (26)$$

where the electromagnetic torque of the machine is given by:

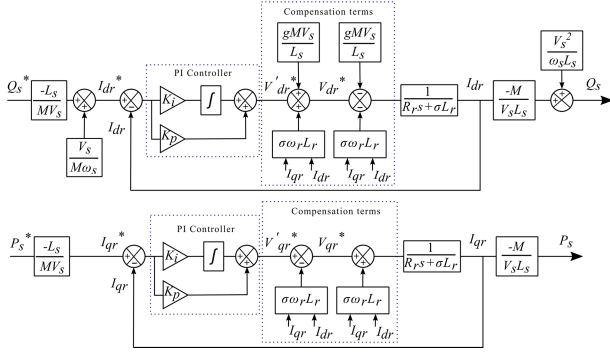
$$T_g = -p \frac{M}{L_s} \phi_s I_{qr} \quad (27)$$

The model is summarized in the block diagram of Figure 15 [54].



**Fig. 15** - Block diagram of the DFIG.

According to the rotor voltage equations, the rotor currents  $I_{dr}$  and  $I_{qr}$  are controlled by the rotor voltages  $V_{dr}$  and  $V_{qr}$ , respectively. Hence, the adjustment of the stator reactive power  $Q_s$  is done by acting directly on the d-axis rotor current  $I_{dr}$  through the PI controller loop, while the active power  $P_s$  control is done by the action on the q-axis current  $I_{qr}$  [55]. Figure 16 illustrates the  $dq$  current loops, the active and reactive power are controlled through two similar PI control loop, and independently thanks to the introduction of decoupling terms in the current loops [8].



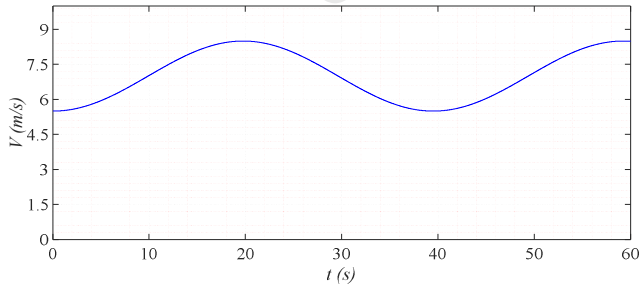
**Fig. 16** - Diagram of the DFIG direct power control using PI controllers.

## 7. Results and discussions

In order to validate the effectiveness of the proposed WECS structure, we conduct experimental tests that affirmed before by the simulation validation under Matlab Simulink framework. They consist of introducing different wind speed profiles that covers the operating modes. At every moment, the control applies a DC motor torque identical to the one of the emulated wind turbine, imposing the driving speed. In addition, the experiments test the MPPT efficiency by TSR method. We apply two tests:

### 6.1 First test: wind profile in a sinusoidal shape

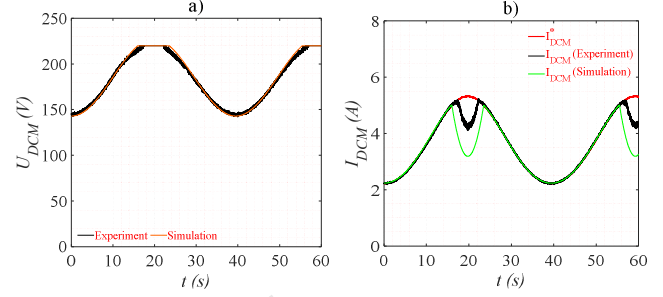
As a first test, we apply a slow sinusoidal variation on the wind speed which varies between 5.5 and 8.5 m/s. The slow transition of the sinusoidal shape makes it possible to observe well the electro-mechanical phenomena of the WTE during the slow transition between the hypersynchronous towards the hypersynchronous, passing by the synchronous speed at 1500 rpm which correspond to a wind speed of 7 m/s (Fig. 17).



**Fig. 17** - Wind speed profile.

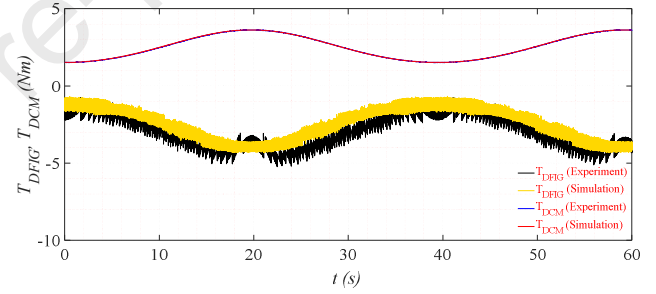
The figure (18.a) shows the good tracking accuracy between the measured armature current  $I_{DCM}$  and the calculated reference  $I_{DCM}^*$  thanks to the PI current controller. The necessary DC motor voltage  $U_{DCM}^*$  that is outputted by the current controller is limited to 220 V for the protection of the DC motor (Fig. 18.b). When it reaches this limit, the current decreases inevitably. This condition of current decrease during saturation is not the

same for both experimental and simulation tests, so the currents  $I_{DCM}^{(SIM)}$  and  $I_{DCM}^{(EXP)}$  are not identical during this test period.



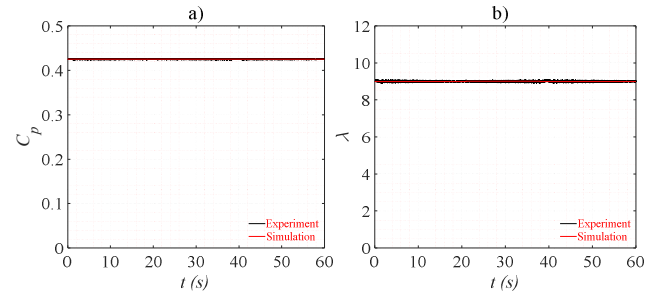
**Fig. 18** - a) DC armature current, b) DC motor voltage.

We then get the WTE torques: turbine torque, which is adapted through the gearbox ratio to get a DC motor torque, they have the same form of the wind speed curve and they are opposed. Harmonic torques due to the gradient and tower shadow effects are neglected and we consider the gearbox as ideal (Fig. 19).



**Fig. 19** - WTE Torques.

The tip speed ratio  $\lambda$  remains stable around its optimum value  $\lambda_{opt}$  (Fig 20.b). The value of the power coefficient  $C_p$  is around 0.42 (Fig 20.a), which allows the production of a significant power.

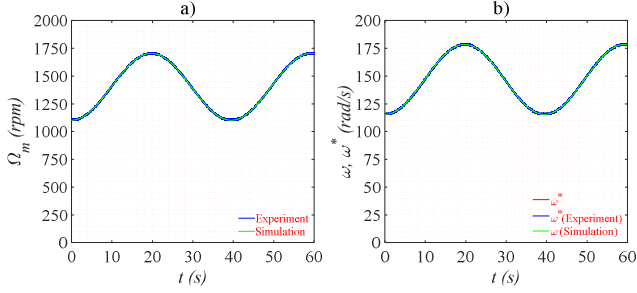


**Fig. 20** - a) Power coefficient, b) Tip speed ratio.

The WTE rotates at an optimum speed  $\Omega_{opt}$ , that is adjusted perfectly by the speed control loop using PI controller (Fig 21.b). The optimum reference speed  $\Omega_{opt}^*$  is imposed by the MPPT algorithm loop based on the TSR structure. As well, the mechanical speed is transmitted slowly

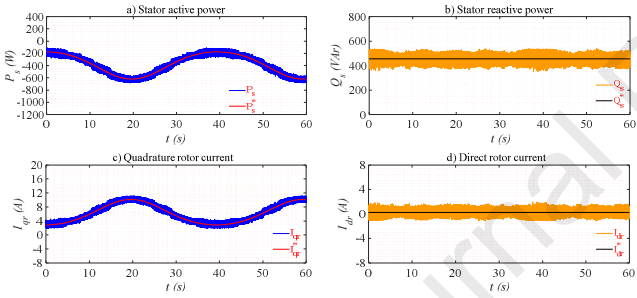


between operating modes on the limited zone of the MPPT operation, and they will be fixed as soon as it reaches its up-maximum value at 1800 rpm (Fig 21.a), the generated power is consequently fixed also.

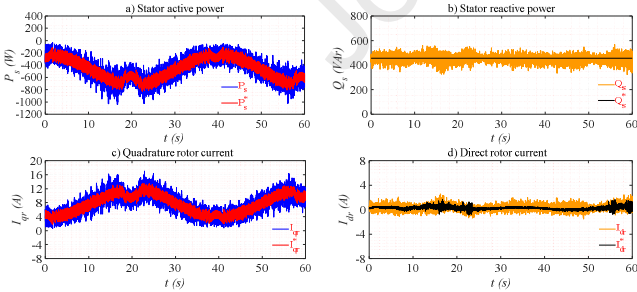


**Fig. 21** - a) WTE Mechanical speed, b) WTE speed control.

The MPPT based TSR algorithm shows the capability to reach the maximum of the extracted power during the transition speeds over a significant range (Fig. 22). A negative power means that it is injected into the grid. The efficiency of both PI current controllers maintains the accuracy of the active and reactive power trajectory. The DFIG consumes a reactive power of 450 VAr to be fluxed.



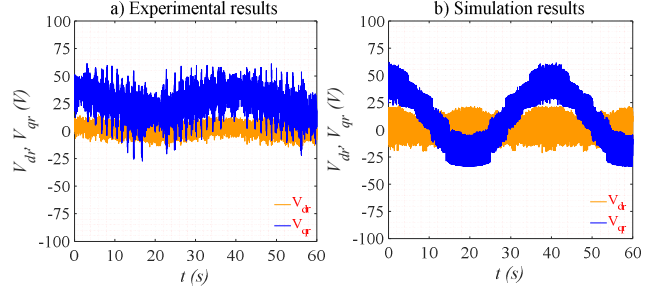
**a) Simulation results.**



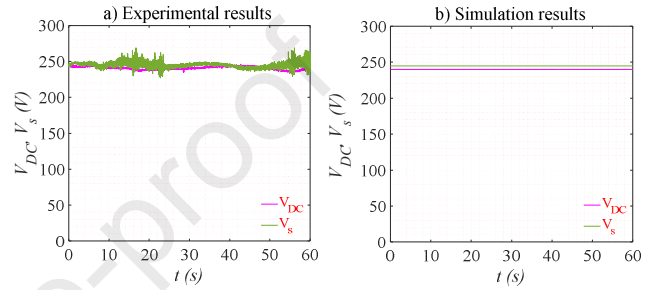
**b) Experimental results.**

**Fig. 22** - DFIG active and reactive power.

Figure 23 shows the required rotor voltages  $V_{dr}$  and  $V_{qr}$  to achieve the needed power. The stator voltage in the experiments is a little disturbed due to measurement fluctuations, the same goes for the DC voltage measurements. For the simulation tests, we use a perfect power source. Thus, The DC bus and the stator voltages stay constant.



**a) DFIG Rotor voltages.**

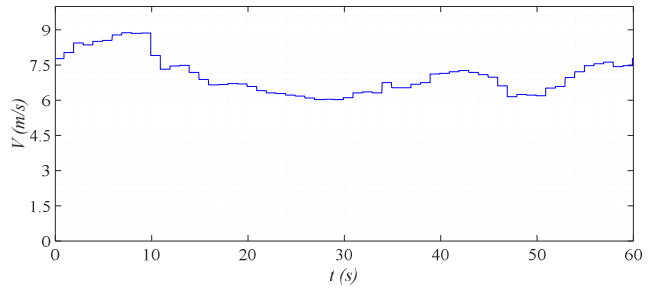


**b) DFIG Rotor, Stator and DC Bus voltages.**

**Fig. 23** – DFIG voltages.

## 6.2 Second test: approximate real wind speed profile

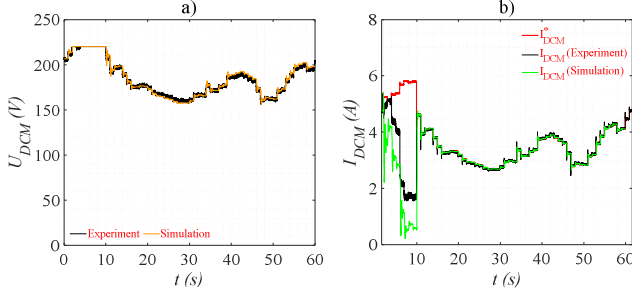
For this test, we have changed the wind speed reference, this time we apply a real wind speed profile to get closer to the actual behavior of a wind turbine power plant (Fig. 24). Therefore, the wind data will be an array of random values from 5.5 to 8.75 m/s includes unbalanced transitions between both operating modes.



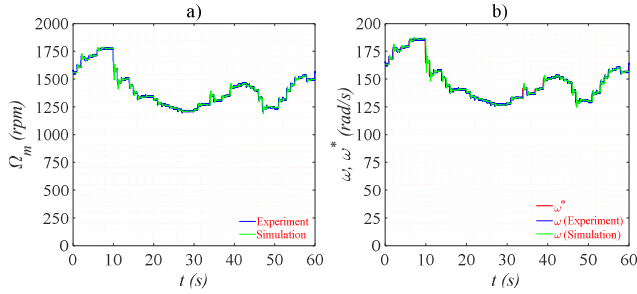
**Fig. 24** - Wind speed profile.

The control loop based on the numerical PI controller for the DC motor current shows high performances as the previous tests (Fig. 25), as well as the speed control loop (Fig. 26).



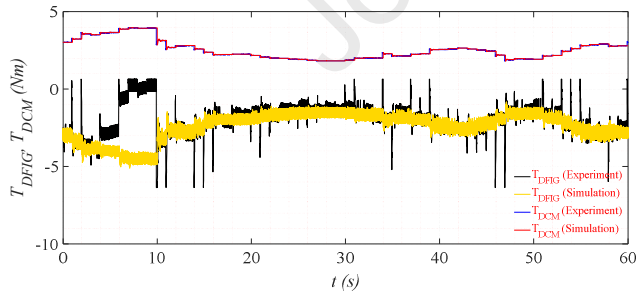


**Fig. 25 - a) DC armature current, b) DC motor voltage.**



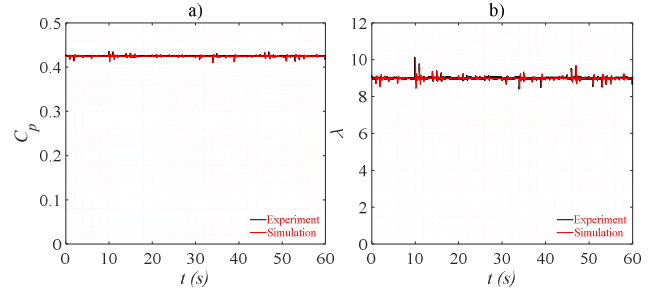
**Fig. 26 - a) WTE Mechanical speed, b) WTE speed control.**

The resulting curves show the same dynamic performances of the WTE control as the previous experiment. The generated torques has a curve identical to that of the wind speed with negligible harmonics (Fig. 27). The high wind speeds between 8 and 10s require a relatively important shaft drive torque, which therefore requires a supply DC motor voltage greater than the limitation at 220 V, necessarily a progressive decrease in armature current, which was accompanied by decrease in the electromagnetic torque with an instantaneous cancellation of the produced energy (Fig. 20).



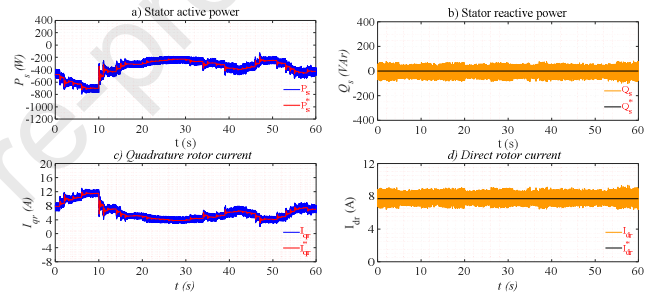
**Fig. 27 - WTE Torques.**

The hardware harmonics have little influence on the quality of the tip speed ratio curve (Fig. 28.b) and the power coefficient quality (Fig. 28.a).

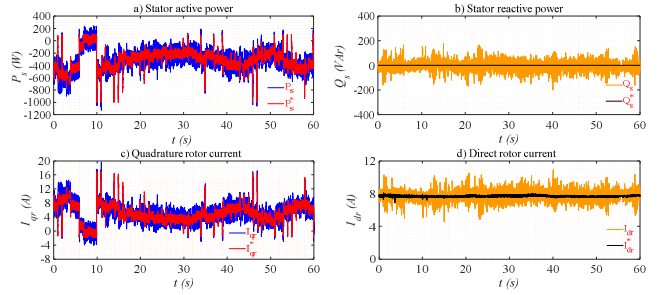


**Fig. 28 - a) Power coefficient, b) Tip speed ratio.**

The estimated active power is still influenced by fluctuation of the measurement which is not so perfect. Thus, it inevitably affects the power quality. In the experimental, the generation of the active energy is stopped when the DC motor voltage reaches its imposed limit. The reactive power of the machine is compensated, so the machine consumes a direct rotor current of 8 A (Fig. 29).



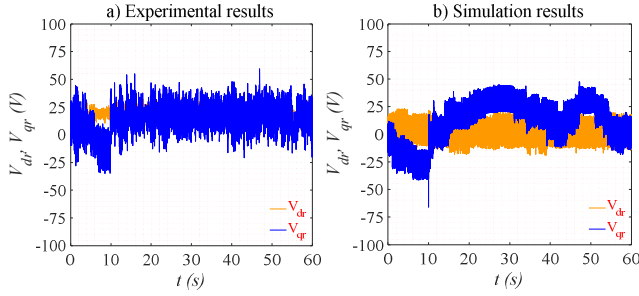
**a) Simulation results.**



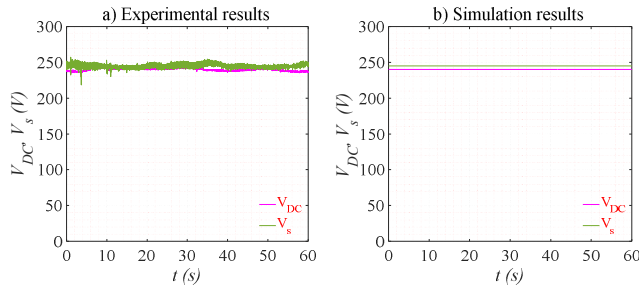
**b) Experimental results.**

**Fig. 29 - DFIG active and reactive power.**

The needed rotor voltages vary according to the actual wind speed references, while the stator and DC bus voltages remain around their nominal values, with some fluctuations (Fig. 30).



a) DFIG Rotor voltages.



b) DFIG Rotor, Stator and DC Bus voltages.

Fig. 30 – DFIG voltages.

The spikes on the active power are due to high frequency noise from the measured rotor current components in Park reference frame ( $I_{dr}$  and  $I_{qr}$ ) of the DFIG. The low-pass filter bandwidth is chosen wide to avoid any lag in the current measurement, but it let pass more hi-frequency contents. High frequency fluctuations also influence electromagnetic torque, the tip speed ratio and power coefficient, unlike simulation tests, where the fluctuations are negligible. In addition to the good physical emulation of the real wind turbine as shown by the tests, the control loops based on PI controllers show good robustness and high performance in the precise monitoring of references of the optimum rotational speed, as well as the imposed armature current.

The experimental and simulation results are approximately identical, thanks to the correct identification of the parameters of both machines and the WTE, therefore, the WTE app was created using the Matlab App Designer, in order to analyze and display the WTE steady-state outputs values (powers, currents, voltages... etc.), according to the WTE inputs which are the instantaneous wind speed, the pitch angle, the ratio of the gearbox... etc [8].

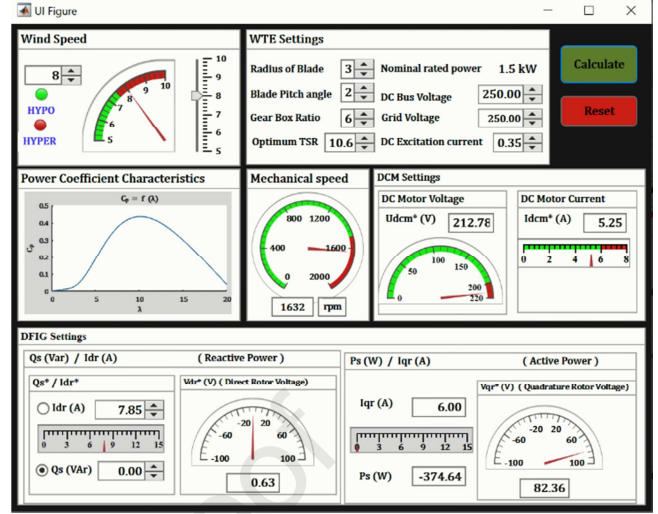


Fig. 31 - WTE steady-state App interface.

The App interface makes possible the definition of the limitation of the hardware protection before starting the simulations or the experiments.

## 8. Conclusion

A relatively low-cost wind energy conversion system was constructed successfully for an emulator test bench, with its associated power electronics and control system and program. The experimental results that affirmed by the simulation tests confirm the validity of the proposed WECS structure and its high performance by using a current controlled DC motor for the emulation of the wind turbine behaviors. On the other hand, the TSR based MPPT algorithm structure is very satisfactory for the extraction of the maximum power available. The DFIG control allows the injection of the active and reactive power to the grid.

The accuracy given by PI control loop affirms the advantage of using this kind of control law sufficiently in wind power system. add to that, the successful implantation of the MPPT algorithm demonstrates the feasibility of the tips speed ratio technique as one of the most efficient solution for the extraction of wind energy.

This work allows the integration of this emulator in another test bench based on a Synchronous Generator and also for testing several linear and nonlinear control algorithms, either for educational use or for the development of research studies. According to national needs in MENA region, there is a need for training a new generation of engineers and researchers in the field of production of renewable energies.

## Declaration of competing interest

The authors declare that they have no known competing financial interests or personal relationships that could have appeared to influence the work reported in this paper.

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## Appendix

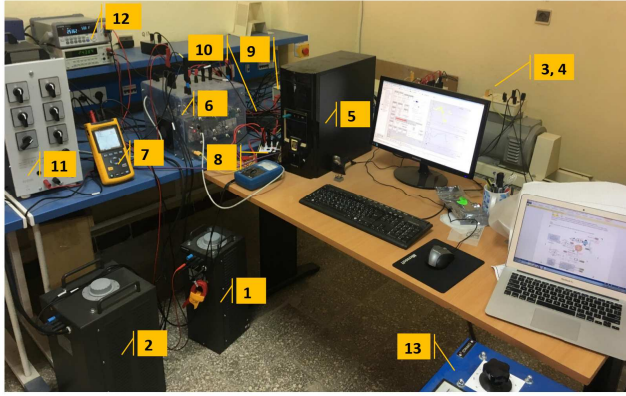


Fig. 32 - WTE Lab Hardware setup.

Table 1 - WTE hardware component.

Component	Name
1, 2	Autotransformer (stator side, rotor side respectively)
3, 4	DFIG & DCM respectively
5	PC
6	Inverter and Rectifier
7	Fluke 43B Power Quality Analyzer
8, 9	Measure interfaces (DCM & DFIG respectively)
10	DS1104 interface
11	Rheostat
12	$V_s$ , $V_{DC}$ Measures
13	Power supply (DCM excitation)

Table 2 - WTE Settings.

Settings	Parametres
$P_n$	1.5 kW
$\Omega_m$	1500 rpm
$R$	3 m
$G$	7
$\beta$	2°
$\lambda_{opt}$	11.68
$\rho$	1.225

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# Improved hardware implementation of a TSR based MPPT algorithm for a low cost connected wind turbine emulator under unbalanced wind speeds

Dekali Zouheyr<sup>a</sup>, Baghli Lotfi<sup>a,b</sup>, Boumediene Abdelmadjid<sup>a</sup><sup>a</sup>*LAT, Laboratoire d'Automatique de Tlemcen, Université de Tlemcen 13000, Tlemcen, Algeria*<sup>b</sup>*Université de Lorraine, GREEN, EA 4366, Vandœuvre lès-Nancy, F-54500, France*

## 1. Tables

**Table 1 - WTE hardware component.**

Component	Name
1, 2	Autotransformer (stator side, rotor side respectively)
3, 4	DFIG & DCM respectively
5	PC
6	Inverter and Rectifier
7	Fluke 43B Power Quality Analyzer
8, 9	Measure interfaces (DCM & DFIG respectively)
10	DS1104 interface
11	Rheostat
12	$V_s$ , $V_{DC}$ Measures
13	Power supply (DCM excitation)

**Table 2 - WTE Settings.**

Settings	Parameters
$P_n$	1.5 kW
$\Omega_m$	1500 rpm
R	3 m
G	7
$\beta$	2°
$\lambda_{opt}$	11.68
$\rho$	1.225



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## 1. Highlights

- Experimental hardware description
- Modeling and control of WTE
- TSR Based MPPT algorithm structure
- The proposed WTE
- DFIG Modeling and control