



UNIVERSITY OF MINNESOTA

Nonlinear Oscillators & Low-inertia Power Systems

Sairaj Dhople

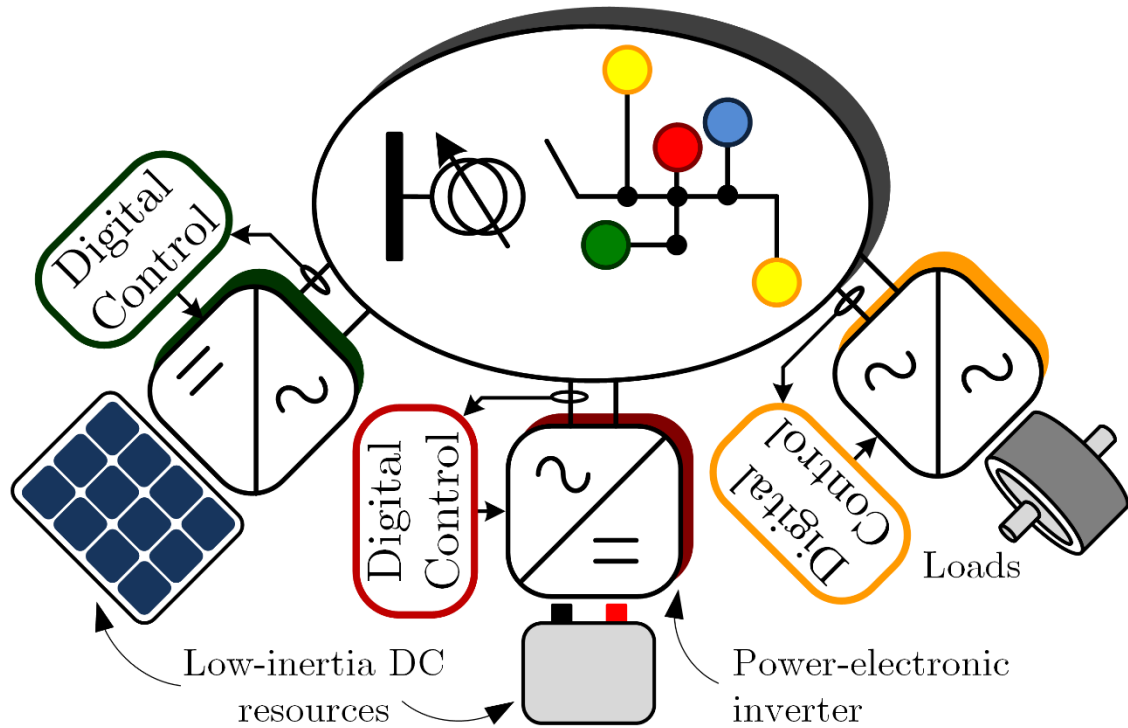
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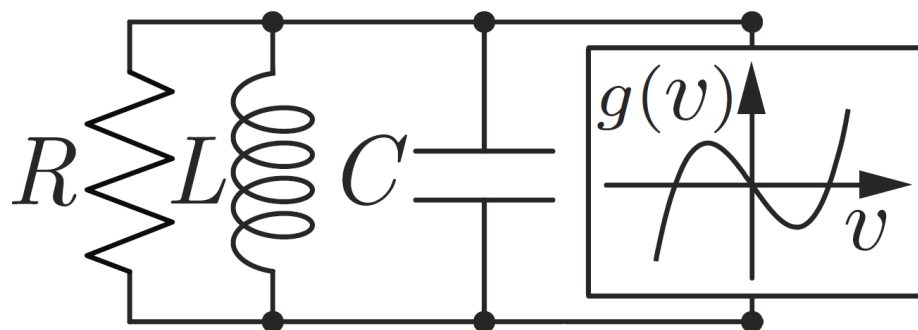


Low-inertia Power System





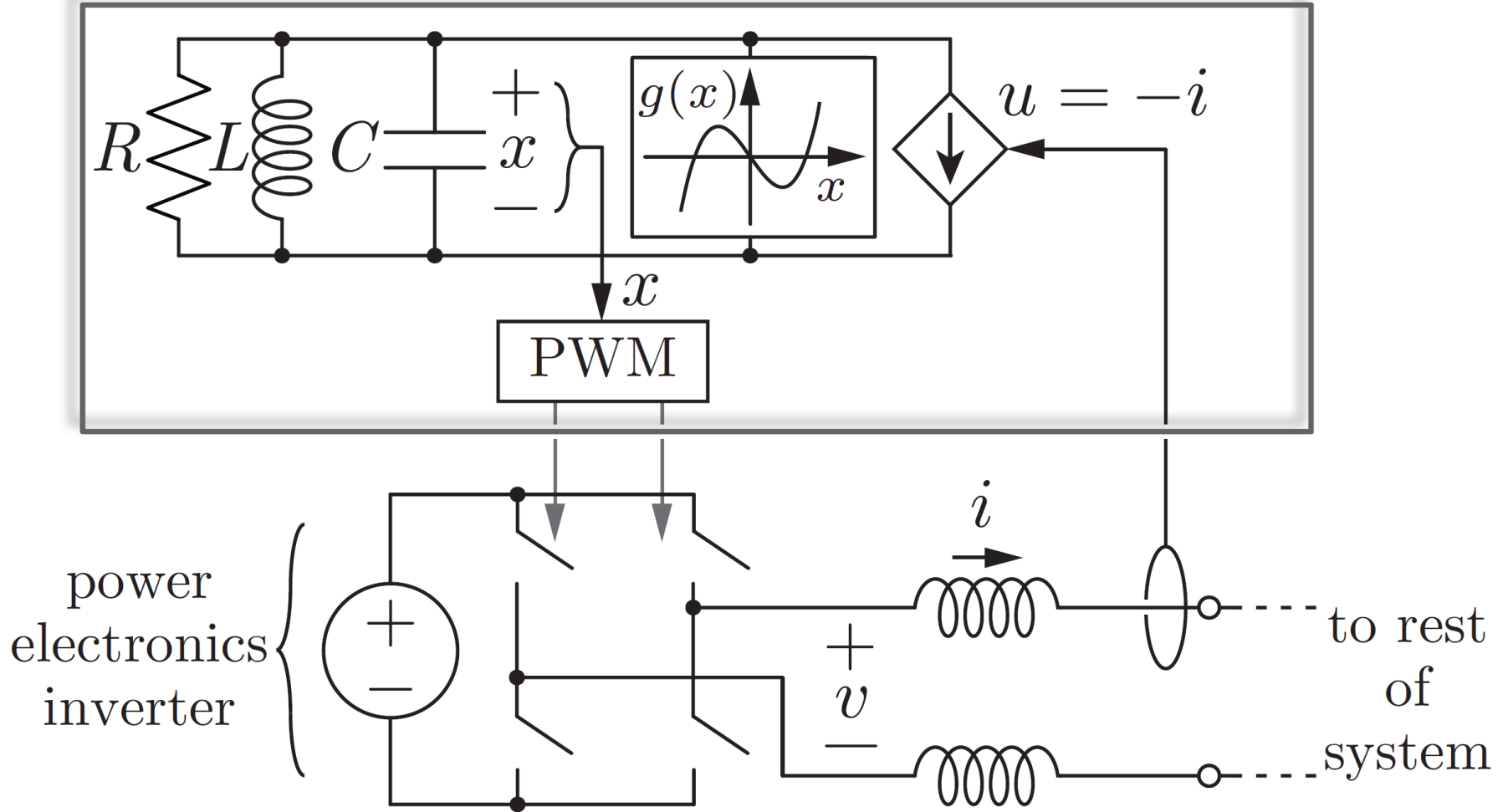
Nonlinear Oscillator



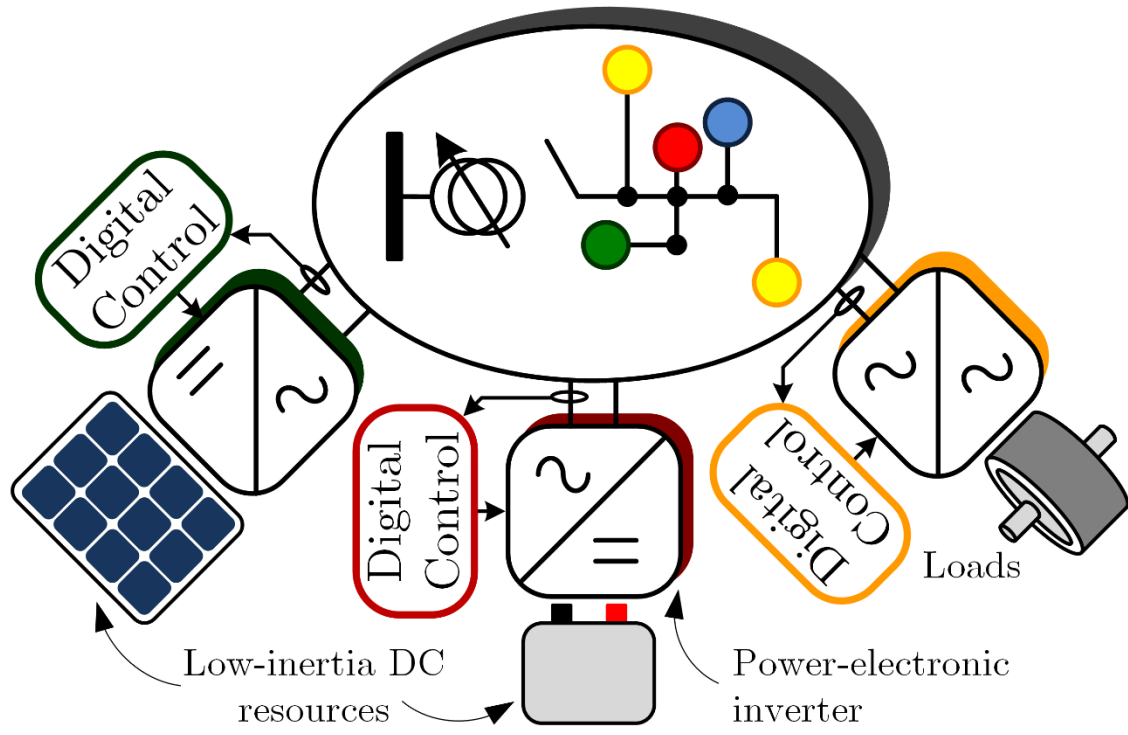


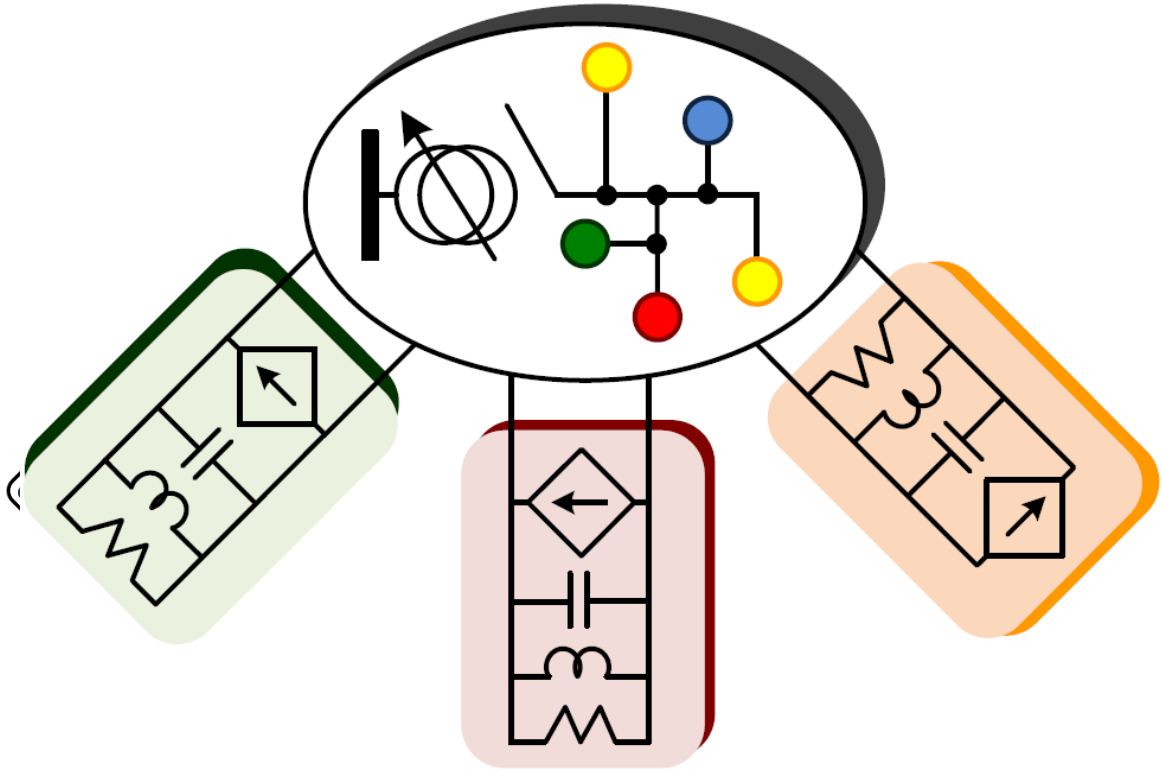
Connecting the two

Inverter Microcontroller



VOC- Virtual Oscillator Control

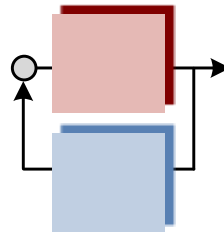


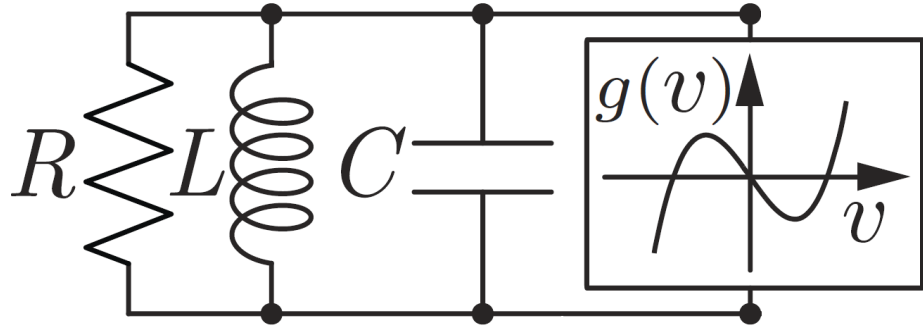




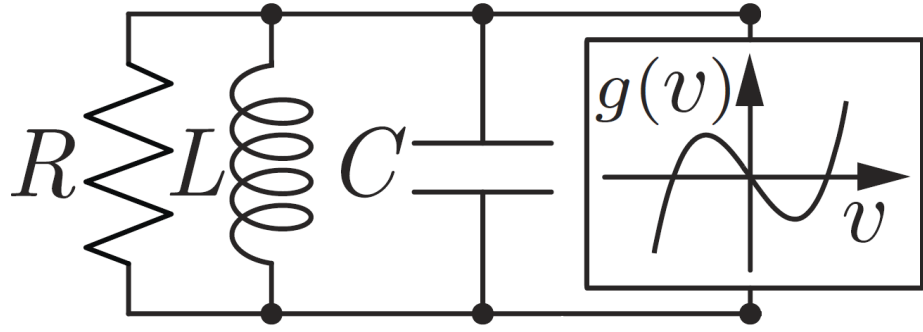
State of the Art

- Droop Control
- Inverters mimic synchronous machines
- Main disadvantages:
 - Slow dynamics (aggressive filtering)
 - Rigid hierarchical control (inner and outer control loops)





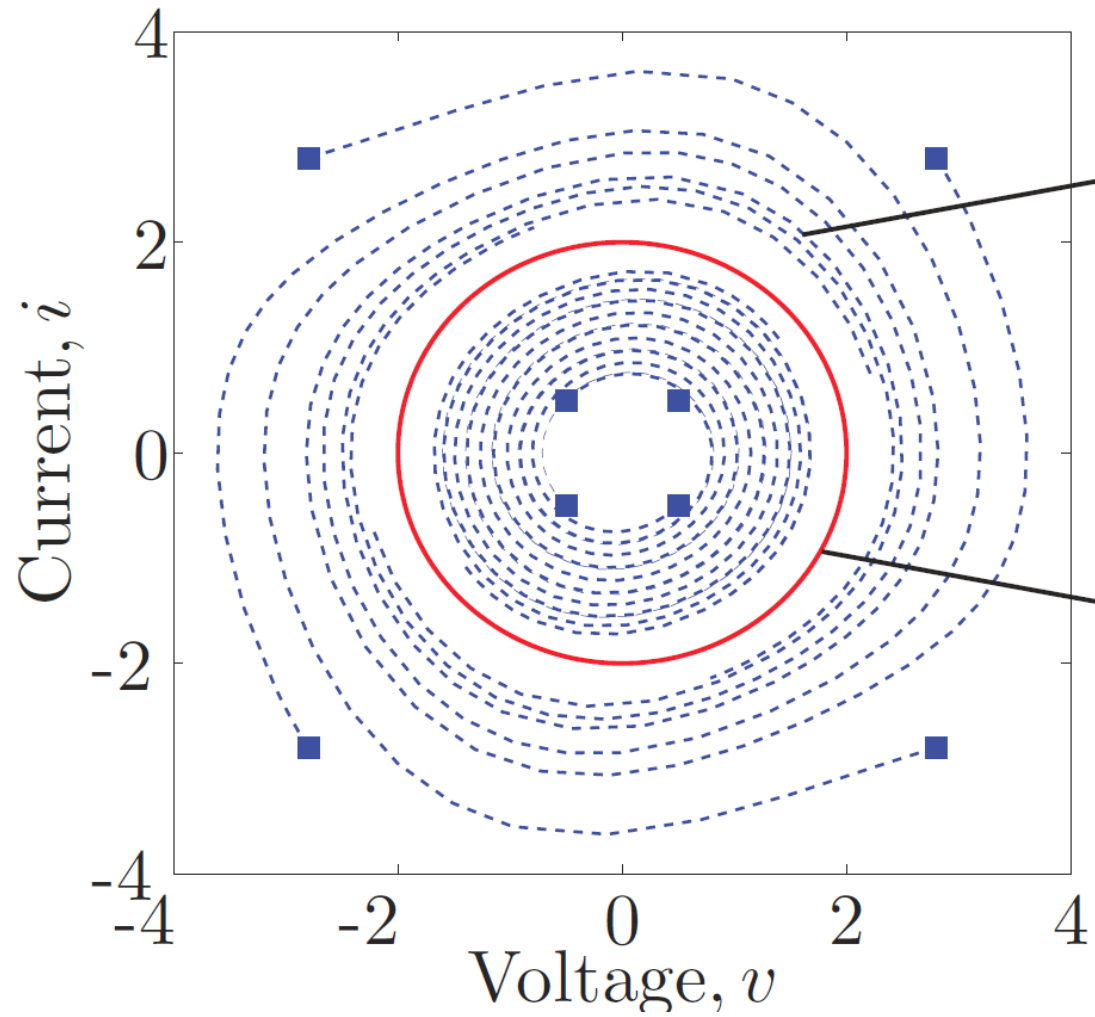
- Time-domain control
- System-wide synchrony
- Backward compatibility



- Time-domain control
- System-wide synchrony
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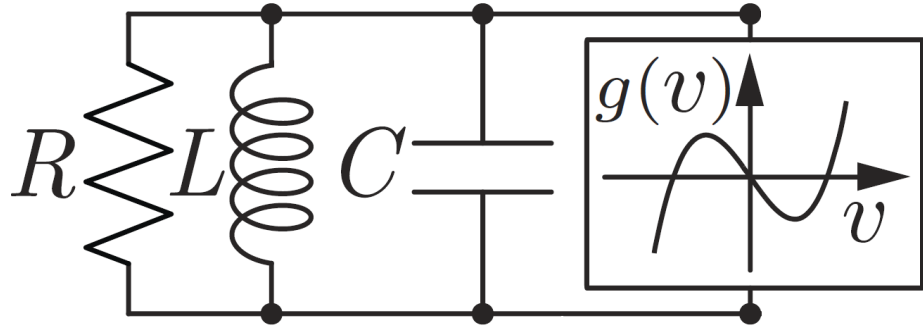


Time-domain Control



VOC stabilizes arbitrary waveforms to sinusoidal steady state

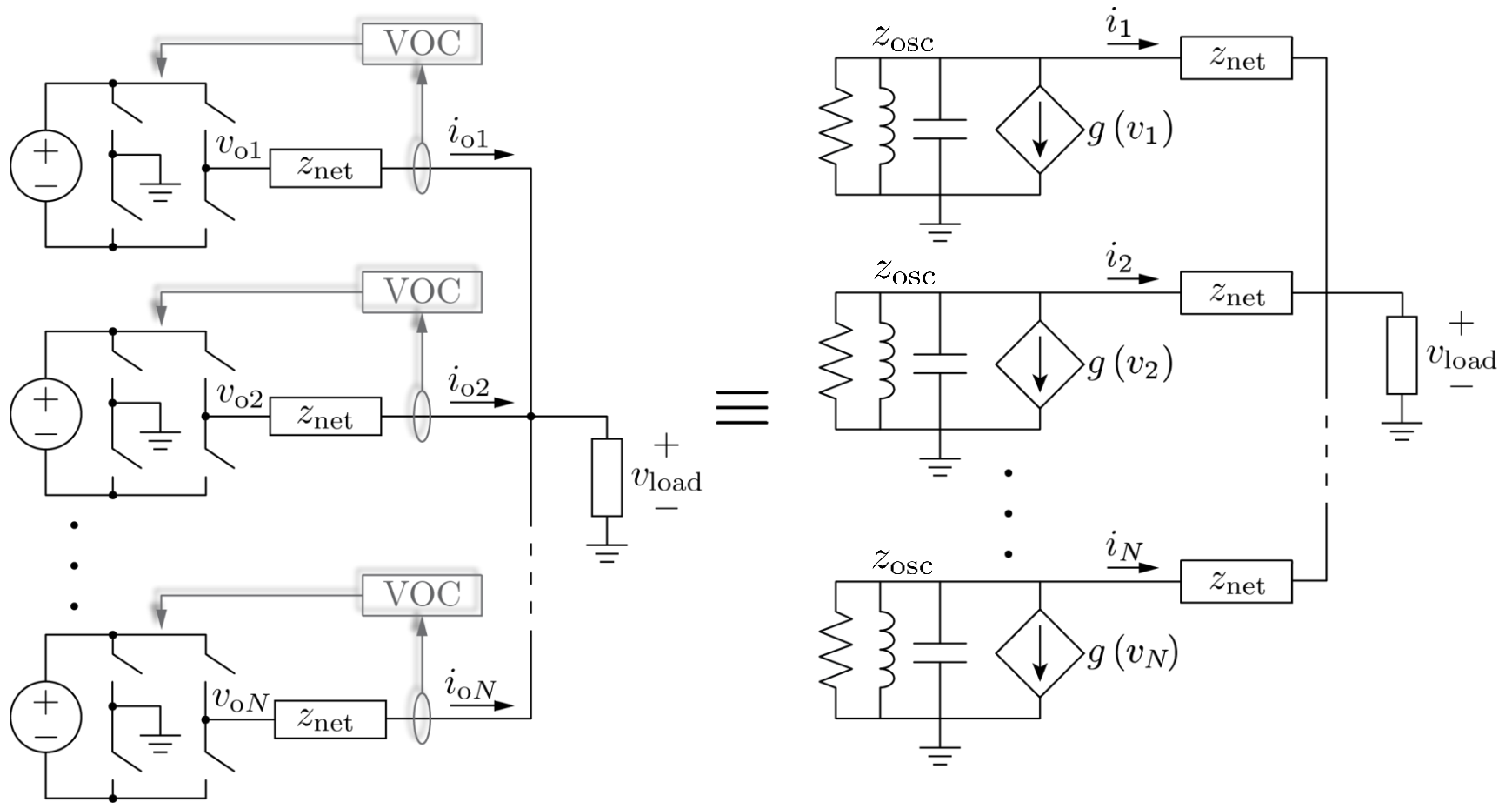
Droop control only acts on sinusoidal steady state



- Time-domain control
- System-wide synchrony
- Backward compatibility



System-wide Synchrony

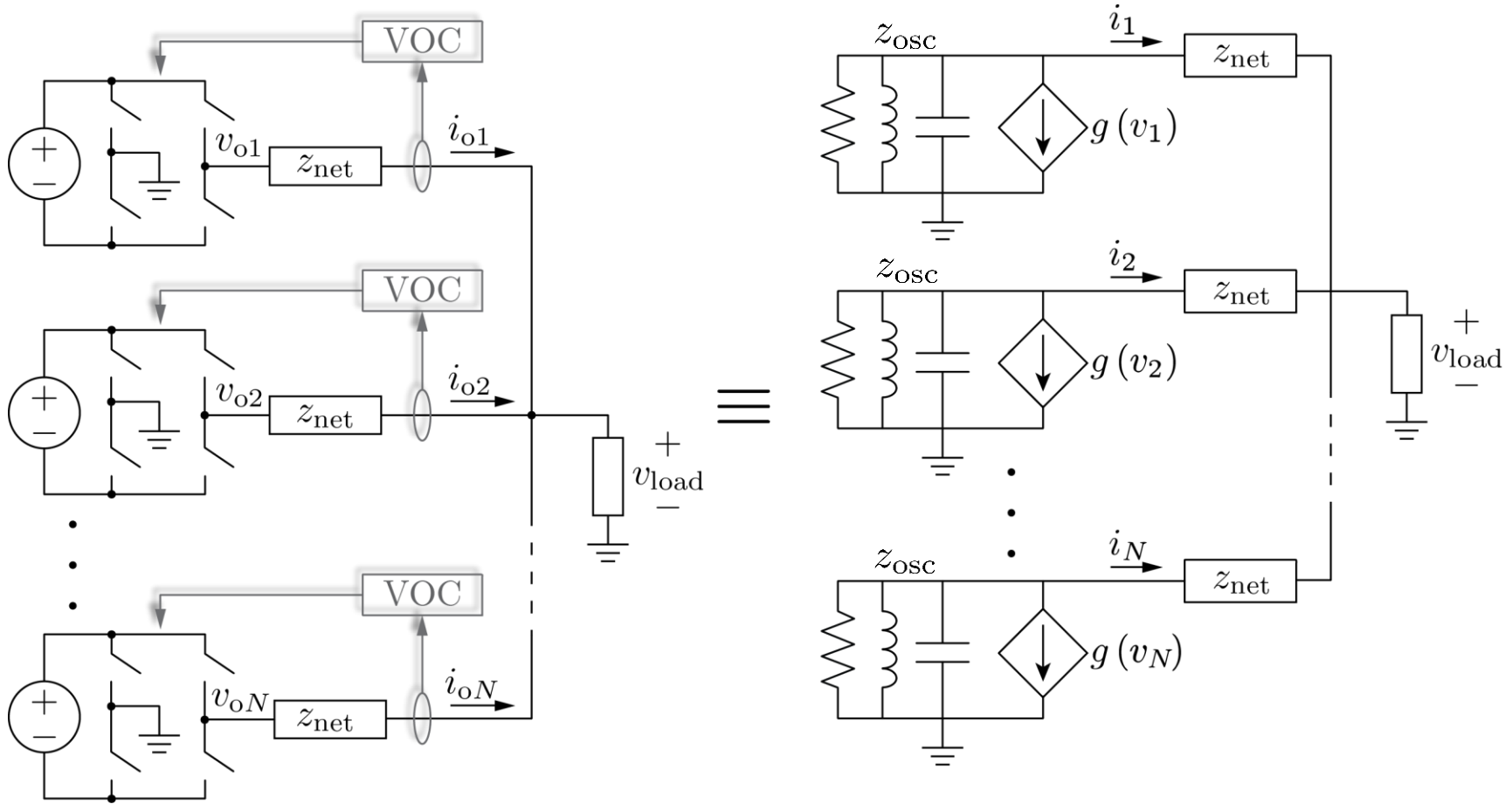


Condition for global asymptotic synchronization

$$\sup_{\omega \in \mathbb{R}} \left\| \frac{z_{net}(j\omega) z_{osc}(j\omega)}{z_{net}(j\omega) + z_{osc}(j\omega)} \right\|_2 \sigma < 1$$



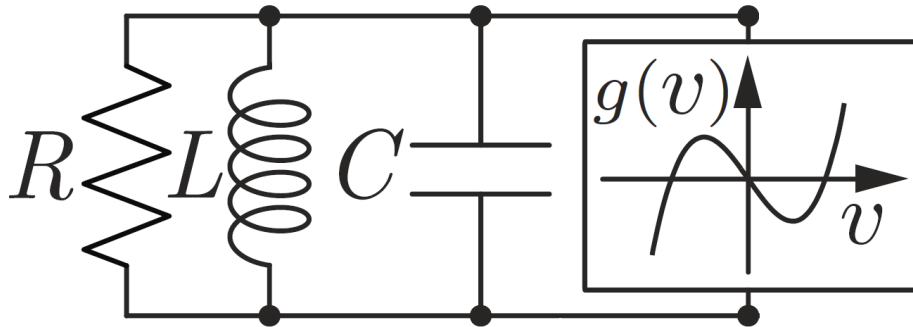
System-wide Synchrony



Condition for global asymptotic synchronization

$$\sup_{\omega \in \mathbb{R}} \left\| \frac{z_{net}(j\omega) z_{osc}(j\omega)}{z_{net}(j\omega) + z_{osc}(j\omega)} \right\|_2 \sigma < 1$$

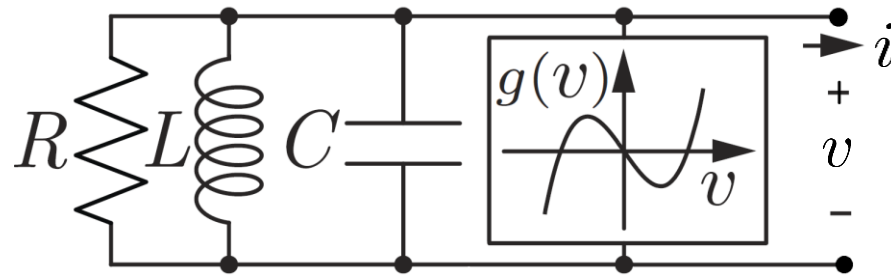
- Modular
- Robust
- Resilient



- Time-domain control
- System-wide synchrony
- **Backward compatibility**



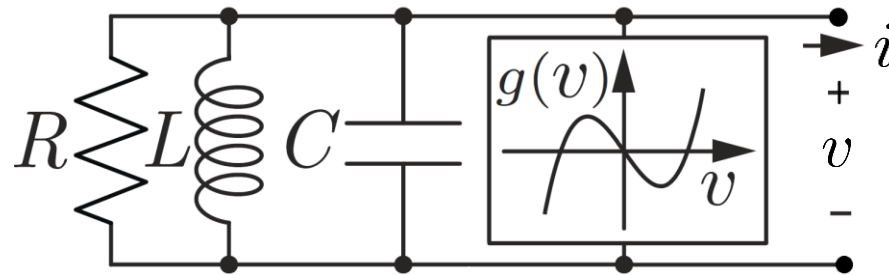
Original Dynamics



$$\frac{d^2 v}{dt^2} + \left(\frac{1}{RC} - \frac{g'(v)}{C} \right) \frac{dv}{dt} + \frac{v}{LC} = -\frac{1}{C} \frac{di}{dt}$$



Averaged Dynamics

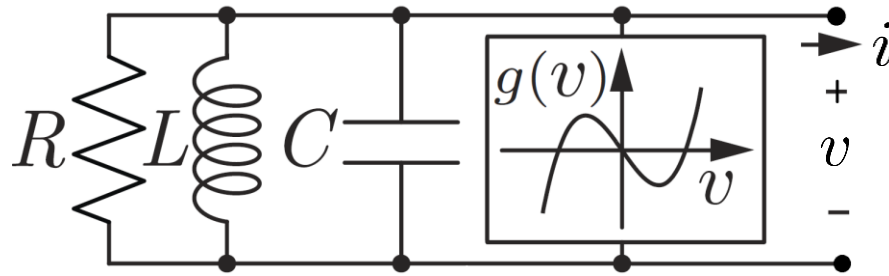


$$\frac{d^2 v}{dt^2} + \left(\frac{1}{RC} - \frac{g'(v)}{C} \right) \frac{dv}{dt} + \frac{v}{LC} = -\frac{1}{C} \frac{di}{dt}$$

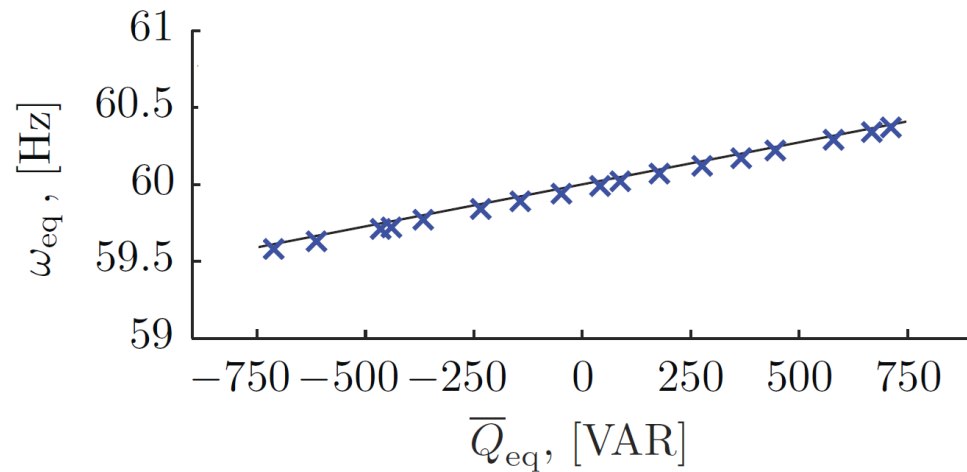
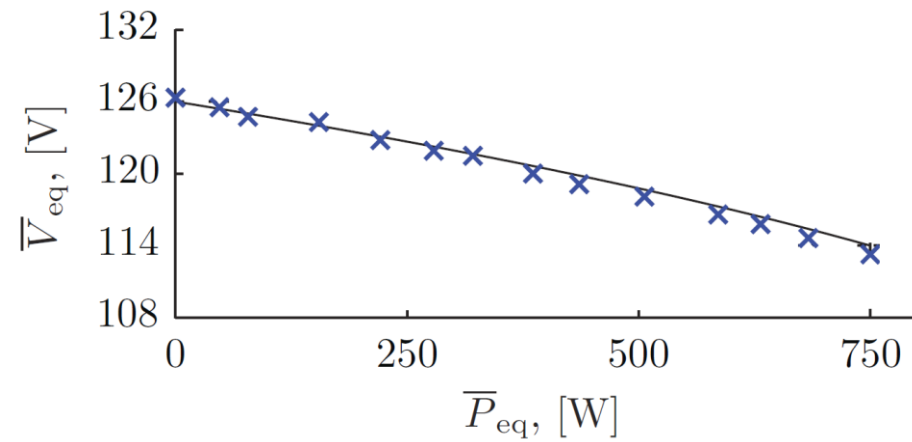
$$\frac{d}{dt} r = \bar{g}(r) - \frac{1}{rC} P, \quad \frac{d}{dt} \theta = +\frac{1}{r^2 C} Q$$



Backward Compatibility



$$\frac{d}{dt}r = \bar{g}(r) - \frac{1}{rC}P, \quad \frac{d}{dt}\theta = +\frac{1}{r^2C}Q$$

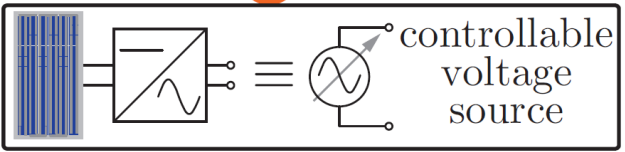
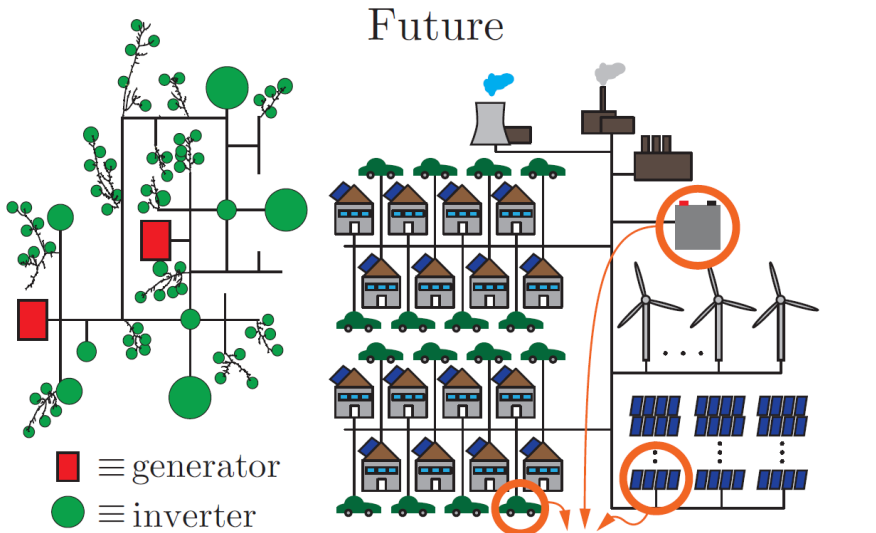
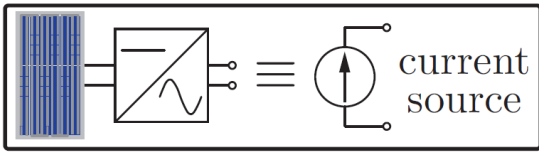
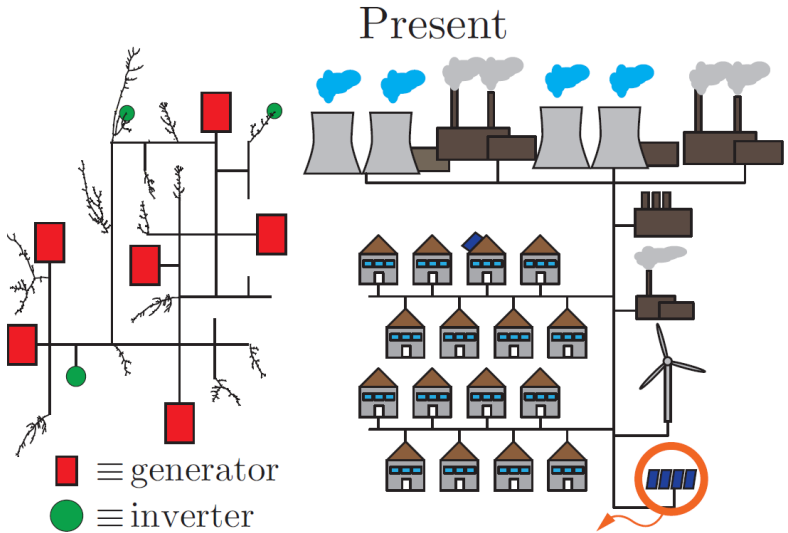


× Experimental

— Analytical



Context





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Comments?

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