

Aeolus

Wind Farm Control Concepts

Supervisory Wind Farm Control Strategy

Gerrit van der Molen and Petros Savvidis,

Industrial Systems and Control

EWEA 2011

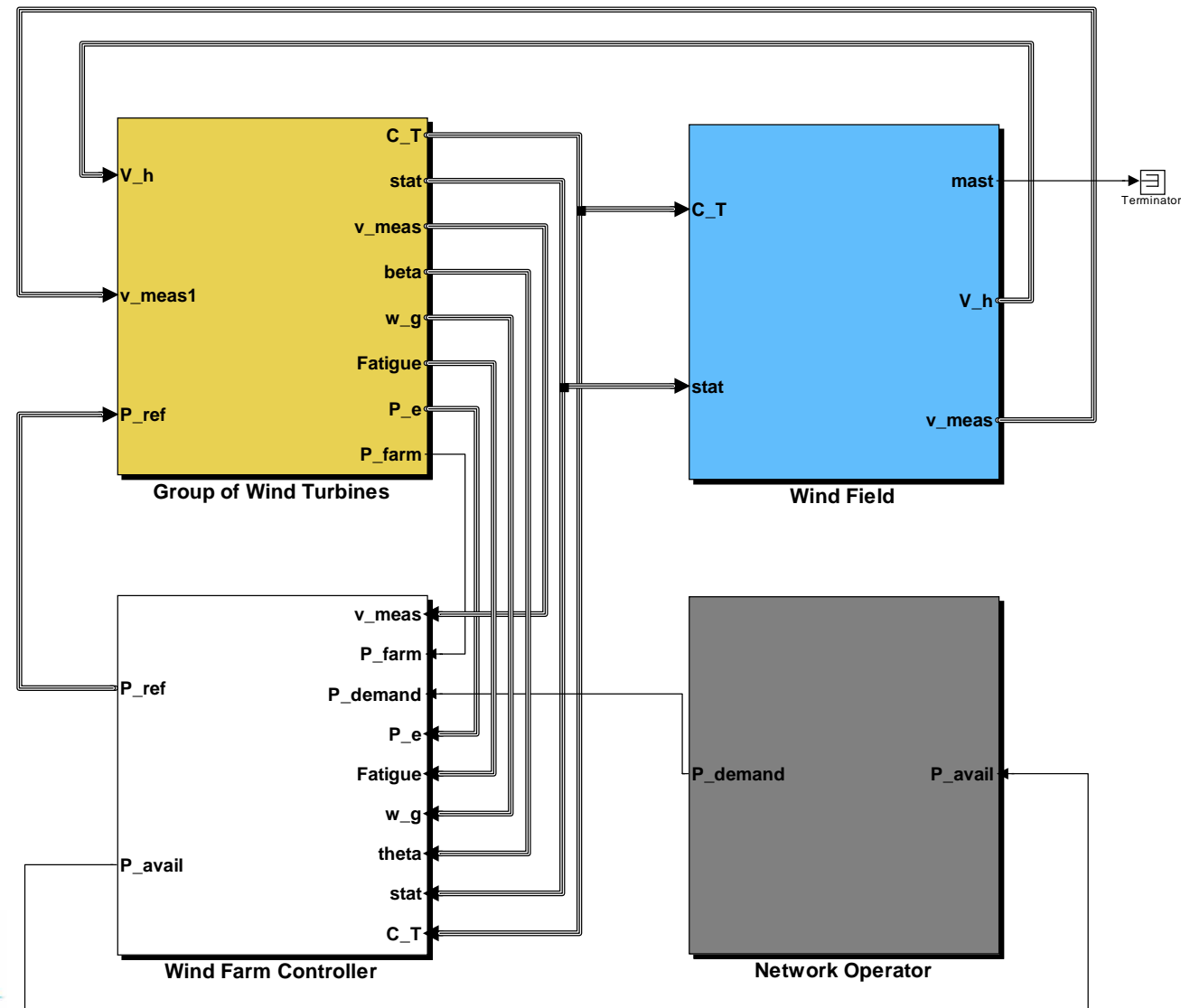
Outline of Presentation

- Introduction
- Control strategy
 - Selection and development
- Simulation results
- Summary

Introduction

- Control objectives
 - Track farm active power demand
 - Minimise Wind Turbine (WT) fatigue load
 - Continuous control, not on-off
- MPC-based strategy
 - Track record in large systems

System Structure



Review Summary

- Farm-control work in research stage
 - Based on simulation models of small WFs
 - No evidence of effectiveness & scalability to large WFs
- Exception: PI strategy used in Horns Rev WF
- Fatigue loads not considered in WT power ref
 - Exception: de Almeida et al. work based on optimisation
 - Fatigue load different from AEOLUS proposal
 - On/off switching i.l.o. continuous load variations
- Few address nonlinearity

Controller Requirements

- Robustness
 - Wind variations
- Scalability
 - Design procedure independent of farm size
- Algorithm flexibility
 - Farm parameters (e.g. no. of WTs, dimensions)
- MPC meets general requirements

Supervisory Control System

1. Nominal control - ISC

- Obtain optimal distribution of WF power reference based on wind flow model
- Adapt to 'slow' changes in wind farm operating conditions
 - 5-10 s sample time

2. Reconfiguration extension – Univ. of Zagreb

- Minimize impact of disturbances on wind farm behaviour
 - Keep wind farm behaviour as close as possible to optimal
- Actively compensate disturbances related to faster dynamics inherent to wind farm

Model Linearisation

- Wind turbine
 - Use models developed by Univ. of Zagreb
 - (Re-)Sampled to 10 seconds
- Wind field
 - Simpler nonlinear model than WT
 - Original field model; later more complex
 - Affine model + delay
 - Gain estimated by sensitivity analysis
 - Delay = distance/wind_speed

MPC Formulation

- Standard GPC state-space formulation
 - E.F. Camacho & C. Bordons, *Model Predictive Control* (2nd Edition), Springer-Verlag, 2004

- Time-varying KF for state estimation enhanced with GPC prediction matrices to produce future output signals
 - M. J. Grimble and P. Majecki, "State-space approach to nonlinear predictive generalized minimum variance control", *International Journal of Control*, 2010

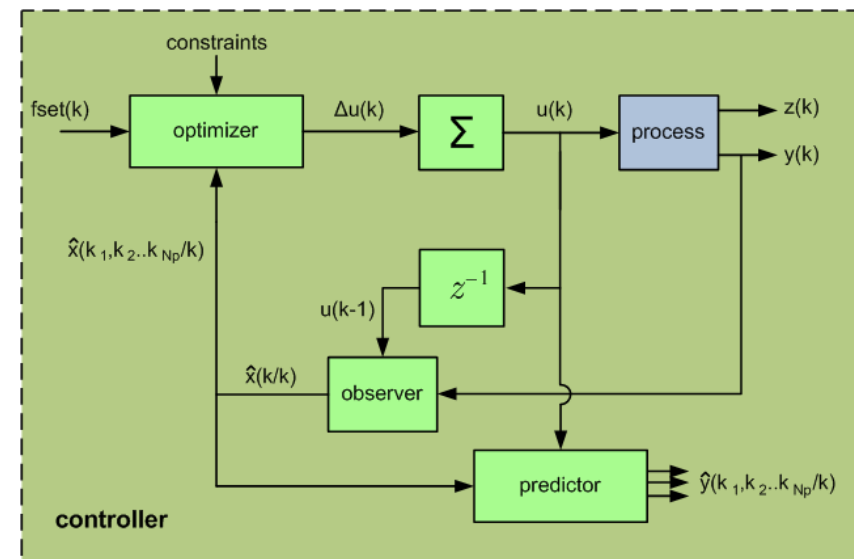
- Quadratic cost function → QP solver online

$$J = (y(t) - R_{\text{fut}})^T Q_w (y(t) - R_{\text{fut}}) + \Delta u(t)^T \lambda_w \Delta u(t)$$

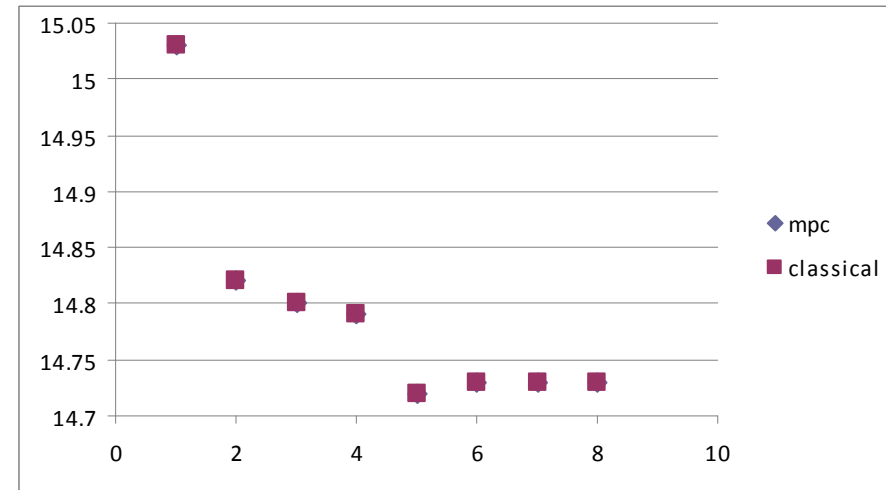
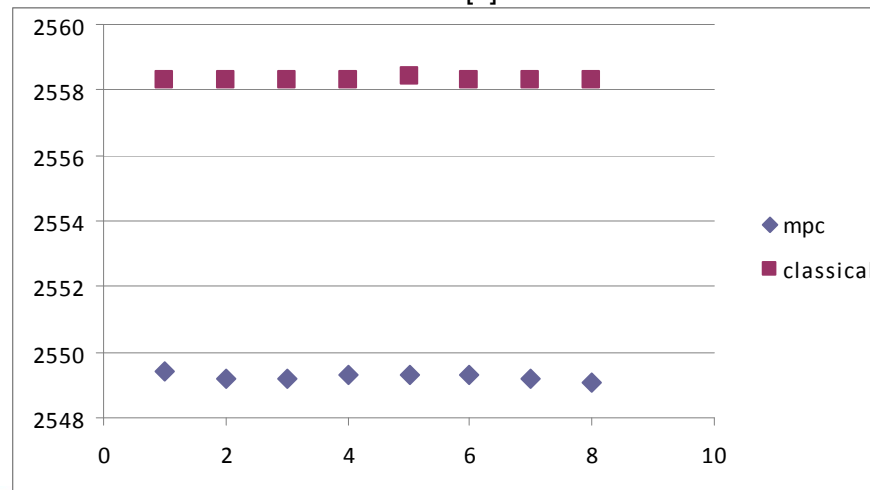
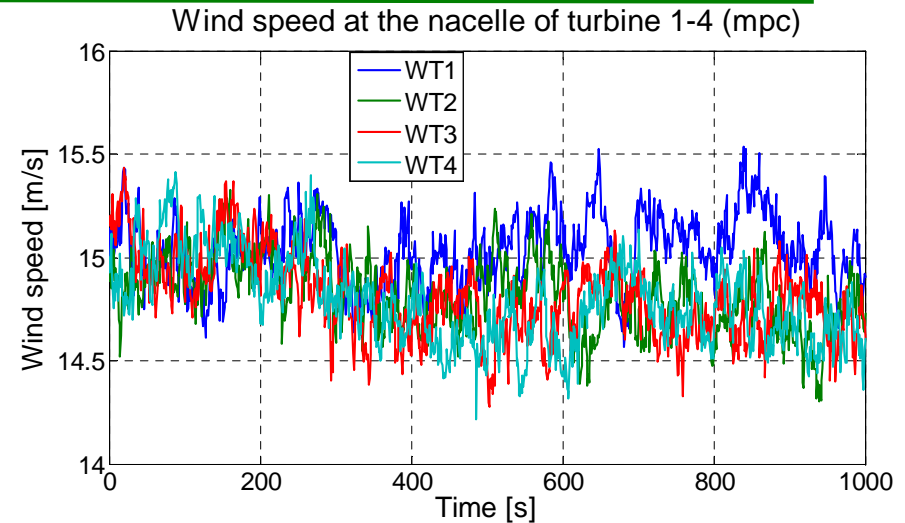
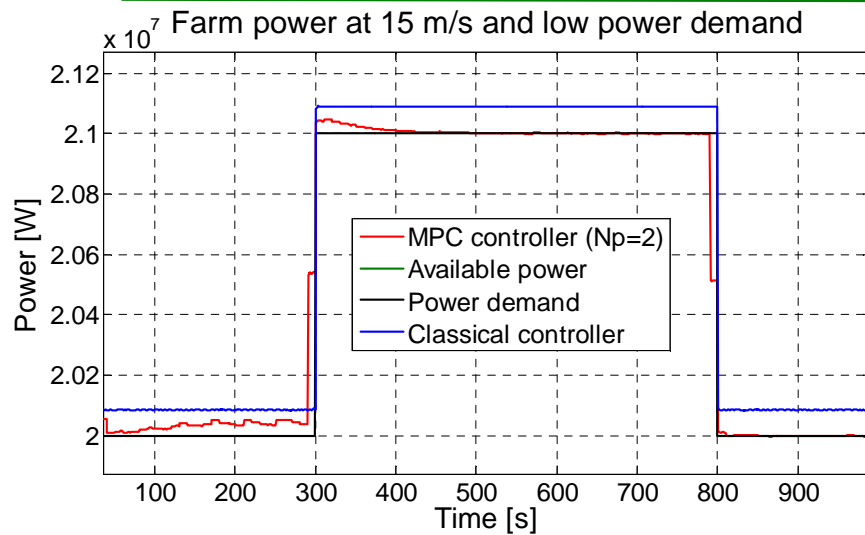
- Incremental model realization

$$\begin{bmatrix} x(t+1) \\ u(t) \end{bmatrix} = \begin{bmatrix} A & B \\ 0 & I \end{bmatrix} \begin{bmatrix} x(t) \\ u(t-1) \end{bmatrix} + \begin{bmatrix} B \\ I \end{bmatrix} \Delta u(t),$$

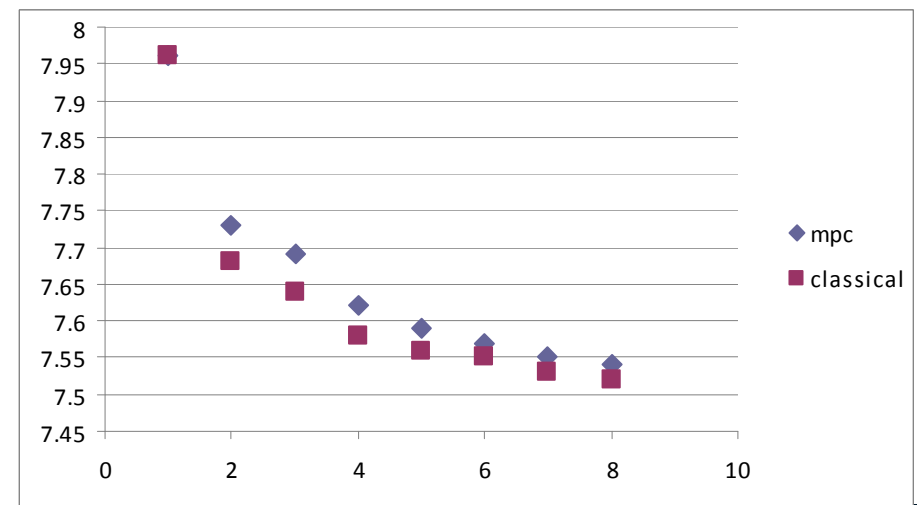
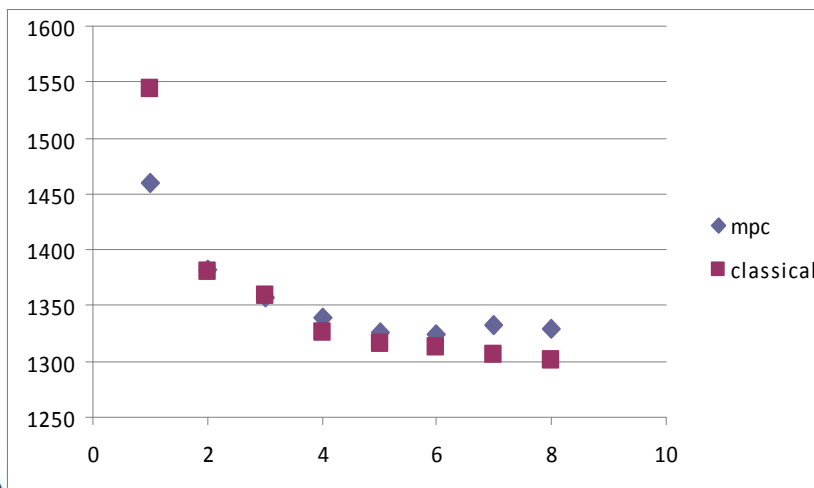
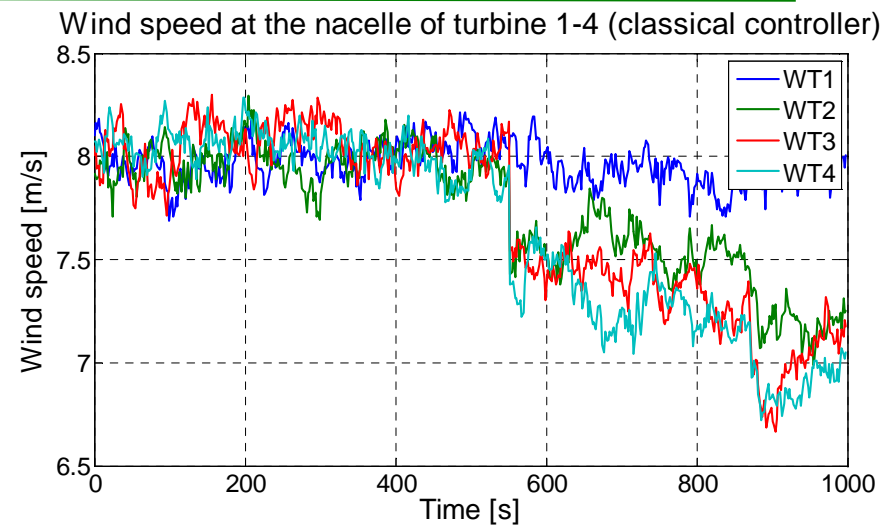
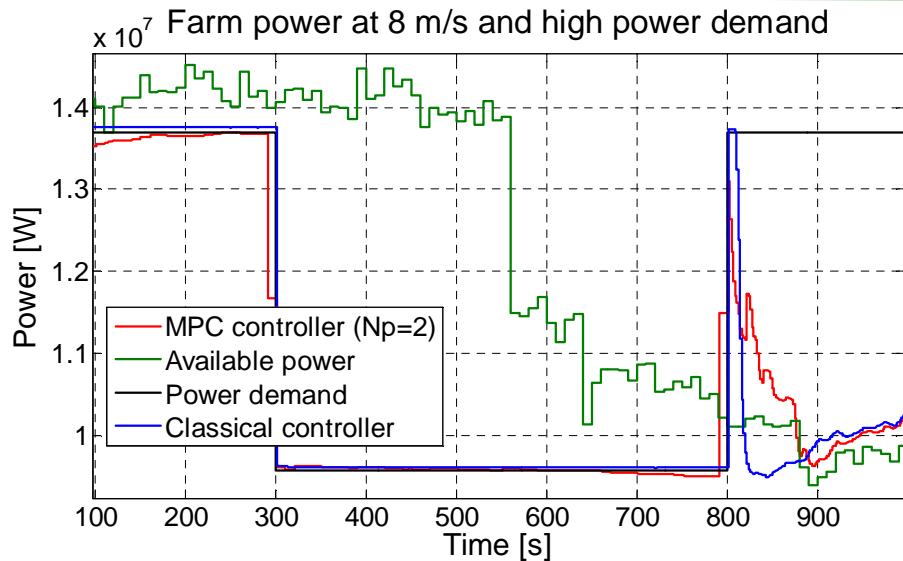
$$y(t) = \begin{bmatrix} C & 0 \end{bmatrix} \begin{bmatrix} x(t) \\ u(t-1) \end{bmatrix}$$



MPC at High Wind Speed Low Power Demand

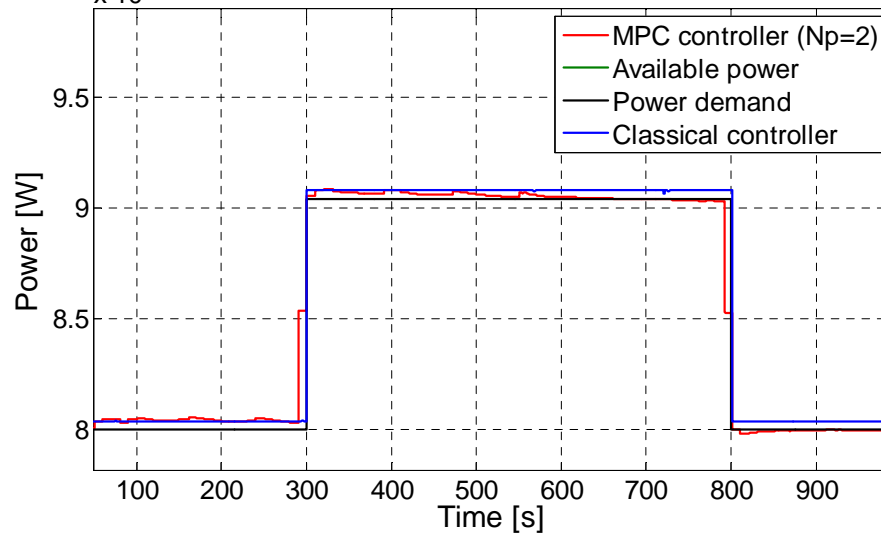


MPC vs. Base at Low Wind Speed High Power Demand

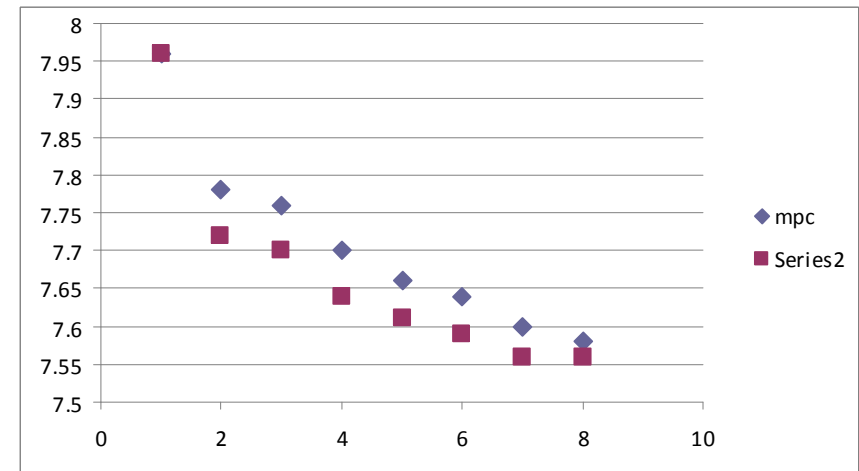
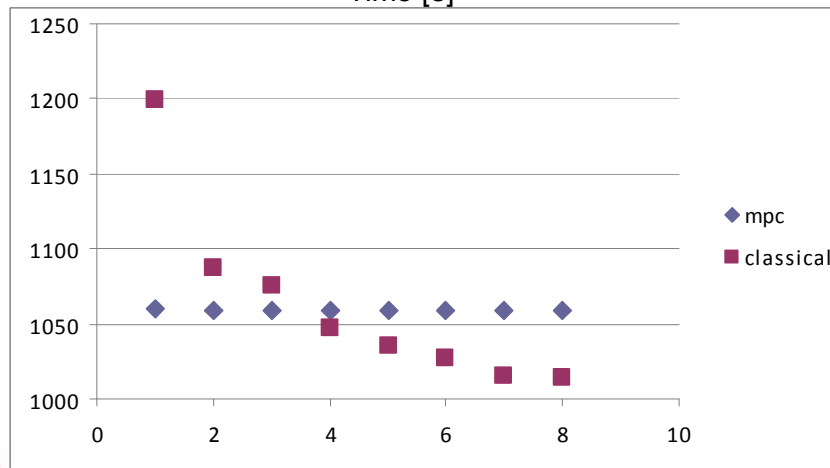
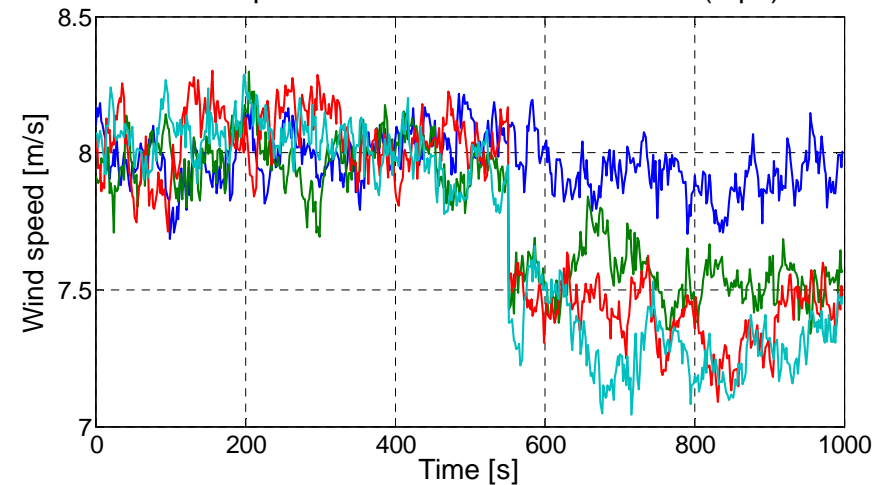


MPC vs. Base at Low Wind Speed Low Power Demand

$\times 10^6$ Farm power at 8 m/s and low power demand



Wind speed at the nacelle of turbine 1-4 (mpc)



RMS Reductions

High wind speed	High Pfarm	Low Pfarm
Total cost	0.50 %	1.00 %
Relative power error	42.50 %	43.00 %
Relative M _{tow} (RMS)	0.21 %	0.31 %
Relative M _{tow} (STD, 10-sample window)	-0.23 %	-0.22 %

Low wind speed	High Pfarm	Low Pfarm
Total cost	2.03 %	2.70 %
Relative power error	10.77 %	50.48 %
Relative M _{tow} (RMS)	1.40 %	3.35 %
Relative M _{tow} (STD, 10-sample window)	13.36 %	36.08 %

Questions?

Gerrit van der Molen

Industrial Systems and Control
Glasgow, UK

T: +44(0)141-8470515

E: gerrit@isc-ltd.com

W: www.isc-ltd.com

Aeolus

FP7-ICT STREP 224548

W: www.ict-aeolus.eu