

# Direct torque control for an autonomous photovoltaic system with MPPT control

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**ABSTRACT** This work deals with the control of a photovoltaic pumping system. It is based on an induction motor, and direct torque control (DTC) is applied. The method adopted is based on the instantaneous space vector theory. By optimal selection of the space voltage vectors in each sampling period, DTC archives effective control of the stator flux and torque. The most important advantage of this method is its rotor position free control system. To improve photovoltaic (PV) system performances, Perturb & Observe maximum power point tracking (MPPT) algorithm has been used to achieve sufficient power to operate the water pumping system under variable conditions. Through this work, it is aimed to obtain a simple and low-cost system for the photovoltaic water pumping systems with rapid tracking of the maximum power. The proposed system with DTC and MPPT strategy not only improves system performance but also extends the working hours of solar photovoltaic systems. Simulation of the adopted method is also presented.

**Keywords:** Photovoltaic, Water Pumping, Direct Torque Control, Maximum power point tracking

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## 1. INTRODUCTION

The output power induced in the photovoltaic modules depends on climatic conditions [1-3]. To maximize power, several MPPT algorithms have been used [4-18]. The most used control consists to act on the duty cycle automatically to place the generator at its optimal value whatever the variations of the metrological conditions or sudden changes in loads. To track the maximum power point (MPP), a look-up table on a microcomputer is employed by Ramli et al [4]. It is based on the use of a database that includes parameters and data such as typical curves of the PV generator for different irradiances and temperatures. In the curve-fitting method, the nonlinear characteristic of the PV generator is modeled using mathematical equations or numerical approximations. These two algorithms have a disadvantage that they may require a large memory capacity, for calculation of the mathematical formulations and storage of the data. The open-circuit voltage photovoltaic generator method is employed by Karami et al [5]. It approximates linearly the voltage of PV generator at the MPP to its open-circuit voltage and a linear dependency between the current at the MPP and the short-circuit current for the short circuit photovoltaic generator method presented by Reisi et al [6]. These methods are simple and economical, but they are not able to adapt to changeable environmental conditions [7-9].

Presented perturb and observe (P&O) algorithm which is based on iterative algorithms to track continuously the MPP through the current and voltage measurement of the PV module. Most control schemes use the P&O technique because it is easy to implement, but the oscillation problem is unavoidable [10]. The conductance incremental algorithm named as "IncCond" presented by Ghayed et al [11] requires a complex control circuit. The two last strategies have some disadvantages such as; high cost, complexity, and instability. Also, intelligent algorithms based on control by MPPT were introduced [12-18]. The fuzzy logic controller (FLC) optimizes the magnitude of the increment to obtain fast and fine tracking [10]. In sliding mode controller (SMC), the control circuit adjusts the duty cycle of the switch control waveform to obtain MPPT as a function of the evolution of the power input at the DC/DC converter. Neuro-fuzzy systems are fuzzy systems based on the theory of neural networks algorithm (ANN). The learning technique operates according to the local information and produces only local changes in the fuzzy system origin. If the MPPT algorithm performances must be optimal, even for a complex implementation, the choice will be relatively focused on advanced algorithms. If the implementation simplicity is preferred, the choice will be based on classical algorithms [4-8].

The control of induction motors has gained a lot of attention both in academia and industry, recently. One of the most significant developments in this area has been the field-oriented control where partial feedback linearization, together with a proportional-integral. This technique is very useful even though it is very sensitive to parameter variations such as rotor time constant and incorrect flux measurement or estimation at low speeds. DTC for induction machines (IM) is a robustness control method for motor drives. It provides a better solution to improve motor characteristics and the voltage inverter source [19-20]. In principle, the DTC method is performed with the instantaneous space vector theory. Thus, the number of space voltage vectors and switching frequency directly influence the performance of the DTC control system.

In this work, a DTC-IG system of a photovoltaic system is proposed. An application has been performed for water pumping. The P&O MPPT is applied to the studied system which can be considered as a low-cost prototype used for photovoltaic water pumping system and quick tracking of maximum power.

The studied system is modeled and simulated under the MATLAB environment, and obtained results by simulation are presented.

**2. MODELING OF THE PROPOSED SYSTEM**

In the case of a method speed drive system of an induction motor supplied by a PV generator, two types of stand-alone PV systems can be considered [2].

- A structure with two static converters.
- A single static converter structure.

In this paper, the second structure, which needs only one converter, has been used. In this case, the proposed system is represented in Figure 1. It consists of an induction motor fed by a photovoltaic generator through a three-phase voltage inverter controlled by the DTC technique.

*2.1. Photovoltaic Array Modelling*

*2.1.1. One diode model*

The equivalent circuit consists of a single diode for the phenomena of cell polarization and two resistors (series and shunt) for the losses is presented in Figure 2.

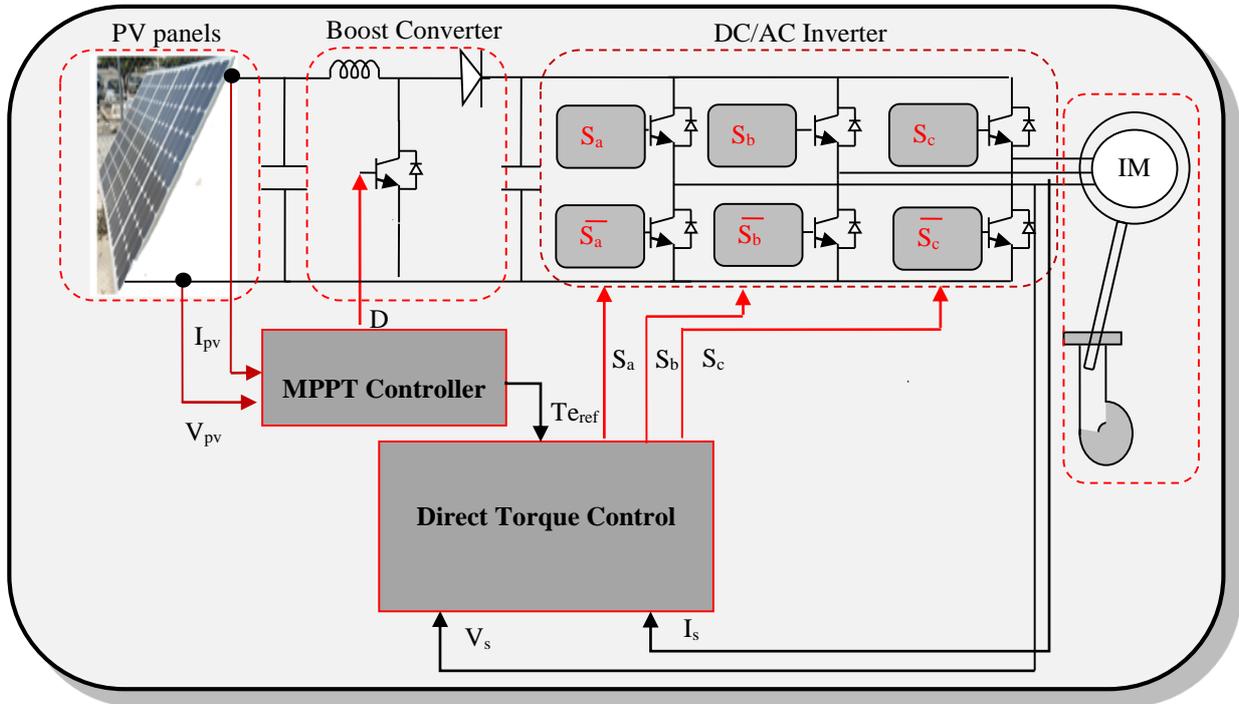


Fig.1. Proposed studied system

This model is given by the following Equation (1):

$$I_{pv} = I_{ph} - I_d - I_{Rsh} \tag{1}$$

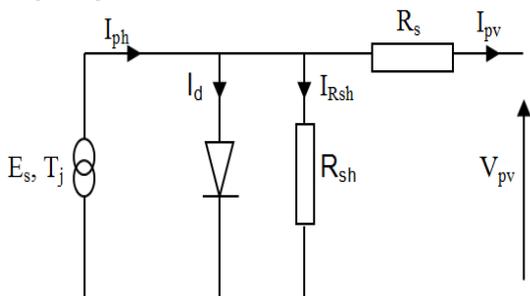


Fig. 2. Equivalent circuit (one diode model) [2]

This model is characterized by a very simple resolution. It requires only four parameters namely  $I_{sc}$ ,  $V_{oc}$ ,  $V_{mp}$ , and  $I_{mp}$ . The model is as follows [2]:

$$I_{pv} = I_{sc} \left\{ 1 - C_1 \left[ \exp\left(\frac{V_{pv}}{C_2 \cdot V_{oc}}\right) - 1 \right] \right\} \tag{2}$$

$$C_2 = \frac{\left(\frac{V_m}{V_{oc}}\right) - 1}{\ln\left(1 - \frac{I_m}{I_{sc}}\right)} \tag{3}$$

$$C_1 = \left(1 - \frac{I_m}{I_{sc}}\right) \exp\left(-\frac{V_m}{C_2 \cdot V_{oc}}\right)$$

2.1.2 Two diode model

In this model, the two diodes represent the PN junction polarization phenomena. These diodes represent the recombination of the minority carriers which are located both at the surface of the material and within the volume of the material as in Figure 3.

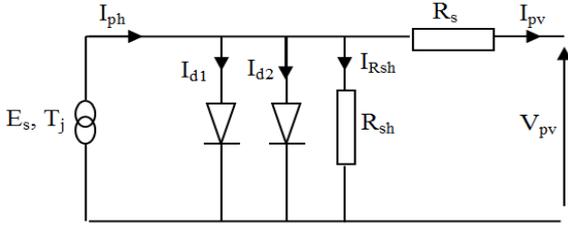


Fig. 3. The equivalent circuit for two diode model

The following equation is then obtained:

$$I_{pv} = I_{ph} - (I_{d1} + I_{d2}) - I_{Rsh} \tag{4}$$

With  $I_{ph}$  and  $I_{Rsh}$  maintaining the same expressions as above. For the recombination currents, we have:

$$\begin{cases} I_{d1} = I_{o1} \cdot \left[ \exp\left(\frac{q \cdot (V_{pv} + R_s \cdot I_{pv})}{A \cdot N_s \cdot k \cdot T_j}\right) - 1 \right] \\ I_{d2} = I_{o2} \cdot \left[ \exp\left(\frac{q \cdot (V_{pv} + R_s \cdot I_{pv})}{2 \cdot A \cdot N_s \cdot k \cdot T_j}\right) - 1 \right] \end{cases} \tag{5}$$

The saturation currents are written as follows;

$$\begin{cases} I_{o1} = P_4 \cdot T_j^3 \cdot \exp\left(\frac{-E_g}{k \cdot T_j}\right) \\ I_{o2} = P_5 \cdot T_j^3 \cdot \exp\left(\frac{-E_g}{2 \cdot k \cdot T_j}\right) \end{cases} \tag{6}$$

Where  $N_s$  is the number of cells in branched series,  $E_g$  represents the gap energy. The final equation of the model is written as:

$$I_{pv} = P_1 \cdot E_s \cdot \left[ 1 + P_2 \cdot (E_s - E_{sref}) + P_3 \cdot (T_j - T_{ref}) \right] \cdot \frac{(V_{pv} + R_s \cdot I_{pv})}{R_{sh}} \cdot P_{04} \cdot T_j^3 \cdot \exp\left(\frac{-E_g}{k \cdot T_j}\right) \cdot \left[ \exp\left(\frac{q \cdot (V_{pv} + R_s \cdot I_{pv})}{A \cdot N_s \cdot k \cdot T_j}\right) - 1 \right] - P_{14} \cdot T_j^3 \cdot \exp\left(\frac{-E_g}{2 \cdot k \cdot T_j}\right) \cdot \left[ \exp\left(\frac{q \cdot (V_{pv} + R_s \cdot I_{pv})}{2 \cdot A \cdot N_s \cdot k \cdot T_j}\right) - 1 \right] \tag{7}$$

Validation has been made using PV panel Siemens SM110-24 as seen in Table1.

Parameters	Values
$P_{mpp}$	110W
$I_{mpp}$	3.15A
$V_{mpp}$	35V
$I_{sc}$	3.45A
$V_{oc}$	43.5V
$\alpha_{sc}$	1.4mA/°C
$\beta_{oc}$	-152mV/°C

Results of power characteristics are obtained by different mathematical models and those obtained by experiment are presented in Figures 4-6. With:  $E_s$  solar irradiation (W/m<sup>2</sup>) and  $T_a$  ambient temperature (°C). It is noticed a good agreement between experimental and simulation characteristics especially in low and moderate irradiances which validates the mathematical model. The error on power is much greater for the two diode model. The one diode model results are closest to the experimental ones, therefore this model is adopted in current study.

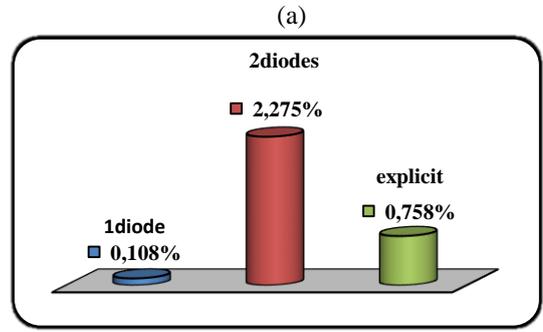
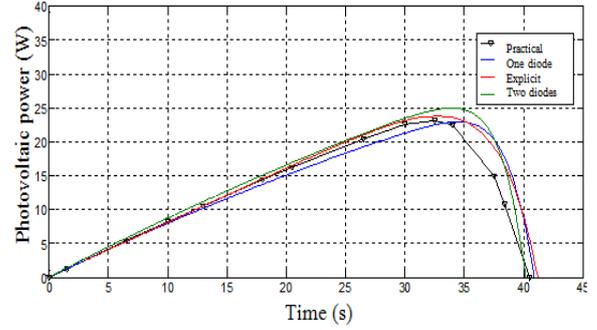


Fig. 4. Power characteristic at  $E_s=244$  W/m<sup>2</sup>,  $T_a=24$ °C, (a)Photovoltaic power, (b)Power error calculation

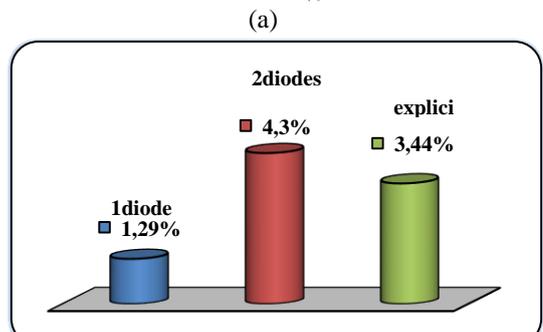
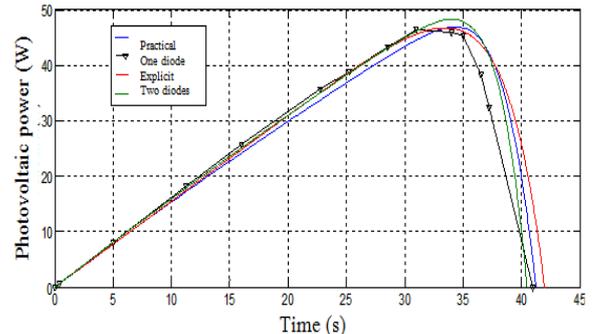
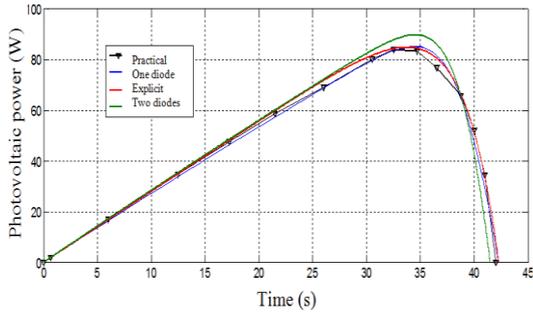
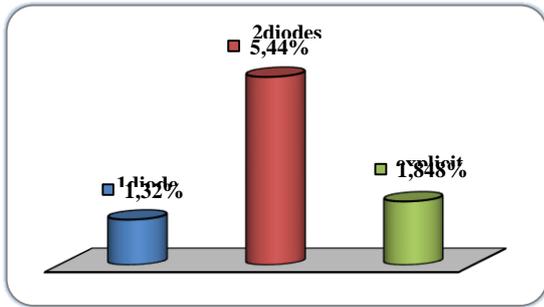


Fig. 5. Power characteristic at  $E_s=460$  W/m<sup>2</sup>,  $T_a=29$ °C, (a)Photovoltaic power, (b)Power error calculation



(a)



(b)

Fig. 6. Power characteristic at  $E_s=856 \text{ W/m}^2$ ,  $T_a=32^\circ\text{C}$ , (a)Photovoltaic power, (b)Power error calculation

## 2. 2. MPPT Algorithm

Many methods have been developed to determine the MPPT control. In this paper, the P&O method is used due to its implementation simplicity in photovoltaic water pumping system. The flowchart of the P&O algorithm is given in Figure 7.

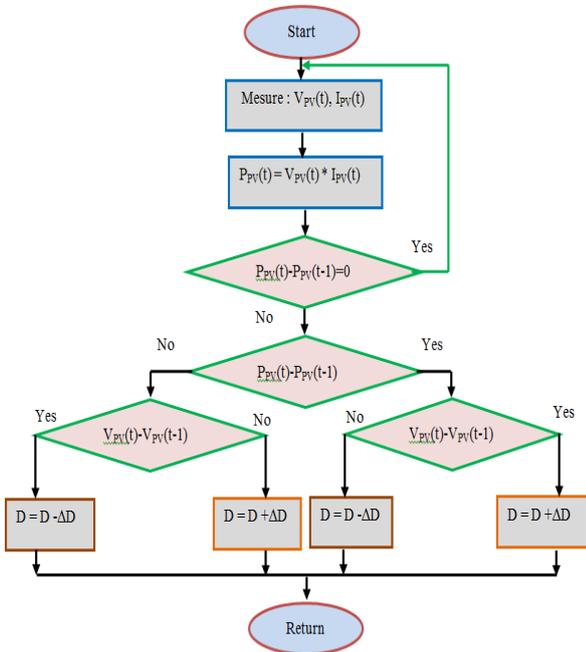


Fig. 7. Flowchart of the P&O MPPT algorithm

The panel voltage is deliberately perturbed, then the power is compared to the power obtained before to disturbance. Specifically, if the power panel is increased due to the disturbance, the following disturbance will be made in the same direction. If the power decreases, the new perturbation is made in the opposite direction.

## 2.1. Machine Modelling

An induction motor is modelled using voltage and flux equations, which are referred to as a general frame and are shown as follows:

Stator voltage equations:

$$\begin{cases} V_{S\alpha} = R_S I_{S\alpha} + \frac{d\Phi_{S\alpha}}{dt} \\ V_{S\beta} = R_S I_{S\beta} + \frac{d\Phi_{S\beta}}{dt} \end{cases} \quad (8)$$

where:  $I_{S\alpha}$ ,  $I_{S\beta}$  are for  $\alpha$ ,  $\beta$  stator currents respectively.  $\Phi_{S\alpha}$ ,  $\Phi_{S\beta}$  are for  $\alpha$ ,  $\beta$  stator flux respectively,  $R_S$  is the stator resistance.

$$\begin{cases} 0 = V_{R\alpha} = R_R I_{R\alpha} + \frac{d\Phi_{R\alpha}}{dt} + \frac{d\theta}{dt} \Phi_{R\beta} \\ 0 = V_{R\beta} = R_R I_{R\beta} + \frac{d\Phi_{R\beta}}{dt} - \frac{d\theta}{dt} \Phi_{R\alpha} \end{cases} \quad (9)$$

where:  $I_{R\alpha}$ ,  $I_{R\beta}$  are for  $\alpha$ ,  $\beta$  rotor current respectively,  $\Phi_{R\alpha}$ ,  $\Phi_{R\beta}$  are for  $\alpha$ ,  $\beta$  rotor flux respectively,  $R_r$  is the rotor resistance.

$$\begin{cases} \Phi_{S\alpha} = L_S I_{S\alpha} + L_m I_{R\alpha} \\ \Phi_{S\beta} = L_S I_{S\beta} + L_m I_{R\beta} \\ \Phi_{R\alpha} = L_R I_{R\alpha} + L_m I_{S\alpha} \\ \Phi_{R\beta} = L_R I_{R\beta} + L_m I_{S\beta} \end{cases} \quad (10)$$

Mechanical equations:

$$T_e - T_L = J_m \cdot \frac{d\omega_r}{dt} \quad (11)$$

$$T_e = P \times (\phi_{s\alpha} \times I_{s\beta} - \phi_{s\beta} \times I_{s\alpha})$$

where:  $T_e$  is the electromagnetic torque,  $T_L$  the load torque,  $J_m$  the inertia,  $P$  is the pole number and  $\omega_r$  the rotor angular speed.

## 2. 3. Inverter Modelling

For each possible switching configuration, the output voltages can be represented in terms of space vector, according to the following equation:

$$V_s = V_{s\alpha} + jV_{s\beta} = \sqrt{\frac{2}{3}} \left[ V_a + V_b \exp\left(j\frac{2\pi}{3}\right) + V_c \exp\left(j\frac{4\pi}{3}\right) \right] \quad (12)$$

where:  $V_a$ ,  $V_b$ , and  $V_c$  are phase voltages.

## 2.4. Pumping System Modelling

The model of the power input (P) is given as [14]:

$$P(h, Q) = a(h).Q^3 + b(h).Q^2 + c(h).Q + d(h) \quad (13)$$

where:  $a(h)$ ,  $b(h)$ ,  $c(h)$ ,  $d(h)$  are the different coefficients:

$$a(h) = a_0 + a_1 h^1 + a_2 h^2 + a_3 h^3 \quad (14)$$

$$b(h) = b_0 + b_1 h^1 + b_2 h^2 + b_3 h^3 \quad (15)$$

$$c(h) = c_0 + c_1 h^1 + c_2 h^2 + c_3 h^3 \quad (16)$$

$$d(h) = d_0 + d_1 h^1 + d_2 h^2 + d_3 h^3 \quad (17)$$

where:  $a_i, b_i, c_i,$  and  $d_i$  constants.  
For  $P > 0$ , we have:

$$Q_k = Q_{k-1} - \frac{F(Q_{k-1})}{F'(Q_{k-1})} \quad (18)$$

where:

$$F(Q_{k-1}) = a Q_{k-1}^3 + b Q_{k-1}^2 + c Q_{k-1} + d - P_a \quad (19)$$

### 3. STUDIED SYSTEM CONTROL

Six non-zero voltage vectors and two zero-voltage vectors can be applied to the machine terminals. The stator flux can be estimated as [15]:

$$\phi_s(t) = \int_0^t (V_s - R_s i_s) dt \quad (20)$$

Since stator resistance  $R_s i_s$  relatively small,  $V_s \gg R_s i_s$ ,

$$\phi_s(t) = V_s T + \phi_s(0) \quad (21)$$

where  $\phi_s(0)$  is the initial value of stator flux,  $T$  the sampling period. The stator voltage vector  $V_s$  is selected using Table 2, where signs errors  $E_T$  and  $E_\phi$  are determined with a zero hysteresis band.

$$E_T = T_{e ref} - T_e \quad (22)$$

$$E_\phi = \phi_{s ref} - \phi_s \quad (23)$$

$$\phi_s = \sqrt{(\phi_{s\alpha})^2 + (\phi_{s\beta})^2} \quad (24)$$

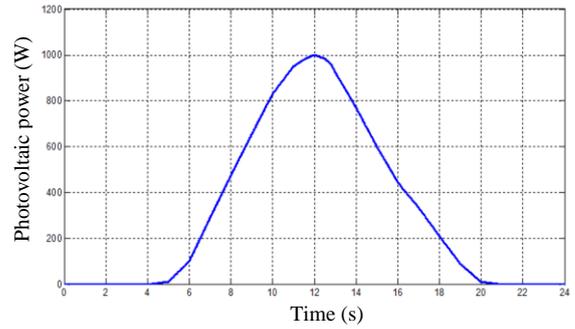
Table 2 provides the associated inverter switching states.

Table 2. Switching table for DTC

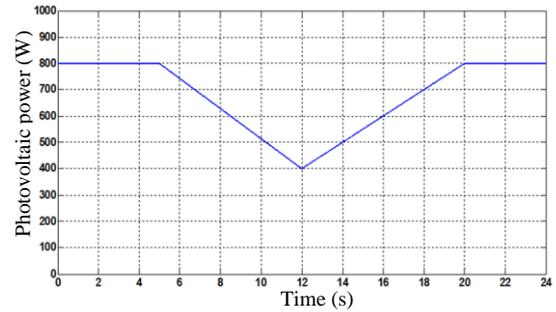
$E_T$	$E_\phi$	$N$					
		1	2	3	4	5	6
1	1	$V_2$	$V_3$	$V_4$	$V_5$	$V_6$	$V_1$
	0	$V_6$	$V_1$	$V_2$	$V_3$	$V_4$	$V_5$
0	1	$V_3$	$V_4$	$V_5$	$V_6$	$V_1$	$V_2$
	0	$V_5$	$V_6$	$V_1$	$V_2$	$V_3$	$V_4$

### 4. SIMULATION RESULTS

A simulation of the proposed system has been carried out by means of MATLAB/Simulink. Two different solar irradiance variations in Figure 8 have been used for one-day profile and sudden variation. The sampling period of the system is about  $T=100\mu s$ . The obtained results are represented in Figures 9-11.



(a)



(b)

Fig. 8. Solar irradiance, (a) one day profile, (b) sudden variation

The stator flux in Figure 9 keeps its reference ( $\Phi_{sref}=0.8$  Wb) during the two different irradiation profiles.

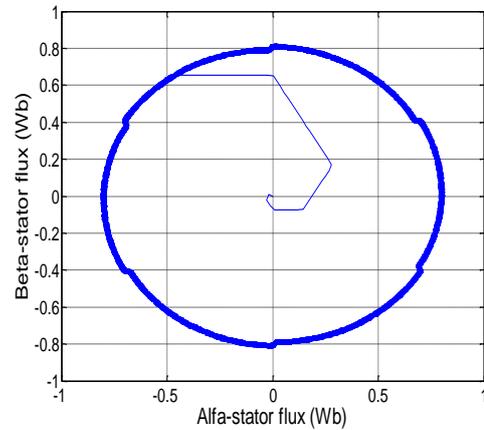


Fig. 9. Stator flux trajectory

It is noticed that the continuous power obtained at the output of the photovoltaic generator in Figure 10 (a) is in accordance with the solar irradiation profile. It reaches a maximum value at the maximum irradiation profile level. It can also be observed that the MPPT algorithm perfectly tracks and locates the point of maximum power for a given irradiance. This implies that the photovoltaic generator is operating at its optimal efficiency. The electromagnetic torque, which presents significant ripples in Figure 10 (b), follows the reference and takes the shape of the solar irradiance. This means that for high values of irradiance, the machine accelerates by increasing the water pumped volume.

The stator current in Figure 10 (c) follows the irradiance profile. It is noticed that the voltage DC bus remains constant and follows its reference within a small

range of variation without being affected by the change of solar irradiance in Figure 10 (d). The water flow rate in Figure 10 (e) changes with the intensity of the solar irradiation since the motor pump uses a continuously variable power, and therefore a variable speed. In

addition, with the introduction of MPPT algorithm, the mechanical speed Figure 11 (a) increases with the increase of the water flow in Figure 11 (b) during the observed period. The same remark can be made for the sudden variation profiles in Figures 11(b) and 11(c).

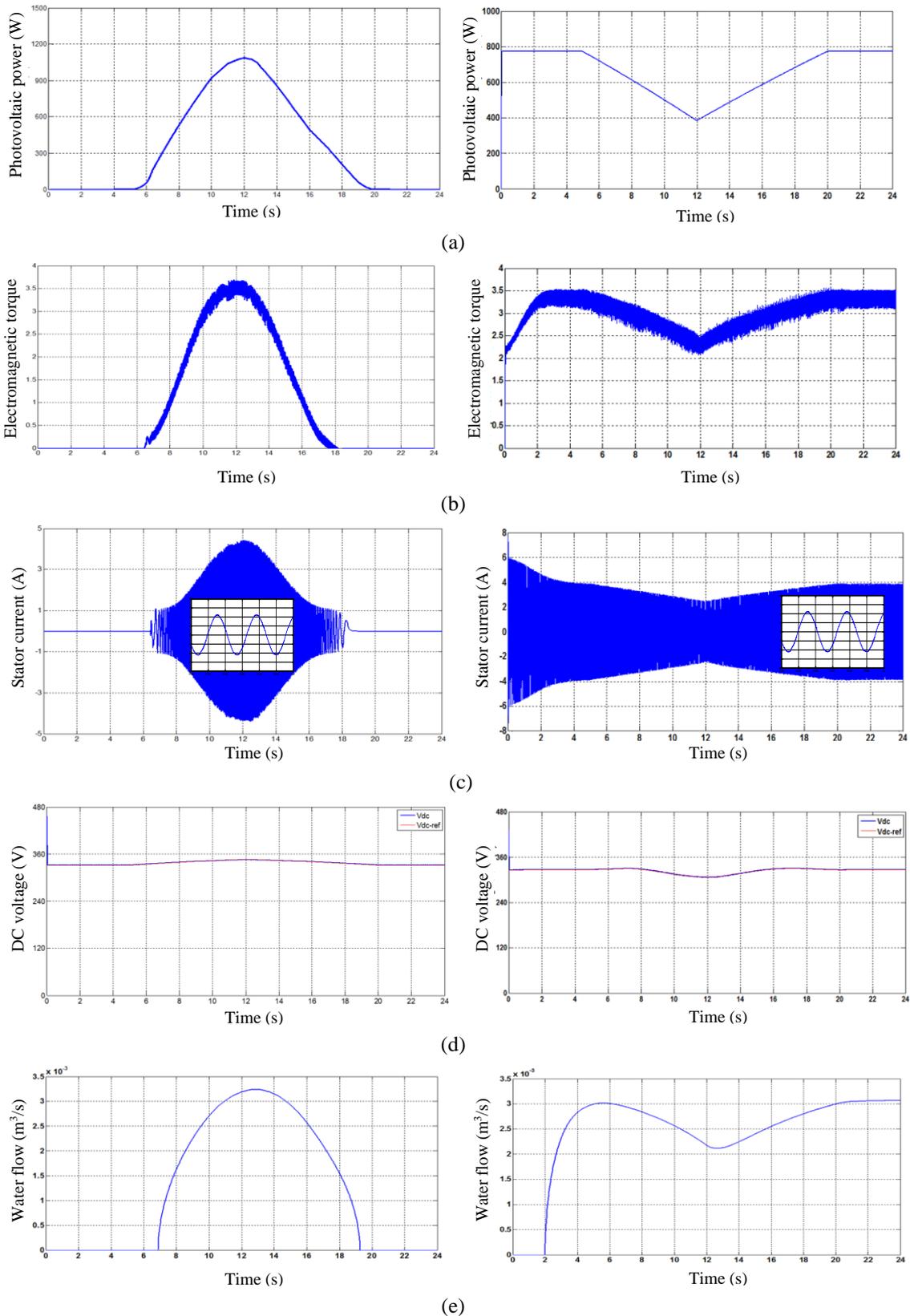


Fig. 10. System performances under two different solar irradiance (Left: under solar irradiation profile, Right under sudden variation profile) a) Photovoltaic power, b) Electromagnetic torque, c) Stator current, d) DC voltage variation with time, (e) Water flow

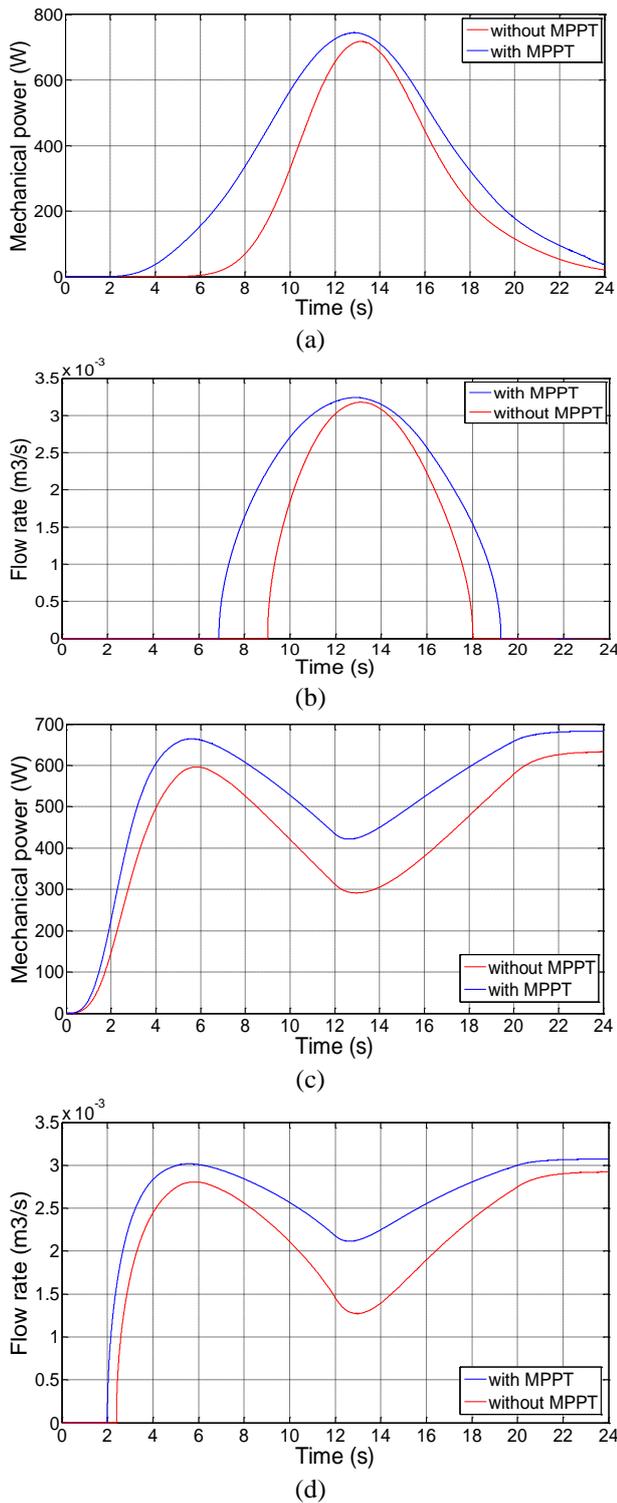


Fig.11. System performances with and without MPPT, (a) Mechanical power during a profile of one day, (b) Flow rate during a profile of one day, (c) Mechanical power during irradiance variation, (d) Flow rate during irradiance variation.

It is noticed that the mechanical power increases with the introduction of the MPPT, and thus the water flow increases. In addition, with the variation of irradiance, mechanical power and flow rate follow the variations with a marked improvement with the introduction of the MPPT.

## 6. CONCLUSION

Direct torque control of an induction generator supplied by a photovoltaic system has been proposed in this paper. The results have shown that the performances obtained are very attractive for the application of this control in photovoltaic system, especially in water pumping installations. Simulation results showed that the PV pumping system offers maximum pumping flow rate due to the MPPT (P&O method). The application of DTC in a photovoltaic pumping system maximizes power, which improves the total efficiency of the system. It was noticed that there is a lot of ripples in the torque; and it would be interesting to use a modulated hysteresis controller, which leads to an important reduction of the torque ripples. Besides, with the introduction of power optimization, the algorithm gives better tracking and allows us to improve the performance of the proposed system with a very high intake of water flow.

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## Nomenclature

ANN	Neural networks algorithm
DTC	Direct Torque Control
FLC	Fuzzy logic controller
IG	Induction generator
IncCond	Conductance incremental algorithm
MPP	Maximum power point tracking
P&O	Perturb & Observe
SMC	Sliding mode controller
$E_s$	Solar irradiation ( $W/m^2$ )
$I_{s\alpha}, I_{s\beta}$	$\alpha, \beta$ stator current (A),
$J_m$	Mechanical inertia ( $kg.m^2$ ),
$L_R, L_S$	Stator and rotor inductance (H),
$L_m$	Magnetizing inductance (H),
$N_s$	Number of cells in branched series,
P	Pole number
$R_s$	Stator resistance ( $\Omega$ )
$T_a$	Ambient temperature ( $^{\circ}C$ ),
$T_e$	Electromagnetic torque (N.m)
$T_L$	Load torque (N.m)
$V_s$	Voltage vector (V),
$\alpha, \beta$	Concordia transformation components
$\Phi_{s\alpha}, \Phi_{s\beta}$	$\alpha, \beta$ stator flux respectively,
$\omega_r$	Rotor angular speed (rad/s)

## Biographies



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