



ISSN Print: 2394-7500  
ISSN Online: 2394-5869  
Impact Factor: 5.2  
IJAR 2016; 2(5): 1138-1140  
www.allresearchjournal.com  
Received: 25-03-2016  
Accepted: 27-04-2016

**Shashi Yadav**  
Research Scholar Singhania  
University, Rajasthan, India

**Dr. Anand Kumar**  
Associate Professor, Jaat  
College, Rohtak, Haryana,  
India

## Study of var flows on specific transformer banks and transmission lines

**Shashi Yadav and Dr. Anand Kumar**

### Abstract

It is necessary to briefly review the current operation practice on western Oregon subsystem in Pacific Northwest before introducing the slow voltage controller framework. This part of system is a large load area without significant local 43 generation. Power is imported from other parts of Pacific Northwest and western Canada. There are tens of small capacitor/reactor banks and LTC transformers available for voltage control purpose in this area. During normal operation, voltage problems are alleviated by reactive compensation performed by system operators based on their experience, current and predicted network conditions. Switching out in-service devices is preferable than switching in alternate devices such that the maximum number of devices are available for future exercises. Tap changing has lower priority than reactive power compensation switching and tap changing frequency is restricted to several tap changes per day because tap changer failure results in transformer outage. Circular VAR flows are monitored by routinely checking the VAR flows on specific transformer banks and transmission paths and are mitigated by switching of capacitor banks or transformer tap changer settings.

**Keywords:** Operation practice, transformers, preferable, tap changer settings

### Introduction

A power system is a proper system to transmit power economically efficiently and reliable manner. As we know everyone desired the uninterrupted supply. But it is always not possible for a system remains in normal state. For more than 99% of the time, a typical system found in its normal state. In this state the frequency and the bus voltages are kept at prescribed value. As these two are responsible for active and reactive power balance. Thematch "Equality" between generation and demand is a fundamental prerequisite for system "Normalcy". Therefore objective is to maintain the system in normal state. This can be achieved by manage generation as well as demand. Generation can be manage by better AGC loop response which deals with frequency, voltage and economic dispatch control with considering generator rate constraints. Therefore specific objective are:

1. To develop simulation model for each component of AGC and AVR loops.
2. To develop AGC model considering generating rate constraints.
3. To develop model for coupled automatic generation and voltage control.
4. To develop AGC model based on demand side management.

Automatic generation control (AGC) is a significant control process that operates constantly to balance the generation and load in power systems at a minimum cost. The AGC system is responsible for frequency control and power interchange, as well as economic dispatch.

### Review of Literature

An extended power system can be divided into a number of load frequency control areas interconnected by means of tie lines in order i. to get commercial benefit from neighboring systems ii. To meet sudden requirement of electric power and improve reliability iv. Reduce in installed capacity. The major disadvantages are control system becomes complex and any disturbance in one system is reflected in the other area. The control objective now is to regulate the frequency of each area and to simultaneously regulate the tie line power as per inter-area power contracts.

**Correspondence**  
**Shashi Yadav**  
Research Scholar, Singhania  
University, Rajasthan, India

As in the case of frequency, PI controller will be installed so as to give zero steady state error in tie line power flow as compared to the contracted power.

**Power transported out of area A is given by**

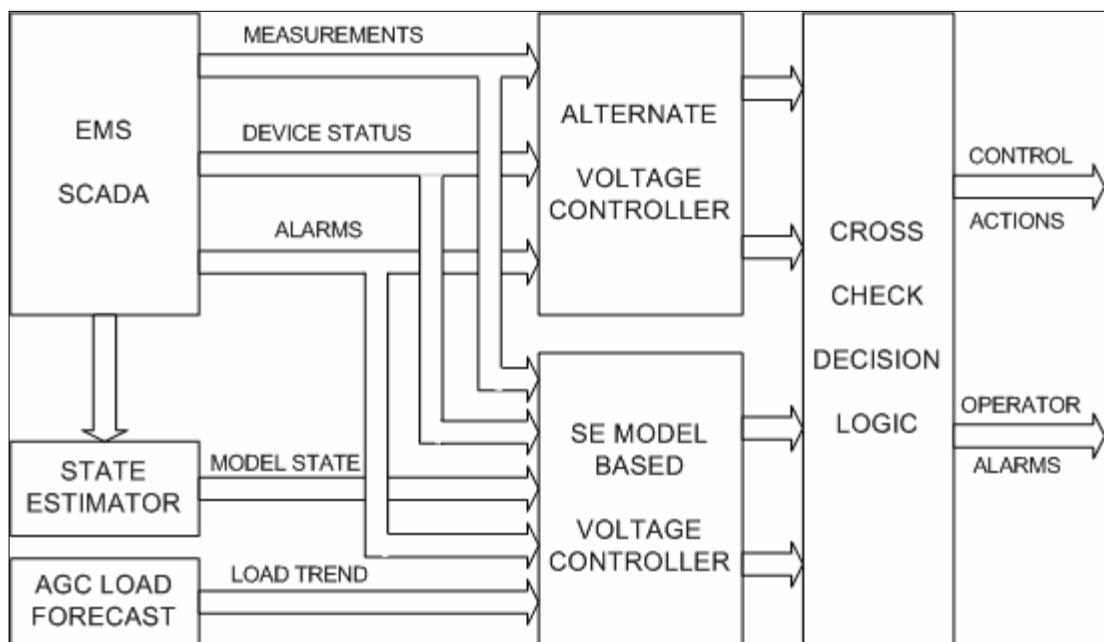
Where, are power angles of equivalent machines of the two areas?

2, the incremental tie line power can be expressed as  $\delta P$  and  $\delta f$  For incremental changes in Where T12 is synchronizing coefficient.  $f_2$ , the above equation can be written as  $\Delta P = T_{12} \Delta f$  and  $\Delta f = \frac{\Delta P}{T_{12}}$  Since incremental power angles are integrals of incremental frequencies ( Similarly the incremental tie line power out of area B is given by  $\Delta P_B = T_{21} \Delta f$  The block diagram of the system based on the above analysis is given below The steady state response of this two area system can be determined as follows. PL2).  $\Delta P_{L1}$  and  $\Delta P_{L2}$  and there are step load changes in both areas ( $\Delta P_{L1}$  and  $\Delta P_{L2}$  Consider the speed changer position is fixed ( $P_{m1}$  ss  $\Delta P_{L1}$  The turbine input change (&  $P_{m2}$  ss) due to the valve opening by the regulation characteristics in the two areas in steady state condition becomes,  $\Delta f_{ss}$ ;  $\Delta P_{m1}$  ss = - (1/R1)  $\Delta f_{ss}$   $\Delta P_{m2}$  ss = - (1/R2)  $\Delta f_{ss}$  Under this condition & Solving for steady state frequency and tie line power, we get  $\Delta f = \frac{\Delta P_{L1} + \Delta P_{L2}}{D_1 \beta + 1/R_1 + D_2 \beta + 1/R_2}$  We thus conclude from the preceding analysis that the two area system, just as in the case of a single area system in the uncontrolled mode, has a steady state error but to a lesser extent and the tie line power deviation and frequency deviation exhibit oscillations that are damped out latter. Hence, in interconnected operation to avoid these deviations and also to enable each area control

the changes in such a fashion that it absorbs its own load change in steady state, area control error signals should be sent to reference (speed changer) in the two areas respectively as follows Using la place transform The general block diagram for a two area system can now be developed as shown below.

**Material and Method**

Since the goal of on-line slow voltage control is to automate actions of an alert and experienced operator, it is necessary to briefly review the current operation practice on western Oregon subsystem in Pacific Northwest before introducing the slow voltage controller framework. This part of system is a large load area without significant local 43 generation. Power is imported from other parts of Pacific Northwest and western Canada. There are tens of small capacitor/reactor banks and LTC transformers available for voltage control purpose in this area. During normal operation, voltage problems are alleviated by reactive compensation performed by system operators based on their experience, current and predicted network conditions. Switching out in-service devices is preferable than switching in alternate devices such that the maximum number of devices are available for future exercises. Tap changing has lower priority than reactive power compensation switching and tap changing frequency is restricted to several tap changes per day because tap changer failure results in transformer outage. Circular VAR flows are monitored by routinely checking the VAR flows on specific transformer banks and transmission paths and are mitigated by switching of capacitor banks or transformer tap changer settings.



**Fig 1:** Common on-line slow voltage control framework.

The common slow voltage control framework integrated the state estimator modelbased controller and the alternate heuristic controller is shown in Figure 3.1. The controller is intended to be used for “slow” control and has a time frame of tens of seconds or a few minutes. Similar to a system operator, the automatic controller primarily acts upon voltage alarms and checks SCADA measurements for the acceptability of the system voltage profile. As a first step, the controllers can be required to process only the voltage

alarms. Other types of alarms relating to outages and contingencies can be handled directly by the system operators. The common slow voltage controller consists of two sub-controllers that operate independently. Under normal conditions when state estimator program has valid results, the model-based controller will act as main controller and its control decisions will be cross-checked against the outputs of the alternate controller. If the control decisions made by the two controllers are different but

similar, the decisions made by model-based controller will be adopted. If there are significant differences between the actions recommended by the two controllers, the system operator will be notified and responsible for making the final control decisions. When the state estimator model is unavailable or unreliable because of topology errors under certain conditions, the model-based controller will go into standby state, and the backup alternate controller will take over to make control decisions based on SCADA measurements only. The model-based controller proposed in calculates the incremental changes in bus voltages after switching control devices by carrying out an adaptive local power-flow starting from the system model output of the state estimation program. Then these incremental changes are assessed with respect to actual SCADA measurements to 45 compute the expected voltage profile after the switching actions. The controller as formulated minimizes the switching cost associated with these devices while keeping the voltage feasible in a robust sense by incorporating load forecast models, and while minimizing circular reactive flow through transformers. Specifically, the penalty for switching each device is a weighted average of the following terms 1) switching penalty based on the switching history and the type of the device, (2) voltage violation penalty based on expected voltages after switching from state estimation power-flow model and future power-flow models, and (3) circular VAR flow penalty computed from the state estimation power-flow model and future power-flow models. Switching action on the device with the minimum penalty will be recommended by the controller. The alternate controller, in contrast, calculates the incremental changes in bus voltages after switching control devices using local voltage estimator proposed in last chapter 46 based purely on the available local measurements from SCADA. The expected voltages after the switching actions also can be computed directly by adding the incremental changes to the actual SCADA voltage measurements.

### Conclusion

In order to reduce the number of switchings during periods of rapid load growths and declines (for instance, during morning and evening pick-ups), load forecasting estimates for individual loads in the area are computed using existing distribution factor formulas and the system total load forecast available from the EPRI AGC load forecasting program. These forecasted loads are then used to form a set of possible future power flow cases in the robust formulation of the controller and each future power-flow case is associated with a confidence level that gradually increases after verifying its reliability during operation. The model-based controller decides whether any control action is necessary by analyzing the SCADA measurement data and the expected voltage levels from future power-flow runs. If an action is required, a subset of candidate control devices which will have an impact on the problem is selected by using the concept of *electrical distance*.

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