Power System Stabilizers Design Using Grasshopper Optimization Algorithm

E. S. Ali[1] and S. M. Abd Elazim[2]
[1]Electric Power and Machine Department, Faculty of Engineering, Zagazig University, Zagazig, Egypt, Email: ehabsalimalisalama@yahoo.com
[2]Electric Power and Machine Department, Faculty of Engineering, Zagazig University, Zagazig, Egypt, Email: sahareldeep@yahoo.com

Abstract- A new meta-heuristic algorithm namely Grasshopper Optimization Algorithm (GOA) for Power System Stabilizer (PSS) design problem is investigated in this paper. The parameters of PSSs are optimized by GOA to minimize the time domain objective function. The performance of the designed GOA based PSSs (GOAPSS) has been has been compared with Differential Evolution (DE) based PSSs (DEPSS) and the Particle Swarm Optimization (PSO) based PSSs (PSOPSS) under various loading events. The results of the proposed GOAPSS are confirmed via eigenvalues, damping ratio, time domain analysis, and performance indices. Moreover, the robustness of the GOA in getting good damping characteristics is verified.

Key-Words:- PSS; Grasshopper Optimization Algorithm; Particle Swarm Optimization; Differential Evolution; Damping Oscillations; Power System.

1. Introduction

Power system stability is one of the recent significant issues in the analysis of power system [1]. One of the compulsory instances of this is an interconnected power system. The heavily loaded long tie-lines could account for a variety of stability issues [2]. This leads to the inclination of the most researchers towards designing of a suitable Power System Stabilizer (PSS).

Recently, a lot of research work is based on an area called "Heuristics from Nature" in which the analogies of nature or social systems are being utilized [3]. These techniques when used in research community can prove their capability of finding optimal solutions of multi-model, non-differentiable and complex objective functions. Various new algorithms have been used for designing a PSS as Differential Evolution (DE) [4], Particle Swarm Optimization (PSO) [5], Bacterial Swarm Optimization (BSO) [6,7], Harmony Search Algorithm (HAS) [8,9], Bacterial Foraging (BF) [10,11], Bat Algorithm (BA) [12,13], Water Cycle Algorithm (WCA) [14], Backtracking Search Algorithm (BSA) [15-16], Grey Wolf Algorithm (GWA) [17], Whale Optimization Approach (WOA) [18], Cuckoo Search Algorithm (CSA) [19,20], Flower Pollination Algorithm (FPA) [21], Genetic Algorithm (GA) [22], Kidney-Inspired Algorithm (KIA) [23], etc. All of these algorithms are based upon Artificial Intelligence (AI).

A new nature-inspired technique inspired from social activities of grasshoppers is introduced by Mirjalili. The technique is termed as Grasshopper Optimization Algorithm (GOA) [24]. Because of its simplicity, avoiding the high local optimum value as well as gradient-free mechanism, and inspiration by nature, it has been commonly implemented these days. Therefore, effectiveness of implementing the proposed algorithm to handle real-life issues is evaluated. The solutions must be upgraded in nature-inspired algorithms until the end criterion is met. Alongside this the optimization procedure partitioned in two stages named exploration and exploitation. Exploration relates to the algorithm's tendency to have randomized behavior to change the solutions. Large variations in solutions lead to more search space exploration and subsequently discovery of its promising areas. However, as an algorithm tends to exploit, solutions usually encounter smaller-scale variations and tend to search locally. An appropriate exploration and exploitation balance can lead to the search for the global optimum of a specified optimization problem. It is evident from [24] that the GOA method gives improved results as compared with several optimization techniques. Previous works clearly reflect the growing interest of the researchers in designing PSS when it comes to stability improvement. Further, the GOA technique has not been used.

2. Problem Formulation

2.1 Power System Model

Generally, a power system can be established by a group of nonlinear differential equations as:

$$\dot{X} = f(X, U) \tag{1}$$

Where X and U are the vector of the state variables and of input variables. In this study, $X = [\delta, \omega, E'_q, E_{fd}, V_f]^T$ and U is the output of PSSs. E'_q, E_{fd} and V_f are the internal, the field, and excitation voltages respectively. Also, δ and ω are the rotor angle and speed, respectively.

In the design of PSS, the state equation of a power system can be formalized as:

$$\dot{X} = AX + BU \tag{2}$$

2.2 PSS Structure

Due to the ease of online tuning, power system companies prefer the structure of conventional PSS (CPSS). The appropriate selection of the CPSS parameters results in satisfactory performance during the system disturbances.
The CPSS can be modeled as:

$$\Delta U_i = K_i \frac{ST_W}{(1+ST_W)} \left[\frac{(1+ST_{1i})}{(1+ST_{2i})} \frac{(1+ST_{3i})}{(1+ST_{4i})} \right] \Delta\omega_i \tag{3}$$

Fig. 1. shows the block diagram of CPSS and excitation system. The model of CPSS contains a limiter, a gain, a dynamic compensator and washout filter. To avoid the delay between the excitation and the electric torque, two lead-lag circuits are included [1,2]. In this paper, the time constants T_{1i}, and T_{3i}, and the gain K_i are optimized by GOA to reduce a time domain objective function.

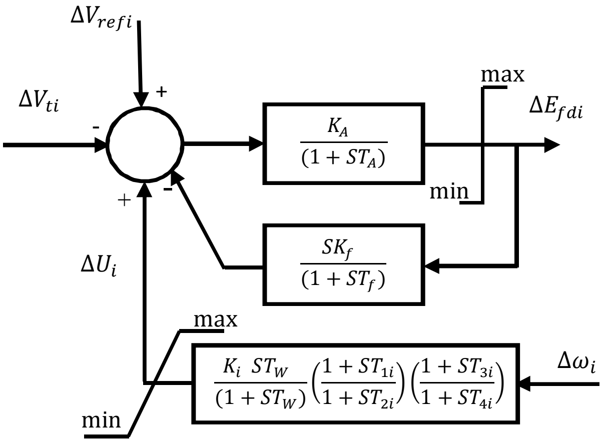

Fig. 1. Block diagram of i^{th} CPSS with excitation system.

2.3 Test System

A multimachine system that consists of three generators and nine buses, is considered here. The system data and loading events are given in [2, 25]. Fig. 2. shows the system under study.

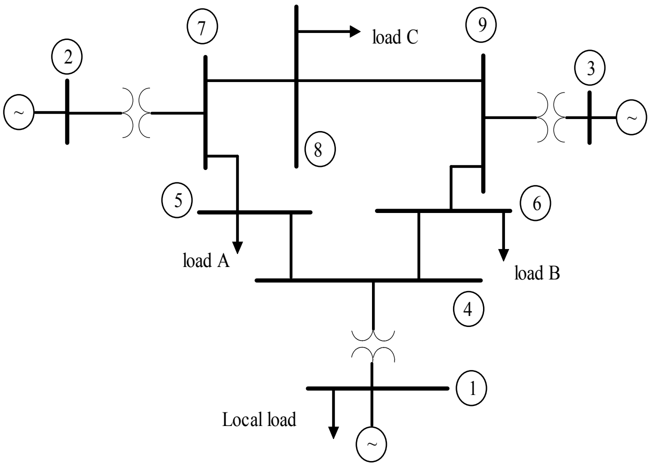

Fig. 2. Multimachine test system.

3. Grasshopper Optimization Algorithm

GOA is an intelligence algorithm presented by Mirjalili [24]. It is population based method which imitates grasshopper swarming behavior. It is an insect pest since it's destructive effect on corps. It's live has two stages, nymph and adulthood. For nymph stage, the insects have no wings so they move slowly but after growing up they become adults with wings that allow them to move very fast covering a large scale area. Grasshopper swarming might be considered as the largest one among all creatures as it is a nightmare for farmers.

In swarming process, there is a larval phase which characterized by slow movement with small grasshopper steps but for adults long-rang and abrupt movements. In food seeking process, grasshopper follows two strategies, exploration and exploitation. Each grasshopper represents a solution, the next position X_j is influenced by the social interaction between grasshopper and the other one S_j, gravity force G_j and wind advection A_j as shown in the following equation:

$$X_j = S_j + G_j + A_j \tag{4}$$

Social interaction can be calculated by the following equation

$$S_j = \sum_{k=1}^{N} s(d_{ik}).\ \hat{d}_{ik} \qquad k \neq i \tag{5}$$

$$d_{ik} = |X_k - X_i| \quad and \quad \hat{d}_{ik} = \frac{X_k - X_i}{d_{ik}} \tag{6}$$

Where N is no. of grasshoppers, d_{ik} is the distance from grasshopper k to grasshopper i and s is the strength of attraction and repulsion forces between grasshopper. Since repulsion force appears when distance between grasshoppers between zero and 2.079 units, while at a distance of 2.079 neither repulsion nor attraction force as it is a comfortable zone. Attraction force increases at a distance greater than 2.079 until reach 4 then it will be decreases and after 10 there will be no forces. Form the previous, the interval should be from 1 to 4 and s calculated as following:

$$s(r) = ae^{\frac{r}{l}} - e^{-r} \tag{7}$$

Where a is the intensity of attraction and l is the attractive length scale.

Gravity force can be calculated by the following equation:

$$G_j = g\hat{e}_g \tag{8}$$

Where g is a gravitational constant and $\hat{e}_g$ is the center of earth unit vector.

Wind advection force A_j can be determined by the following equation:

$$A_j = u\hat{e}_w \tag{9}$$

Where u is a drift constant and $\hat{e}_u$ is the wind direction unit vector

Equation (4) will be represented as following:

$$X_j = \sum_{k=1}^{N} \left(ae^{\frac{r}{l}} - e^{-r}\right) (|X_k - X_i|).\ \frac{X_k - X_i}{d_{ik}} - g\hat{e}_g + u\hat{e}_w \qquad k \neq i \tag{10}$$

To avoid comfortable zone and global optimum, the grasshopper position will be

$$X_j^d = c\left[\sum_{k=1}^{N} c\left(\frac{ub_d - lb_d}{2}\right) s\left(|X_k^d - X_i^d|\right).\ \frac{X_k - X_i}{d_{ik}}\right] + \hat{T}_d \tag{11}$$

Where ub_d and lb_d represent upper and lower bounds respectively in D^{th} dimension, $\hat{T}_d$ is the target value assuming wind direction tends towards target and c is decreasing constant to minimize all zones neglecting gravity.

$$c = cmax - l\frac{cmax - cmin}{L} \tag{12}$$

l is the current iteration, cmin=10^{-5} , cmax= 1 and L is the maximum number of iterations.

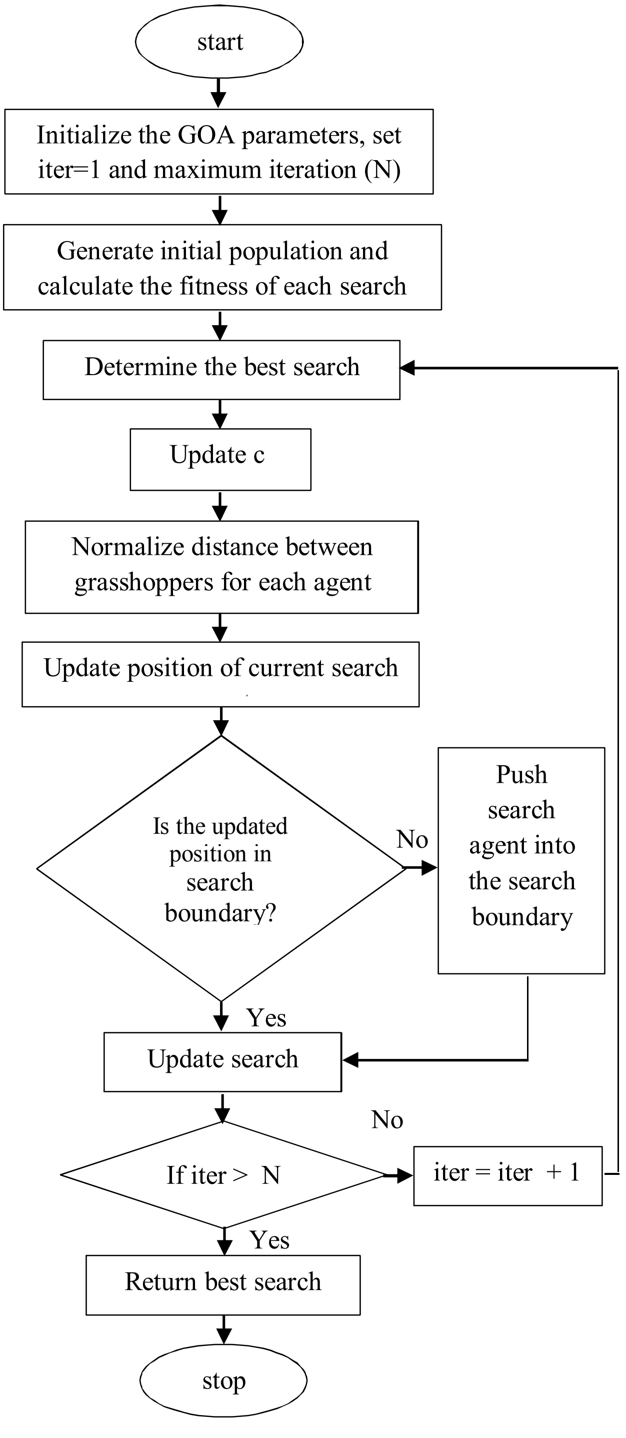

Fig.3. Flow chart of the GOA.

4. Objective function

An Integral Time Absolute Error (ITAE) of the speed deviation of generator is considered as the proposed objective function. It can be written as:

$$J = \int_{0}^{t_{sim}} t\left\{\left|\Delta\omega_{12}\right| + \left|\Delta\omega_{23}\right| + \left|\Delta\omega_{13}\right|\right\}dt \quad (13)$$

The lower and upper limits of the stabilizer gain are [1- 50] . Also, these limits are [0.06 -1.0] for T_{1i} and T_{3i}. Other time constants T_{2i} and T_{4i} are fixed at 0.05 second. GOA searches for the optimal parameters of PSSs to enhance the damping behavior and reduce the overshoots and settling time of the system response.

5. Simulation results and analysis

The eigenvalues and their damping ratios of mechanical modes are given in Table (1) for three various loading conditions and different algorithms. It is obvious that, the damping factors corresponding to GOAPSS are improved to be (σ =-1.12,- 1.19,-1.32) and the eigenvalues have been shifted to the left of S plane. Moreover, the damping ratios related to GOAPSS are greater than other controllers. Thus, GOAPSS gives better damping performance compared with DEPSS and PSOPSS. Also, the parameters of each controller using GOA, DE and PSO are shown in Table (2).

Table (1) Mechanical modes and ζ for various loading events and algorithms.

	PSO PSS	DE PSS	GOA PSS
Light load	-0.22±0.67j, 0.31 -2.43±4.01j, 0.51 -3.45±7.1j,0.44	-1.06±0.66j,0.85 -3.75±6.23j,0.51 -3.65±5.94j,0.52	-1.12±0.64j,0.87 -6.3±6.34j, 0.70 -3.33±5.12j,0.54
Normal load	-0.36±0.72j,0.37 -2.41±4.32j,0.48 -3.64±8.17j,0.41	-1.12±0.68j,0.85 -4.29±7.0j,0.52 -4.21±8.02j,0.46	-1.19±0.69j,0.87 -6.9±6.88j,0.71 -3.37±5.24j,0.54
Heavy load	-0.35±0.89j,0.36 -1.99±4.31j,0.42 -3.8±8.9j,0.39	-1.19±0.71j,0.86 -3.52±6.7j,0.47 -3.06±5.15j,0.51	-1.32±0.72j,0.88 -7.99±5.34j,0.83 -4.65±7.29j,0.54

5.1 Response for light load event:

The effectiveness of the decided controller is proved by setting a 3 phase fault near bus 7 of 6 cycle at 1 second. The system responses are shown in Figs. 4-6 for light load event. It is obvious that, the system responses with the decided GOAPSS are better than PSOPSS and DEPSS. Also, the settling times are 2.2, 3.2, and 3.5 second with GOAPSS, DEPSS, and PSOPSS respectively. The decided controller is competent to assign appropriate damping characteristic compared with DEPSS and PSOPSS.

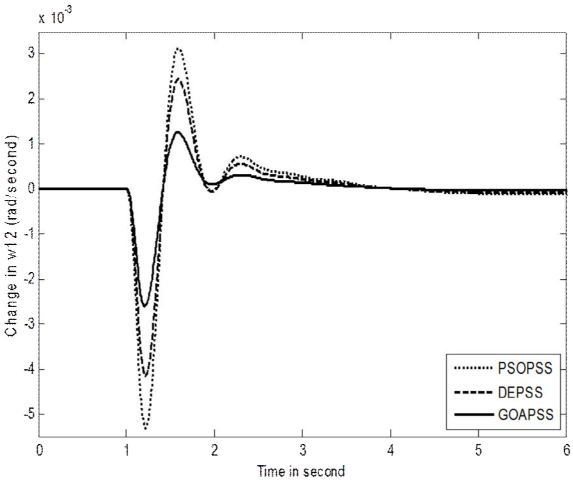

Fig. 4. Change of $\Delta\omega_{12}$ for light load event.

Table (2) Parameters of controllers for several algorithms.

	GOA	DE	PSO
PSS_1	K=42.128 T_1=0.5436 T_3=0.428	K=27.4566 T_1=0.5264 T_3=0.7578	K=17.4736 T_1=0.4224 T_3=0.7853
PSS_2	K=9.4211 T_1=0.4723 T_3=0.1643	K=7.9983 T_1=0.3108 T_3=0.1469	K=6.3649 T_1=0.5542 T_3=0.3231
PSS_3	K=5.2641 T_1=0.3234 T_3=0.1861	K=4.7541 T_1=0.5361 T_3=0.3931	K=7.8875 T_1=0.5668 T_3=0.4567

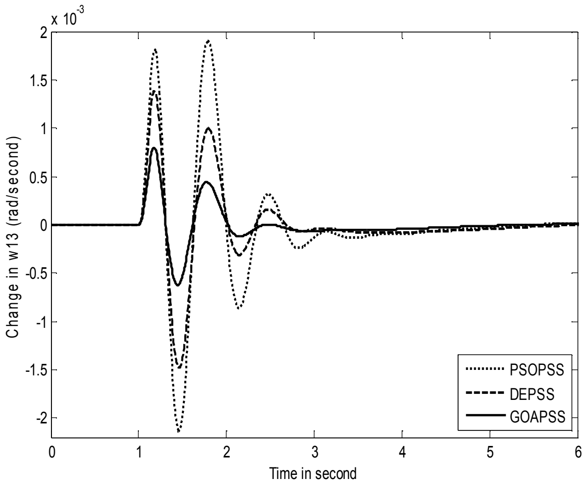

Fig.5. Change of $\Delta\omega_{13}$ for light load event.

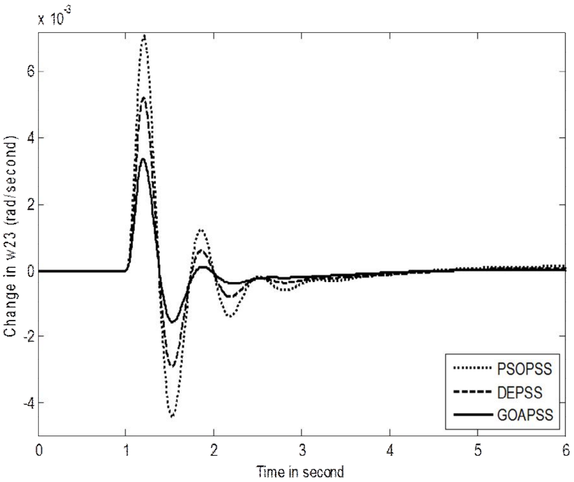

Fig. 6. Change of $\Delta\omega_{23}$ for light load event.

5.2 Response for normal load event:

The system responses under normal loading event are given in Figs. 7-9. From these responses, the damping behavior has been improved by the decided GOAPSS. The settling times of these responses are T_S =2.4, 3.1, and 3.2 second for GOAPSS, DEPSS, and PSOPSS respectively. Also, the decided GOAPSS outlasts DEPSS and PSOPSS in mitigating oscillations and shortening settling time. Hence, the decided GOAPSS expands the system stability limit.

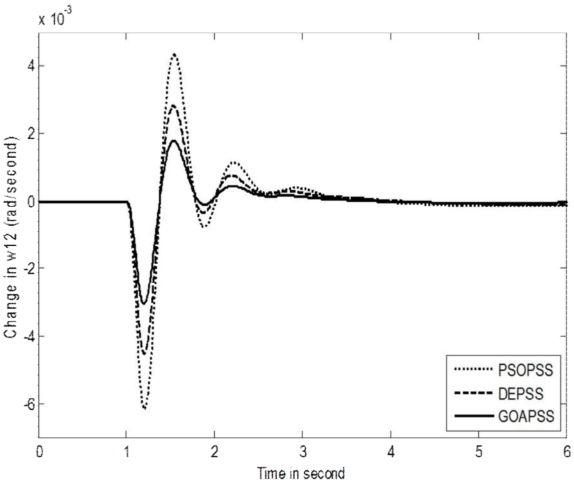

Fig. 7. Change of $\Delta\omega_{12}$ for normal load event.

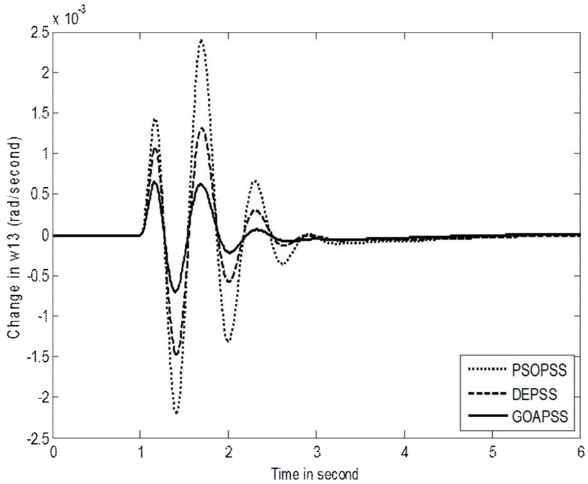

Fig. 8. Change of $\Delta\omega_{13}$ for normal load event.

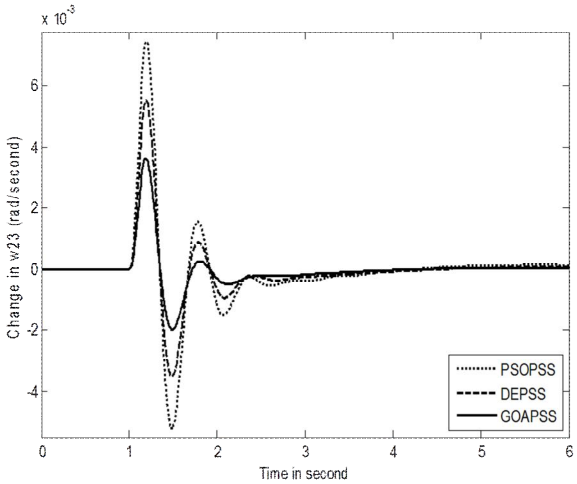

Fig. 9. Change of $\Delta\omega_{23}$ for normal load event.

5.3 Response for heavy load event:

Figs. 10-12, give the responses for heavy loading event. The superiority of the GOAPSS in attenuating system oscillations and minimizing the settling time are indicated in these figures. Also, the settling times of these oscillations are T_S =2.5, 3.1, and 3.3 second for GOATPSS, DEPSS, and PSOPSS respectively. Hence, GOAPSS controller largely develops the system stability and increases the damping behavior of power system. Moreover, the settling times of the decided GOAPSS are shorter than these in [5,12,19].

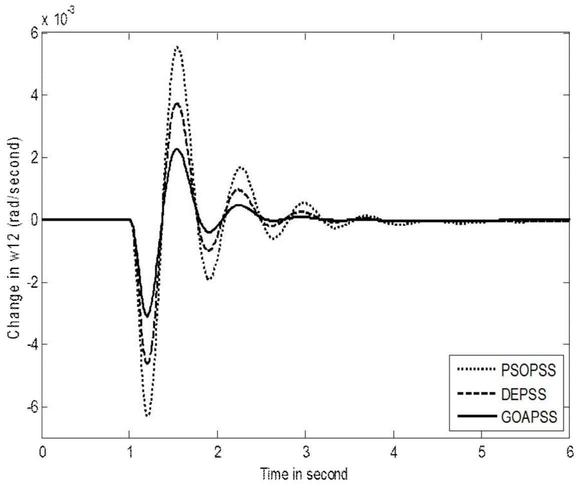

Fig. 10. Change of $\Delta\omega_{12}$ for heavy load event.

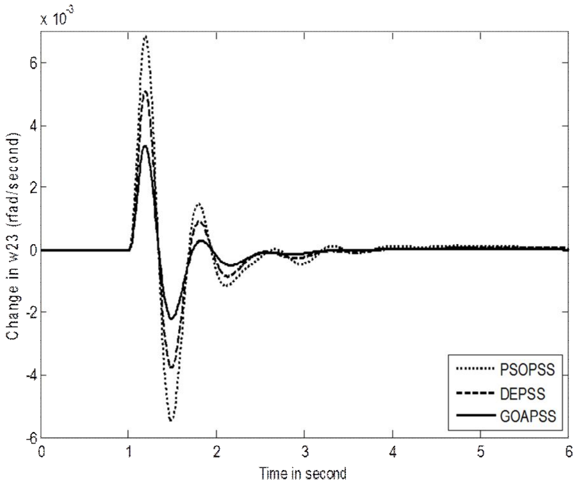

Fig. 11. Change of $\Delta\omega_{23}$ for heavy load event.

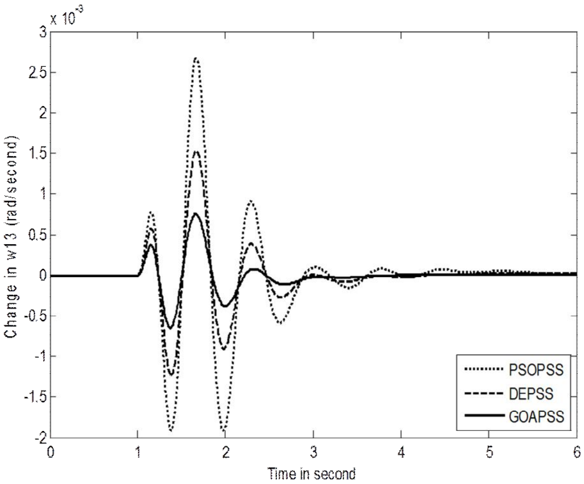

Fig. 12. Change of $\Delta\omega_{13}$ for heavy load event.

5.4 Response under small disturbance

The responses of $\Delta\omega_{13}, and\, \Delta\omega_{23}$ are given in Figs. 13-14 due to 0.2 step increase in mechanical torque of machine 1 like a small disturbance. It is clear from these figures, GOAPSS presents supreme damping and acquire the best behavior compared with DEPSS and PSOPSS.

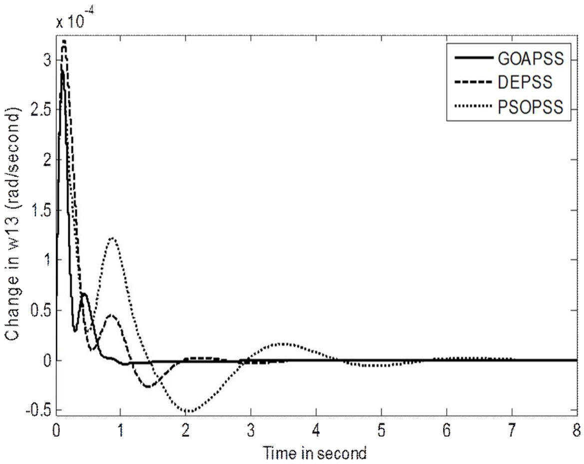

Fig. 13. Change of $\Delta\omega_{13}$ for small disturbance.

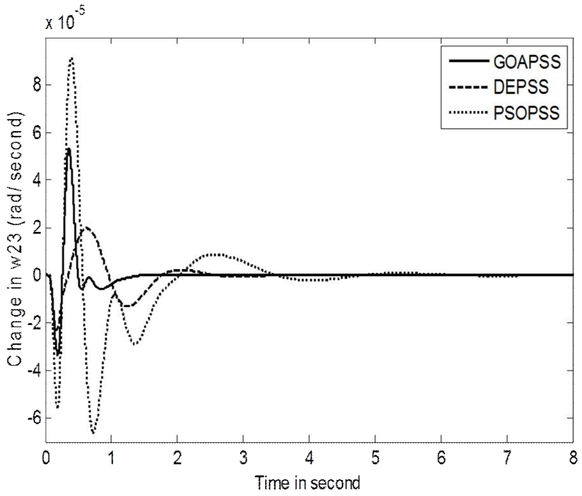

Fig. 14. Change of $\Delta\omega_{23}$ for small disturbance.

5.5 Performance indices:

To assign the superiority of the decided GOAPSS, some performance indices: the Integral of Absolute value of the Error (IAE), and ITAE are considered as:

$$IAE=\int_{0}^{20}\left(\left|\Delta w_{12}\right|+\left|\Delta w_{23}\right|+\left|\Delta w_{13}\right|\right)dt \qquad (14)$$

$$ITAE=\int_{0}^{20}t\left(\left|\Delta w_{12}\right|+\left|\Delta w_{23}\right|+\left|\Delta w_{13}\right|\right)dt \qquad (15)$$

The more weaker the value of indices have, the more supreme the system response is. Numeral results of performance indices for various events are given in Table (3). It is obvious, that the values of these indices with the GOAPSS are junior compared with those of DEPSS and PSOPSS. This assents that the speed deviations of all generators, settling time, and overshoot, are extremely diminished by setting the decided GOA based tuned PSSs.

Table (3) Performance indices for several algorithms.

	IAE * 10^{-4}			ITAE * 10^{-4}		
	PSO PSS	DE PSS	GOA PSS	PSO PSS	DE PSS	GOA PSS
Light event	0.2663	0.1484	0.0451	0.4642	0.4148	0.2746
Normal event	0.3973	0.2648	0.0657	0.7756	0.7551	0.6001
Heavy event	0.5686	0.4126	0.1001	0.9729	0.9406	0.8407

6. Conclusions

GOA is introduced in this paper for optimal designing of PSSs parameters as minimizing the proposed time domain objective function. An ITAE of the generator speed is considered as the objective function to enhance the system stability. Simulation results evidence the superiority of the decided GOAPSS in assigning good damping behavior to system oscillations for several loading events. Moreover, the decided GOAPSS affirms its efficacy than PSOPSS and DEPSS through some indices. Coordination of PSS and FACT controller with GOA is the future scope of this work.

Conflict of interest

The authors declare no conflict of interest.

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