

# WEC Development Project

Winter Semester 2024/2025

## Final Design Report



Project Name: **Optimus Shakti 5.0**  
Sub-Project: **Turbine Controller**

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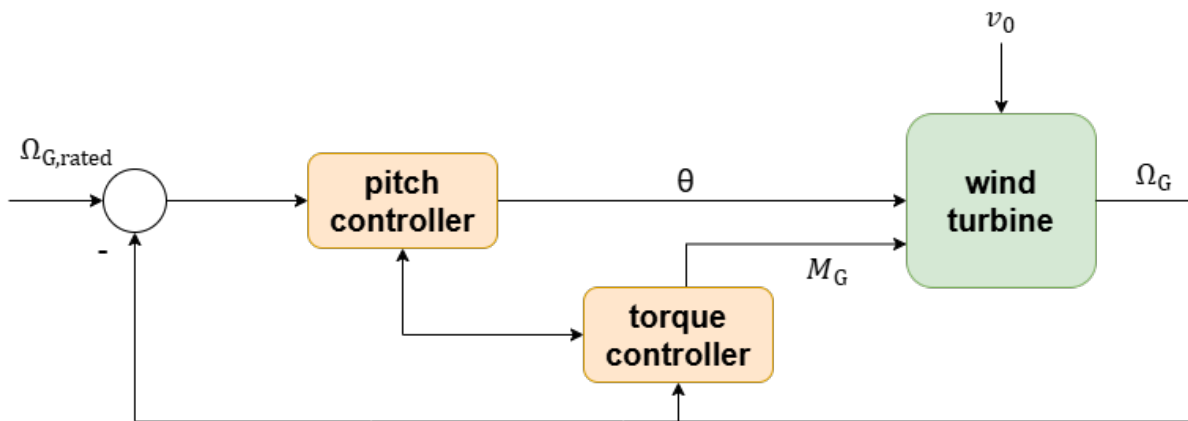
## **1 Introduction and motivation (Soni)**

## 2 Controller design objectives

### 2.1 Advanced Controller (Soni)

Wind turbine use closed-loop control (maximum energy capture over normal operation and less structural load) systems to continuously adjust their operations based on feedback. Figure 1, illustrates the advanced closed-loop control diagram of a wind turbine.

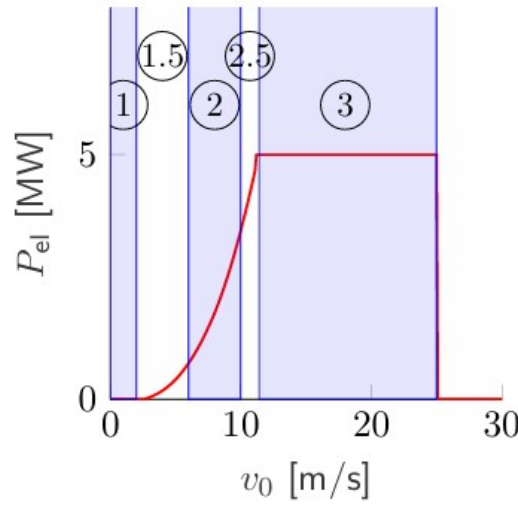
The torque controller optimizes power production below rated speed and maintain rated power above rated wind speed by adjusting generator torque ( $M_G$ ) based on generator speed ( $\Omega_G$ ). Advance torque control uses a PI controller with anti-windup to regulate the generator torque based on the difference between the actual and reference generator speeds. Above rated wind speed, Pitch controller maintains the rated generator speed ( $\Omega_{G,rated}$ ) by adjusting blade pitch angle ( $\theta$ ), which ensures the rated power is maintained. With increasing wind speed, the pitch angle increases to reduce power coefficient ( $c_p$ ). Once the wind speed reaches the rated value, the generator torque is maintained at its rated value. The control is categorized into different regions, as detailed in Section 2.2.



**Figure 2.1** Advance Wind Turbine Controller

### 2.2 Control Regions (Soni)

Wind turbine operations are segmented into three primary regions based on varying wind speed. These regions are defined by the turbine power output relative to wind speed. These regions are detailed below and illustrated in Figure 2.



**Figure 2.2** Wind turbine control regions

**Region 1:** When the wind speed is below the cut-in speed ( $v_{in}$ ), the turbine does not generate any power and remains stationary.

**Region 1.5:** This phase indicates the shift to Region 2, where wind speeds are sufficient to accelerate rotor. The generator torque is carefully controlled to accelerate the transition to Region 2. While energy production has started, the power output remains relatively low. The goal is to quickly reach Region 2, where the turbine can operate more efficiently.

**Region 2:** Wind speeds are above the cut-in speed ( $v_{in}$ ) but below the rated wind speed ( $v_{rated}$ ). The primary objective is to maximize energy yield. To achieve this, the turbine operator at the optimal power coefficient ( $c_{P,opt}$ ), which is determined by reaching the optimal tip speed ratio ( $\lambda_{opt}$ ) and pitch angle ( $\theta_{opt}$ ). The control system ensures that the turbine maintains these optimal conditions by regulating the rotational speed through the torque controller. In this region, the generator torque is adjusted based on rotor speed, as shown in Equation 2.1.

$$M_G = \frac{1}{2} \rho R^5 \frac{P_{opt}}{\lambda_{opt}^3 r_{GB}^3} \Omega_G^2 \quad (2.1)$$

$$M_G = k \Omega_G^2 \quad (2.2)$$

**Region 2.5:** This phase represents a transition between Region 2 and Region 3. In this region, the wind speed is increasing, and the turbine is approaching its rated wind speed. The control system continues to optimize the generator torque to ensure a smooth transition. Energy production is higher compared to Region 2, but the turbine has not yet reached its maximum power output. The pitch controller begins to act to keep the thrust on the rotor as low as possible while aiming to reach the rated speed as quickly as possible.

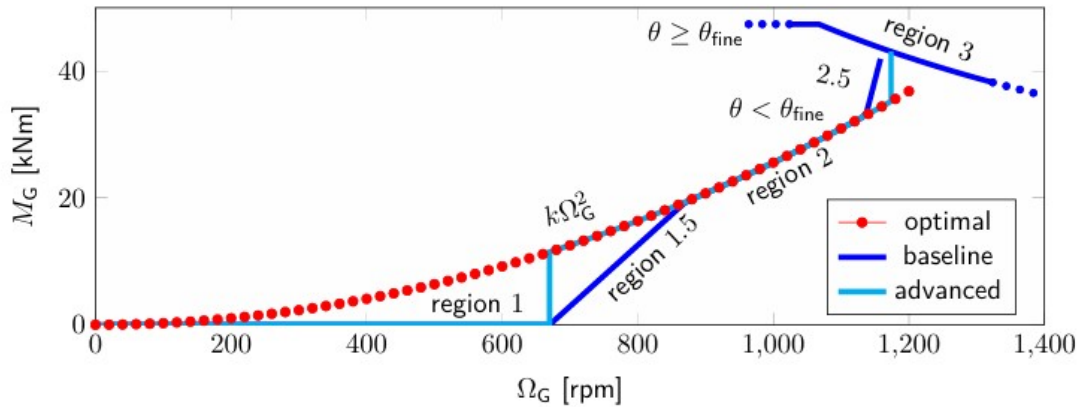
**Region 3:** In this region, wind speeds have reached the rated wind speed, and the primary goal is to generate maximum power. The control goal is maintain rated power and generator speed as well as reduce structure loads. The torque controller maintains the generator torque at its rated value. The pitch controller actively adjusts the blade pitch angle to regulate the power and keep it within the turbine rated capacity.

## 2.3 Advanced Generator Torque controller (Soni)

Generator torque is one of the two main control inputs for a wind turbine. The performance of an advanced generator torque controller offers significant improvements and greater flexibility compared to a baseline torque controller. The primary goals of the advanced torque controller are to reach the optimal power curve earlier and to maintain it for a longer duration compared to the baseline controller. Additionally, the dynamics in Regions 1.5 and 2.5 are tunable, allowing for more precise control.

Goals of the advanced torque controller:

- Achieve the optimal power curve earlier.
- Maintain the optimal power curve for a longer period.
- Enable tunable dynamics in Regions 1.5 and 2.5.



**Figure 2.3** Wind turbine control regions

Strategy for the Advanced Torque Controller:

**Region 1.5:** Lowest generator speed  $\Omega_{G,1.5}$  to avoid the 3P frequency interacting with the tower's eigenfrequency. Torque PI controller used for fine-tuning.

**Region 2.5:** Generator speed  $\Omega_{G,2.5} = \Omega_{G,rated}$ . Switch from  $\Omega_{G,1.5}$  to  $\Omega_{G,2.5}$  if the measured generator speed  $\Omega_G$  exceeds

$$\Omega_{G,R2switch} = \frac{1}{2}(\Omega_{G,1.5} + \Omega_{G,2.5}) \quad (2.3)$$

Torque Limits:

The generator torque limits are determined by the measured generator speed  $\Omega_G$  and incorporate Anti-Windup mechanisms.

- if  $\Omega_G < \Omega_{G,R2switch}$ :

$$M_{G,lb} = 0 \quad (2.4)$$

$$M_{G,ub} = k\Omega_G^2 \quad (2.5)$$

- if  $\Omega_G > \Omega_{G,R2switch}$ :

$$M_{G,lb} = k\Omega_G^2 \quad (2.6)$$

$$M_{G,ub} = \min \left( M_{G,rated} \frac{\Omega_{G,rated}}{\Omega_G}, M_{G,max} \right) \quad (2.7)$$

**Region 2:** The controller aims to maximize energy yield while ensuring the turbine operates efficiently.

**Region 3:** The torque controller maintains the generator torque at the rated value to protect the turbine from excessive mechanical stress due to high wind speeds.

## 2.4 Collective Pitch Controller (CPC) (Julius)

Collective pitch control (CPC) adjusts the pitch for all 3 blades similarly. The pitch control behavior has a high impact on the structural loads therefor on the life time of the wind turbine and thus on costs. CPC can be implemented with a standard PI-Controller. Main task of the CPC is to make the rotor area more permeable for the wind in order to reduce the power coefficient. This is done by pitching the rotor blades in a less advantageous aerodynamic position. With increasing wind speed the power output increases as well as the loads. In order to keep the loads within an acceptable limit the power output of the wind turbine must be limited.

The pitch controller is only active in region 3, when the wind speed is above the rated wind speed as described in figure 2.2. In region 3 the pitch controller maintains rated speed and the generator torque controller rated torque. In the OPTIMUS Shakti wind turbine a gain scheduled PI controller is used to control the rotor speed.

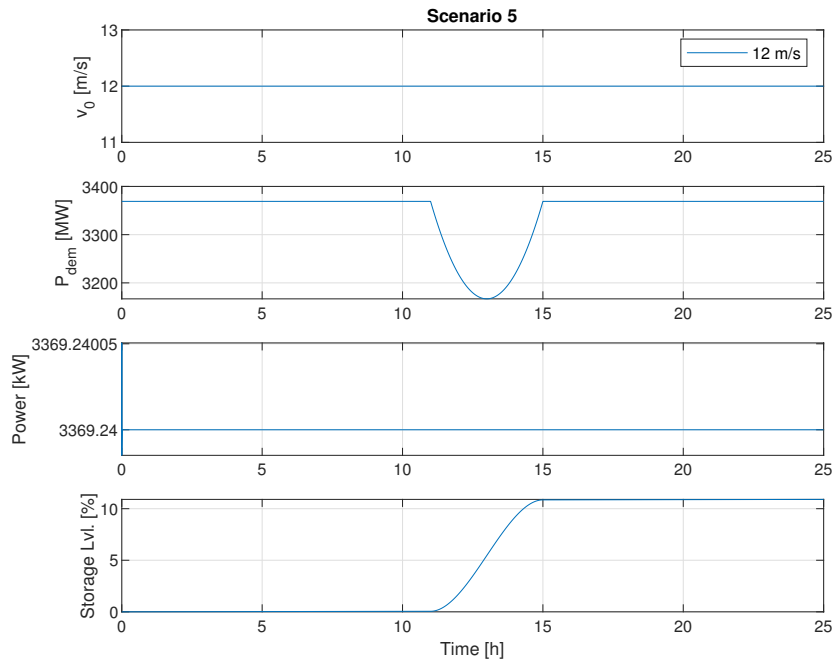
The concept of gain scheduling is widely used and a common feature in blade pitch controllers. With the use of gain scheduling the parameter of the controller are changed based on the operating point of the system.

## 2.5 Tower Damper (Felix)





2. **Rated power demand from grid:** The storage system is in working condition. There is rated power feed into the grid. The storage is not getting charged.
3. **50 % of rated power demand from grid:** The storage system is in working condition. The storage system is not at full capacity. There is a power demand from the grid of 50 % of rated power. The storage is getting charged with a reduced rate of charge.
4. **Turbine operated below rated power, grid demand is exceeding production:** The storage system is in working condition. The storage is charged to 50 % of its maximum capacity. The WT is operating below rated power and the grid demand is higher than the power production of the WT. The storage system is getting discharged.
5. **Curtailment scenario of 4h in 25h period:** The storage system is in working condition. The storage system is not at full capacity. The WT is operating at rated power. The power must be reduced for a certain amount of time because of a curtailment order from the grid operator. The storage system is getting charged.



**Figure 3.2** Curtailment scenario for 4h duration, a storage capacity of 5 MWh and a curtailment rate of 6%.

### 3.3 Tower Bending Stiffness (Julius)

For the implementation of the tower damper in the SLOW model the tower equivalent bending stiffness  $k_{Te}$  and the initial tower top deflection  $X_{T0}$  is needed. With OpenFAST the steady states calculations (section 4.1) with a wind speed range from 3 m/s to 9 m/s where done. The bending stiffness of the tower can be calculated with:

$$k_{Te} = \frac{F_a}{X_T - X_{T0}} \quad (3.1)$$

Where  $F_a$  is the aerodynamic thrust force onto the rotor plane and  $X_T$  the deflection of the tower top. The initial tower top deflection  $X_{T0}$  is determined from the calculated steady states via a polyfit of the curve to get the deflection of the tower at  $F_a = 0$  N. With 3.1 the bending stiffness in every steady state is determined and averaged over the number of points. This leads to an tower equivalent bending stiffness of  $k_{Te} = 2.185$  MN/m and a initial tower top deflection of  $X_{T0} = -0.021$  m.

### 3.4 Peak shaving idea (If: Who?)

Put it maybe also in since we did show a plot with it?

## 4 Controller tuning

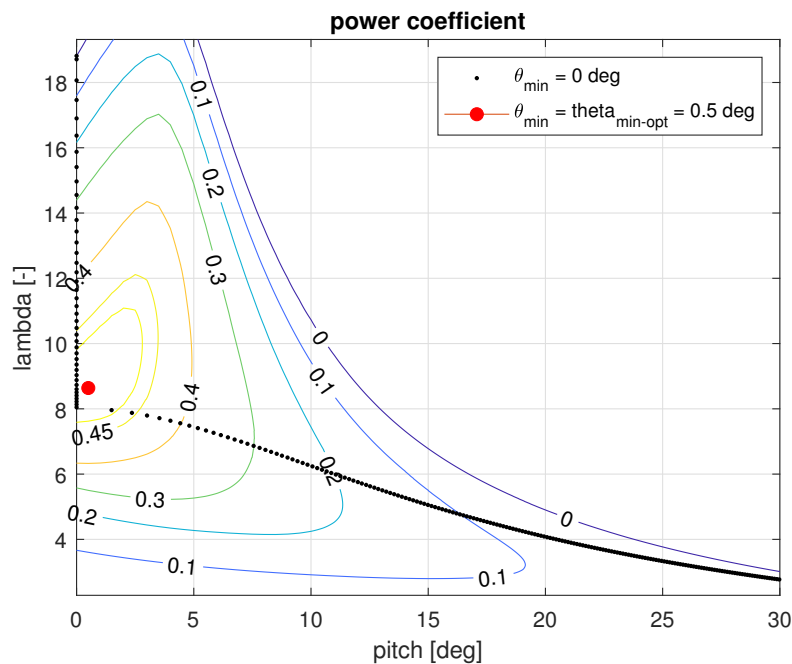
### 4.1 Steady States (Who?)

### 4.2 DEL calculation thetaK Felix

### 4.3 Minimum Pitch Angle Optimization (Julius)

The optimization of the minimum pitch angle is a simple adjustment which leads to a small increase in the AEP. The optimization was done with a brute force approach and the steady states calculations (Section 4.1). In control region 2 the WT should work at optimum  $C_p$  and  $\lambda$ . The use of minimum pitch angle can lead to an more efficient state of the turbine at the start of region 2 and therefor increase the AEP. For different pitch angles the steady states where calculated. As optimum, min. pitch angle the angle which leads to the highest  $C_p$  was chosen. As a result the min. pitch angle of  $0.5^\circ$  was determined and is shown in figure 4.1. During the calculation the pitch angle was optimized in a range of  $0^\circ$  to  $5^\circ$  with a step size of  $0.1^\circ$ .

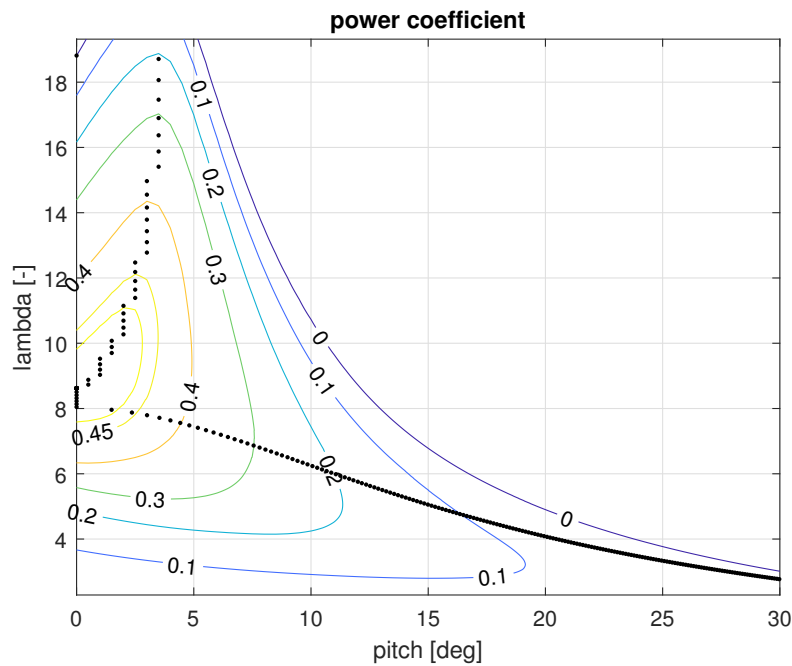
The determined min. pitch angle of  $0.5^\circ$  leads to an increase in AEP of  $0.29\%$  compared to min. pitch angle of  $0^\circ$ . (Calculated with Weibull parameters of TC III and  $k = 2$ .)



**Figure 4.1** brute force optimization for minimum pitch angle  $\theta$

#### 4.4 Minimum Pitch Angle Optimization for Control Region 1.5 (Julius)

Since the control region 1.5 has a large wind speed range of  $3.28 \text{ m/s}$  the optimization of the pitch angle could lead to an increase in AEP. As optimization process a brute force approach was used in order to find the optimum pitch angle for every operating wind speed in region 1.5. During the calculation the pitch angle was optimized in a range of  $0^\circ$  to  $5^\circ$  with a step size of  $0.1^\circ$ . The results of the optimization can be seen in figure 4.2. The result shows, that keeping a static pitch angle through region 1.5 is not leading to the optimal power production. A calculation of the AEP with a dynamic pitch adjustment for region 1.5 leads to an increase of  $0.19\%$  compared to a static minimum pitch angle of  $0.5^\circ$  as shown in section 4.3. (Calculated with Weibull parameters of TC III and  $k = 2$ .) Since the calculation is done without transition regions for the adjustment of the pitch the increase in AEP after implementation of the control behavior is to be expected less than the named  $0.19\%$ . The approach of changing the pitch angle dynamically in region 1.5 was not implemented in the OPTIMUS Shakti project but could be interesting for further optimization of the developed WT.



**Figure 4.2** brute force optimization for minimum pitch angle  $\theta$  in region 1.5

## 5 Challenges, Teamwork and Lessons Learned

### 5.1 Generator Speed and Control Region 2.5 (Who?)

### 5.2 Rated Wind Speed (Julius)

In order to get started with the project some specifications of the turbine had to be decided really quick. In this particular case the value of the rated wind speed lead to some confusion during the development phase of the Shakti WT. After the rotor blades where aerodynamically designed the steady states calculations revealed a problem with the rated wind speed. It was discovered that the design value of the rated wind speed was not fitting to the aerodynamic behavior of the rotor.

An investigation in cooperation with the project management lead to the result, that the decision regarding the rated wind speed was not based on the same source as rotor diameter, rated power and  $C_p$ . This lead to large mismatch in between the listed values.

The basis for the decision of the rotor diameter based on the fixed value of rated power was done by using a data base of multiple similar turbines with similar technical specifications. From the database a power per square meter value was derived from which the rotor diameter was calculated. The  $C_p$  value and the rated wind speed was calculated based on the scaling of a power curve from a Senvion WT.

The unchecked use of the calculated power per square meter value which already contained an unknown averaged  $C_p$  value in combination with the chosen  $C_p$  and rated wind speed from the scaled power curve lead to the mismatch. In absolute numbers the difference where a calculated rated wind speed value of 9.3 m/s compared to the design value of 10.61 m/s.

In order to fix the issue the 4 following options where proposed: The fixed design values at that time where: rated wind speed 10.61 m/s, rotor diameter 178 m, rated power 5 MW,  $C_p$  0.48.

1. Keep rated wind speed and **power**, but **reduce** Rotor radius.  $C_p = 0.48$  for  $R = 140$  m
2. Keep rated wind Speed and **rotor** radius, but **increase** rated power.  $C_p = 0.3$  for  $P = 5.5$  MW
3. Keep rated power and rotor radius and accept new rated wind speed at ca. 9.3 m/s.
4. Keep the design values and use the "peak shaving" method to start pitching already before region 3 in order to only reach rated power at a higher wind speed.

Since the project aim is to build a WT for low wind speed regions in collaboration with the project management and the project owner the decision was made to go with the option number 3 and accept the new rated wind speed.

### 5.3 Mismatch of SLOW and FAST Model (Julius)

During development and the release of the first OpenFAST (FAST) version of the WT controller big problem was encountered. In order to validate the new controller version for FAST a simulation was done and the results were compared to the expected behavior of the turbine and the SLOW model of the developed WT. The findings were inconclusive. The simulations carried out showed for the same conditions, such as constant wind, no pitch activity and a matching number of DOFs a difference in power production of 16 %. The FAST model showed for rated wind conditions a 16 % lower power output compared to the SLOW model.

After investigating several possibilities in SLOW and FAST the aerodynamics in FAST were identified as the cause of the mismatch. The rotor blades team provided a  $C_p$  lookup table with the software QBlade which is used by the SLOW model for deriving the correct aerodynamic power from the rotor within the Simulink model. Since FAST was used for the load simulations the blade design in QBlade had to be exported. FAST in this case is not using a  $C_p$  look up table and is instead calculating the aerodynamics directly from the blade design. The design is input via the airfoil data and the corresponding position along the blade. The load simulations in FAST were based on the AerodynV15 module. Because QBlade is only supporting the export up to version AerodynV13 the conversion from AerodynV13 to V15 was done separately by the rotor blades team. During this conversion an unidentified error occurred and led to the faulty aerodynamics which led to a difference in power production.

As a solution the change from the AerodynV15 module to the AerodynV14 module was approached. This was done because the conversion from the QBlade output in AerodynV13 is compatible with the AerodynV14. The change from one aerodyn version to another revealed that faulty airfoil data was exported by QBlade. The files contained random NaN values as certain key values. This problem was solved by correcting the wrong values after the export. The change from AerodynV15 to AerodynV14 were able to solve the issue and make the SLOW and FAST simulation match.

The faulty exported data was not the cause for the mismatch of AerodynV15. This problem is still unclear.

As in section 5.2 described the rated wind speed was reduced during the design process from 10.61 m/s to 9.3 m/s. Because of the higher wind speed used for the FAST simulations up to that point the low aerodynamic power output was only identified quite late during the design process. With the incorrect rated wind speed the WT was apparently providing the rated power. Which in truth the turbine was operating way above wind conditions to reach rated power. Nevertheless the problem was identified in time and solved as a team effort of the loads, blades and control team. The described issue shows, that the validation of a model is of high importance and mistakes in totally different areas of responsibilities can lead to unexpected behavior later in the development phase.

## **6 Summary (Who?)**

### **6.1 Conclusion (Who?)**



## 7 Appendix