Power System Stability

Power System Dynamic Models
Small-signal Stability
Transient Stability

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Stability Concepts

- Small-signal Stability
  - Ability to damp out small perturbations
  - Oscillations?
- Transient stability
  - Recovery from large disturbances
  - Islanding? Voltage collapse?

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Stability concepts

- Small signal stability
  - Load fluctuations
  - Generation changes
  - Oscillatory modes
    - well damped?

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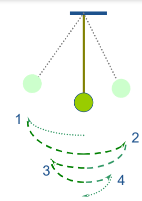
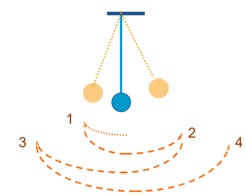
Small-signal stability



Positive damping
Oscillations damp out



Negative damping
Growing oscillations

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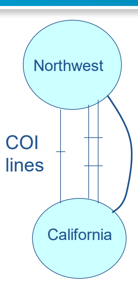
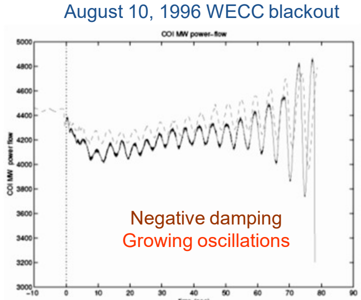
Small-signal instability in WECC



COI lines

Unstable 0.25 Hz Inter-area mode

August 10, 1996 WECC blackout



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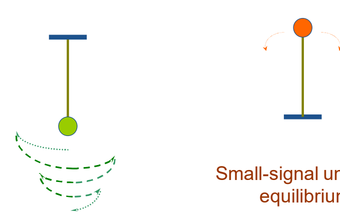
Small-signal stability



Small-signal stable equilibrium

Small-signal unstable equilibrium

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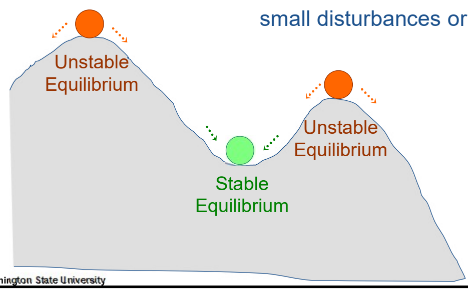
Small-signal stability

Can withstand small disturbances or not?



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Stability concepts

- Transient stability
  - Faults/line openings
  - Generator outages
  - Major disturbances
  - Loss of synchronization?
  - Voltage declines

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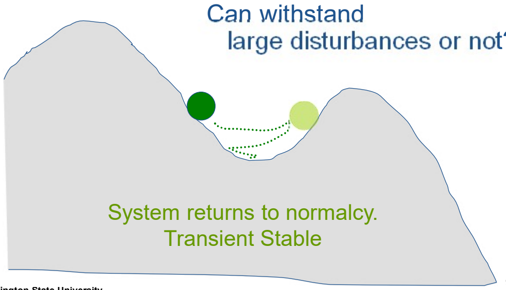
Transient stability

Can withstand large disturbances or not?



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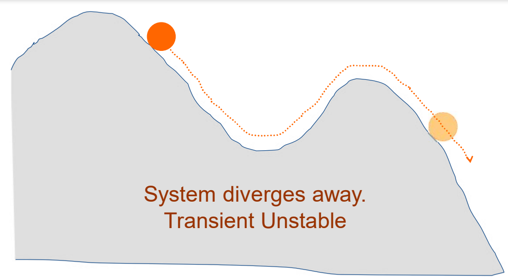
Transient instability



Loss of synchronism. Islanding.

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Stability Analysis

- Modeling
  - Swing equations model
- Analysis
  - Eigenvalues (Small signal stability)
  - Numerical Integration (Transient Stability)
  - Equal Area Criterion (Transient stability)
- Controls
  - Governor controls/AGC

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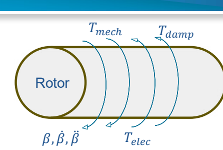
Rotor electromechanics



β = actual angular displacement of the rotor

θ = relative angular displacement with 60 Hz frame

$$\beta = \omega_s t + \theta,\ \dot{\theta} = \dot{\beta} - \omega_s = \omega - \omega_s$$

$$J\ddot{\beta} = T_m - T_e - T_d = J\ddot{\theta}$$

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Swing equations

$$J\ddot{\theta} = T_m - T_e - T_d$$
$$J\omega_s\ddot{\theta} = T_m\omega_s - T_e\omega_s - T_d\omega_s$$
$$\frac{J\omega_s\ddot{\theta}}{\text{S rating}} = \frac{T_m\omega_s}{\text{S rating}} - \frac{T_e\omega_s}{\text{S rating}} - \frac{T_d\omega_s}{\text{S rating}}$$
$$= P_m(p.u.) - P_e(p.u.) - P_d(p.u.)$$
$$H = \frac{Kinetic\ Energy}{MVA\ rating} = \frac{1/2J\omega_s^2}{\text{S rating}} = \text{Inertia time-constant}$$
$$\Longrightarrow \frac{J\omega_s}{\text{S rating}} = \frac{2H}{\omega_s}$$

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Swing equations

$$\Longrightarrow \frac{2H}{\omega_s}\ddot{\theta} = P_m(p.u.) - P_e(p.u.) - P_d(p.u.)$$

$\dot{\theta} = \omega_r - \omega_s$, ω_r = Speed of the rotor

$$\frac{2H}{\omega_s}\dot{\omega}_r = P_m - P_e - P_d$$

Define $\omega(p.u.) = \omega_r/\omega_s$. Then,

$$\boldsymbol{\dot{\theta} = (\omega - 1)\omega_s}$$
$$\boldsymbol{2H\dot{\omega} = P_m - P_e - P_d}$$

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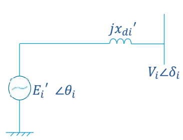
Classical machine model

Assume $P_d = K_D(\omega - 1)$

$$\dot{\theta} = (\omega - 1)\omega_s$$
$$2H\dot{\omega} = P_m - P_e - K_D(\omega - 1)$$



x_{di}' = Transient reactance of the stator coil

E_i' = Induced Voltage (Assume constant)

θ_i = Relative rotor angle

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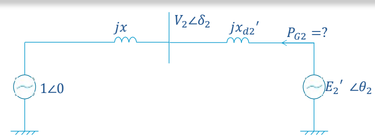
Example



$$\overrightarrow{I_{G2}} = \frac{E_2'\ \angle\theta_2 - 1\angle0}{jx_{d2}' + jx}$$
$$\Longrightarrow P_{G2} + jQ_{G2} = E_2'\ \angle\theta_2\overrightarrow{I_{G2}}^*$$
$$or\ P_{G2} = \frac{E_2'\ 1}{x_{d2}' + x}\sin(\theta_2 - 0) = \frac{E_2'}{x_{d2}' + x}\sin(\theta_2)$$

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Swing equations model

$$\dot{\theta}_2 = (\omega_2 - 1)\omega_s$$
$$2H_2\dot{\omega}_2 = P_{T2} - P_{G2} - K_{D2}(\omega_2 - 1)$$
$$where\ \ P_{G2} = \frac{E_2'}{x_{d2}' + x}\sin\theta_2$$

$$Suppose\ x = 0.5, x_{d2}' = 0.25, P_{T2} = 1,$$
$$K_{D2} = 1, \omega_s = 2\pi\ 60 = 377,$$
$$H_2 = 5, E_2'\ = 1.5$$

Then, $P_{G2} = \frac{1.5}{0.75}\sin\theta_2 = 2\sin\theta_2$

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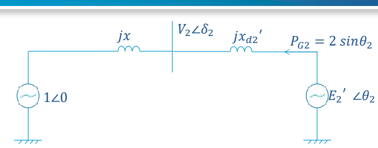
Swing equations for the system



$$x = 0.5, x_{d2}' = 0.25, P_{T2} = 1, K_{D2} = 1,$$
$$\omega_s = 2\pi\ 60, H_2 = 5, E_2'\ = 1.5$$

$$\dot{\theta}_2 = (\omega_2 - 1)377$$
$$10\dot{\omega}_2 = 1 - 2\sin\theta_2 - (\omega_2 - 1)$$

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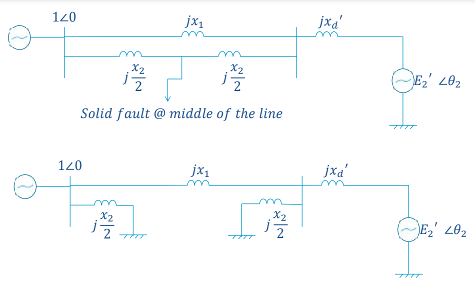
Faulted system



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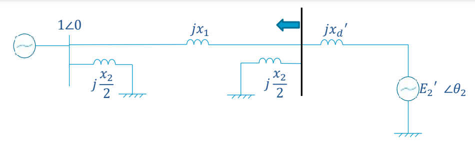
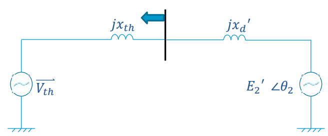
Thevenin equivalents





$$\overrightarrow{V_{th}} = (1\angle 0)\frac{j\frac{x_2}{2}}{jx_1 + j\frac{x_2}{2}}$$

$$Z_{th} = (jx_1) \parallel \left(j\frac{x_2}{2}\right) = jx_{th}$$

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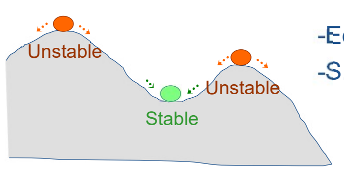
Small-Signal Stability

Model: $\frac{dx}{dt} = f(x) \qquad x \in \mathbb{R}^n$

Equilibrium point : $f(x_e) = 0$

Linearized system: $\dot{\Delta x} = \mathrm{J}\,\Delta x$ where $J = \left.\frac{\partial f}{\partial x}\right|_{x_e}$



-Equilibrium

-S.S.Stability?

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Small-signal stability analysis

General: $\dot{x} = f(x)$

$$x_e \ is\ an\ equilibrium$$

$$\Delta x = x - x_e \Longrightarrow x = \Delta x + x_e$$

$$\dot{\Delta x} = \dot{x} = f(x_e + \Delta x)$$

$$= \cancel{f(x_e)} + \left.\frac{\partial f}{\partial x}\right|_{x_e}\Delta x + \cancel{\left.\frac{\partial^2 f}{\partial x^2}\right|_{x_e}\Delta x^2 + O(3) + \cdots}$$

$$\dot{\Delta x} = J\Delta x, \qquad where\ J = \left.\frac{\partial f}{\partial x}\right|_{x_e}$$

$$is\ the\ Jacobian\ matrix\ of\ \dot{x} = f(x)$$

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Eigenvalues

Eigenvalues of J are the solutions of

$$\det(\lambda I - J) = 0$$

All eigenvalues have negative real parts $\Longrightarrow$ x_e is a small-signal stable eq. point

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Example

$$\dot{x} = -\sin(x)$$

Equilibrium:

$set\ \ \sin(x) = 0 \Longrightarrow x = 0, \pm\pi, \pm 2\pi \ldots = \pm n\pi$

Multiple Equilibrium points.

Small-Signal Model around an Equilibrium.

Linearization.

Compute eigenvalues.

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Small-signal linearized model

$$\dot{x} = -\sin(x)$$

$x = 0$ equilibrium, J = -cos(0) = -1

$$\dot{\Delta x} = -\left(\Delta x - \frac{\Delta x^3}{3!} + \frac{\Delta x^5}{5!} - \cdots\right)$$

$$\dot{\Delta x} = -\Delta x \Longrightarrow \text{Eigenvalue of } -1 \Longrightarrow stable$$

Equilibrium $x = 0$ is small-signal stable

Example (continued)

$$\dot{x} = -\sin(x)$$

$$x = 0 \Longrightarrow J = \left.\frac{\partial f}{\partial x}\right|_{x=0} = -\cos(x)\Big|_{x=0} = -1$$

-1 has negative real part $\Longrightarrow x = 0$ is s.s.stable.

$$x = \pi \Longrightarrow J = \left.\frac{\partial f}{\partial x}\right|_{x=\pi} = -\cos(x)\Big|_{x=\pi} = +1$$

+1 has positive real part $\Longrightarrow x = \pi$ is s.s.unstable.

Small perturbations can drive the system away from equilibrium $x = \pi$.

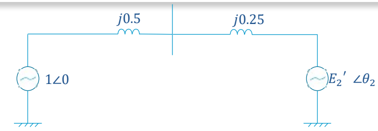
Example (continued)

$$x = 2\pi \Longrightarrow J = \left.\frac{\partial f}{\partial x}\right|_{x=2\pi} = -\cos(x)\Big|_{x=2\pi} = -1$$

$\Longrightarrow x = 2\pi$ is s.s.stable.

$$Equilibria\ x = n\pi \begin{cases} Stable\ if\ n\ is\ even \\ Unstable\ if\ n\ is\ odd. \end{cases}$$

Example 2



$$x = 0.5, x_{d2}{}' = 0.25, P_m = 1p.u.,$$
$$P_e = 2\sin\theta_2$$
$$K_{D2} = 1p.u., \omega_s = 2\pi\ 60 = 377,$$
$$H_2 = 5, E_2{}' = 1.5$$

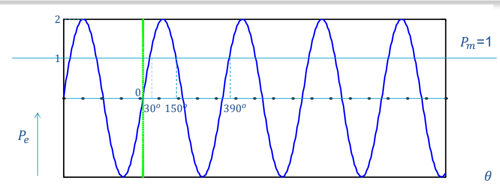
Equilibrium points

$$\dot{\theta_2} = (\omega_2 - 1)377$$
$$\dot{\omega_2} = \frac{1}{10}[1 - 2\sin\theta_2 - (\omega_2 - 1)]$$

Equilibrium points:

$$\dot{\theta_2} = 0 \Longrightarrow \omega_2 = 1$$
$$\dot{\omega_2} = 0 \Longrightarrow 1 - 2\sin\theta_2 - (\omega_2 - 1) = 0$$
$$2\sin\theta_2 = 1 \Longrightarrow \sin\theta_2 = \frac{1}{2}$$
$$\Longrightarrow \theta_2 = 30^o, 150^o, 390^o,$$

Power – Angle curve



Equilibrium point are

$$(\theta, \omega)^T = \ (30^o, 1)^T or\ (150^o, 1)^T or\ (390^o, 1)^T$$
$$or\ (510^o, 1)^T \ldots$$

Jacobian

$$\frac{\partial f}{\partial x} = \begin{bmatrix} \frac{\partial f_1}{\partial \theta} & \frac{\partial f_1}{\partial \omega} \\ \frac{\partial f_2}{\partial \theta} & \frac{\partial f_2}{\partial \omega} \end{bmatrix} = \begin{bmatrix} 0 & \omega_s \\ -\frac{2}{10}cos\theta & -\frac{1}{10} \end{bmatrix}$$

$$(30^o, 1)^T \Longrightarrow \left.\frac{\partial f}{\partial x}\right|_{(30^o,1)^T} = \begin{bmatrix} 0 & 377 \\ -\frac{2}{10}0.866 & -0.1 \end{bmatrix}$$

$$\text{J} = \begin{bmatrix} 0 & 377 \\ -0.17 & -0.1 \end{bmatrix}$$

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Eigenvalues

$$det\begin{bmatrix} \lambda & -377 \\ 0.17 & \lambda + 0.1 \end{bmatrix} = 0$$

$$\Longrightarrow \lambda^2 + 0.1\lambda + 65.3 = 0$$

$$\lambda = \frac{-0.1 \pm \sqrt{0.1^2 - 4(65.3)}}{2}$$

$$= \underline{-0.05} \pm j8.08 \Longrightarrow Freq = \frac{8}{2\pi} \approx 1.286\ Hz$$

$\Downarrow$

negative $\Longrightarrow$ Equilibrium $(30^o, 1)^T$is small-signal stable

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Eigenvalues

Standard form: -$\xi\omega_n \pm j\omega_n\sqrt{1-\xi^2}$

$$\Longrightarrow \xi = \frac{|Real\ part|}{\sqrt{Real^2 + Imag^2}} = \frac{0.05}{\sqrt{0.05^2 + 8.08^2}}$$

$$= 0.006 = 0.6\% \Longrightarrow low\ damping$$

Equilibrium point $(150^o, 1)^T \Longrightarrow$

$$J = \left.\begin{bmatrix} 0 & \omega_s \\ -\frac{2}{10}cos\theta & -\frac{1}{10} \end{bmatrix}\right|_{(150^o,1)} = \begin{bmatrix} 0 & 377 \\ 0.17 & -0.1 \end{bmatrix}$$

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Unstable equilibrium

$$\Longrightarrow \lambda^2 + 0.1\lambda - 65.3 = 0$$

$$\lambda = \underline{8.03}, -8.13$$

$\Downarrow$

positive real part

$\Longrightarrow$ Equilibrium $(150^o, 1)^T$s.s. unstable

small perturbations $\Longrightarrow$ will drive system away.

cannot operate at $(150^o, 1)^T$.

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Example 3

$$\dot{x_1} = -x_1 + x_1x_2$$
$$\dot{x_2} = -x_2 + x_1x_2$$

$$\Longrightarrow \begin{matrix} \dot{x_1} = -x_1(1-x_2) \\ \dot{x_2} = -x_2(1-x_1) \end{matrix}$$

$\dot{x_1} = 0\ and\ \dot{x_2} = 0$ for eq. point

$$\Longrightarrow \begin{matrix} \dot{x_1} = 0 \Longrightarrow x_1 = 0\ or\ x_2 = 1 \\ \dot{x_2} = 0 \Longrightarrow x_2 = 0\ or\ x_1 = 1 \end{matrix}$$

$$\frac{\partial f}{\partial x} = \begin{bmatrix} -1 + x_2 & x_1 \\ x_2 & -1 + x_1 \end{bmatrix}$$

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Analysis

eq. points: $(0,0)^T$ and $(1,1)^T$

$(0,0)^T$: $\text{J} = \begin{bmatrix} -1 & 0 \\ 0 & -1 \end{bmatrix} \Longrightarrow (\lambda+1)^2 = 0$

$\Longrightarrow \lambda = -1, -1 \Longrightarrow S.S.Stable$

$(1,1)^T$: $\text{J} = \begin{bmatrix} 0 & 1 \\ 1 & 0 \end{bmatrix} \Longrightarrow \lambda^2 - 1 = 0$

$\Longrightarrow \lambda = 1, -1 \Longrightarrow S.S.Unstable$

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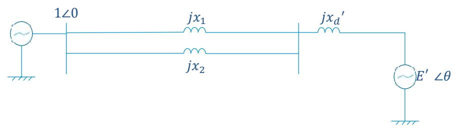
Transient Stability Analysis



Pre−fault $t < 0$ $\overset{\binom{\theta_s}{1}}{\Longrightarrow}$ Fault−on t=0 to t_c $\overset{\binom{\theta_c}{\omega_c}}{\Longrightarrow}$ Post−fault $t > t_c$

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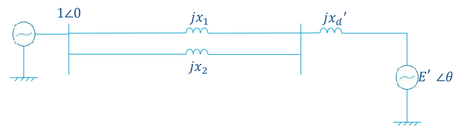
Pre-fault



$$\dot{\theta} = (\omega - 1)\omega_s$$
$$2H\dot{\omega} = P_m - P_e^{pre} - P_d$$
$$P_m = P_e^{pre} = P_{max}^{pre}\sin\theta$$
$$P_{max} = \frac{E' \cdot 1}{x_d{}' + (x_1 \parallel x_2)} \qquad \mathrm{x} = \begin{pmatrix} \theta_s^{pre} \\ 1 \end{pmatrix}$$

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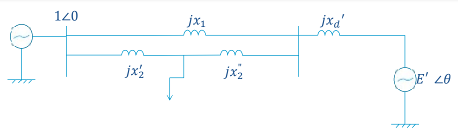
Fault-on



$$\dot{\theta} = (\omega - 1)\omega_s$$
$$2H\dot{\omega} = P_m - P_e^{fault} - P_d$$
$$P_e \downarrow \Longrightarrow \dot{\omega} > 0 \Longrightarrow \omega \uparrow \Longrightarrow \theta \uparrow$$
$$\mathrm{t} = t_c \quad \text{fault cleared} \longrightarrow \mathrm{x} = \begin{pmatrix} \theta_c \\ \omega_c \end{pmatrix}$$

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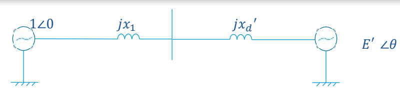
Post-fault



$$\dot{\theta} = (\omega - 1)\omega_s$$
$$2H\dot{\omega} = P_m - P_e^{pos} - P_d$$
$$P_e^{post} = P_{max}^{post}\sin\theta,\ P_{max}^{post} = \frac{E' \cdot 1}{x_d{}' + x_1}$$

Can system recover?

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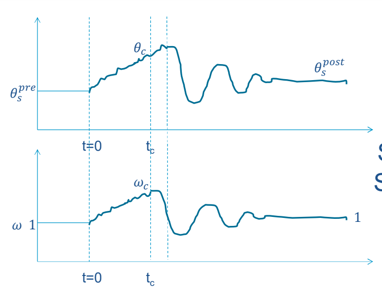
Transient stable case



Stable.
Small t_c

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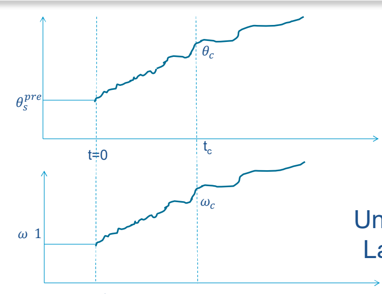
Transient unstable case



Unstable.
Large t_c

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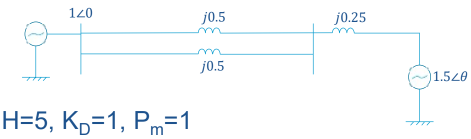
Example



H=5, K_D=1, P_m=1

Pre-fault:

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Pre-fault system

$$P_e = \frac{1.5}{0.5}\sin\theta = 3\sin\theta$$

$$\dot{\theta} = (\omega - 1)\omega_s$$

$$10\dot{\omega} = 1 - 3\sin\theta - (\omega - 1)$$

Equilibria:

$$\omega = 1, \qquad 1 = 3\sin\theta \Longrightarrow \theta = \sin^{-1}\frac{1}{3} = 19.5^o$$

$$x_s^{pre} = \begin{pmatrix} 19.5^o \\ 1 \end{pmatrix}$$

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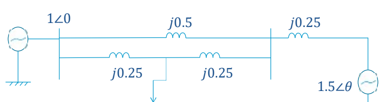
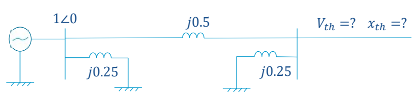
Fault-on system

Fault occurs $\Downarrow t = 0$

Fault-on: middle of lower line





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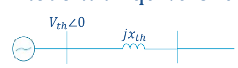
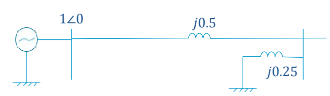
Thevenin equivalents

$\Downarrow$ *Thevenin* Equivalent



to find V_{th}:



$$V_{th} = \frac{0.25}{0.5 + 0.25} \cdot 1\angle 0 = \frac{1}{3}\angle 0$$

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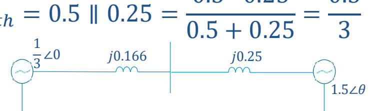
Thevenin equivalents

to find x_{th}:

$$x_{th} = 0.5 \parallel 0.25 = \frac{0.5 \cdot 0.25}{0.5 + 0.25} = \frac{0.5}{3}$$



$$P_e^{fault} = \frac{1.5 \cdot \frac{1}{3}}{0.25 + 0.166}\sin\theta = 1.2\sin\theta$$

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Fault-on system response

$$\dot{\theta} = (\omega - 1)\omega_s$$

$$10\dot{\omega} = 1 - 1.2\sin\theta - (\omega - 1)$$

Integrate from $\begin{pmatrix} 19.5^o \\ 1 \end{pmatrix}$ *at t=0 to clearing time say t=6 cycles=0.1 sec.*

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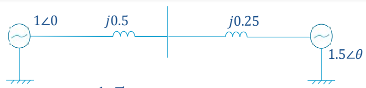
Post-fault system

Post-fault:



$$P_e^{post} = \frac{1.5}{0.5+0.25}\sin\theta = 2\sin\theta$$

$$\dot{\theta} = (\omega - 1)\omega_s$$

$$10\dot{\omega} = 1 - 2\sin\theta - (\omega - 1)$$

Integrate from $\begin{pmatrix}\theta_c \\ \omega_c\end{pmatrix}$ at t=t_c onwards to see if frequency returns to 1 (Stable) or diverges (Unstable).

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Euler Numerical integration

$\dot{x} = f(x), x(t_0) = x_0$, h = step size

$$\frac{\Delta x}{\Delta t} = f(x) \Longrightarrow \Delta x = f(x)\cdot\Delta t$$

$$\Longrightarrow x(t_0 + h) - x(t_0) = f\big(x(t_0)\big)\cdot h$$

$$x(t_0 + h) = x(t_0) + f\big(x(t_0)\big)\cdot h$$

$$\overset{k=0}{\Longrightarrow} \quad x_{k+1} = x(t_{k+1}) = x_k + f(x_k)\cdot h$$

$t_k = t_0$ $\qquad$ $t_{k+1} = t_k + h$

$x_k = x_0$

k=k+1

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Fault-on trajectory

$$x_s^{pre} = \begin{pmatrix}0.3398 \\ 1\end{pmatrix}$$

$$\Downarrow t = 0$$

Integrate fault-on

$$\dot{\theta} = (\omega - 1)\omega_s$$

$$10\dot{\omega} = 1 - 1.2\sin\theta - (\omega - 1)$$

from $\begin{pmatrix}0.3398 \\ 1\end{pmatrix}$ at t=0

to $\begin{pmatrix}\theta_c \\ \omega_c\end{pmatrix}$ at t=t_c

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Post-fault system

$$\Downarrow t = t_c$$

Integrate post-fault say for 30 seconds

$$\dot{\theta} = (\omega - 1)\omega_s$$

$$10\dot{\omega} = 1 - 2\sin\theta - (\omega - 1)$$

from $\begin{pmatrix}\theta_c \\ \omega_c\end{pmatrix}$ at t=t_c

onwards

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Euler Algorithm

$$k = 0$$

$$t_k = t_0,\ x_k = x_0$$

$$\Downarrow$$

k=k+1

$$t_k = t_{final}? \overset{Ye}{\Longrightarrow} Stop$$

$$\Downarrow No$$

$$x(t_{k+1}) = x(t_k) + f(x(t_k))\cdot h$$

$$t_{k+1} = t_k + h$$

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Euler Iterations Example

$$x_s^{pre} = \begin{pmatrix}0.3398 \\ 1\end{pmatrix}$$

$$\Downarrow t = 0$$

Integrate fault-on

$$\dot{\theta} = (\omega - 1)\omega_s$$

$$10\dot{\omega} = 1 - 1.2\sin\theta - (\omega - 1)$$

from $\begin{pmatrix}0.3398 \\ 1\end{pmatrix}$ at t=0.

h = 0.002.

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Euler Iterations Example

$$\dot{\theta}|_{t=0} = 0.0$$
$$\dot{\omega}|_{t=0} = 0.06$$
$$\theta\Big|_{0.002} = 0.3398 + 0.002 * 0.0 = 0.3398$$
$$\omega|_{0.002} = 1 + 0.002 * 0.06 = 1.00012$$

$$\Downarrow h = 2$$

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Euler Iterations

$$\Downarrow k = 2$$
$$\dot{\theta}|_{t=0.002} = 0.0452$$
$$\dot{\omega}|_{t=0.002} = 0.06$$
$$\Downarrow$$
$$\theta\Big|_{0.004} = 0.3398 + 0.002 * 0.0452 = 0.3399$$
$$\omega|_{0.00} = 1.00012 + 0.002 * 0.06 = 1.00024$$

Continue till t=tc. Then, switch to post-fault equations and continue iterations till end time.

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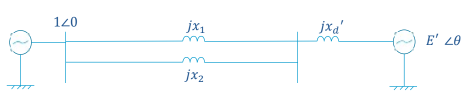
Analytical criterion

Pre-fault



$$P_e^{pre} = \frac{E' \cdot 1}{x_d' + (x_1 \parallel x_2)} \sin\theta$$
$$P_{max}^{pre} = \frac{E' \cdot 1}{x_d' + (x_1 \parallel x_2)}$$

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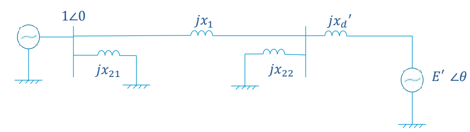
Fault-on system



$$P_e^{fault} = \frac{E' \cdot V_{Th}}{x_d' + x_{Th}} \sin\theta$$
$$P_{max}^{fault} = \frac{E' \cdot V_{Th}}{x_d' + x_{Th}}$$

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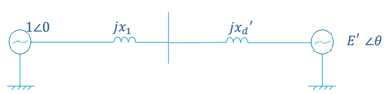
Post-fault system



$$P_e^{post} = \frac{E' \cdot 1}{x_d' + x_1} \sin\theta$$
$$P_{max}^{post} = \frac{E' \cdot 1}{x_d' + x_1}$$

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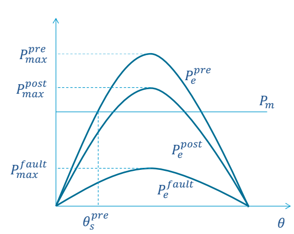
Power-Angle curves



$$P_{max}^{pre} = \frac{E' \cdot 1}{x_d' + (x_1 \parallel x_2)}$$
$$P_{max}^{fault} = \frac{E' \cdot V_{Th}}{x_d' + x_{Th}}$$
$$P_{max}^{post} = \frac{E' \cdot 1}{x_d' + x_1}$$

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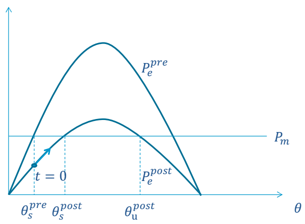
Transient analysis

Fault clearing assumed instantaneous. K_D=0



$$2H\dot{\omega} = P_m - P_e$$

1) $P_e^{post} < P_m \Rightarrow$
$\dot{\omega} > 0 \Longrightarrow \omega \uparrow$

2) $P_e^{post} > P_m \Rightarrow$
$\dot{\omega} < 0 \Longrightarrow \omega \downarrow$

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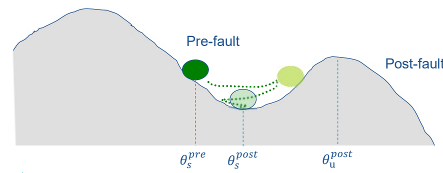
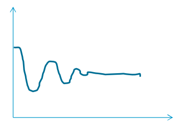
Transient stable case





Net Acceleration < Maximum Deceleration

⟹Stable

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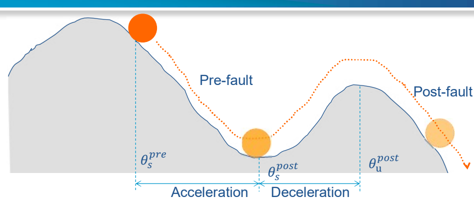
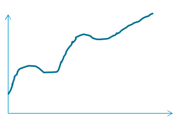
Transient unstable case





Net Acceleration > Maximum Deceleration

⟹Unstable

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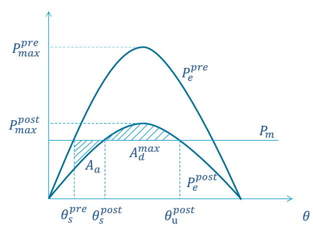
Equal Area Criterion



$A_a < A_d^{max}$
$\Longrightarrow Stable$
$A_a > A_d^{max}$
$\Longrightarrow Unstable$

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Area Definitions

$$A_a = \int_{\theta_s^{pre}}^{\theta_s^{post}} (P_T - P_e^{post})d\theta \propto KE_{acceleration}$$

$$A_d^{max} = \int_{\theta_s^{post}}^{\theta_u^{post}} (P_e^{post} - P_T)d\theta \propto KE_{deceleration}^{max}$$

$A_a < A_d^{max} \Longrightarrow Transient\ Stable$
$A_a > A_d^{max} \Longrightarrow Transient\ Unstable$

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Equal Area Criterion

⟹ Pick up K.E. during acceleration from θ_s^{pre} to θ_s^{post}

⟹ Loses K.E. between θ_s^{post} and θ_u^{po}

⟹ When K.E. becomes zero, rotor angle turns back

⟹ stable if $KE_{acc} < KE_{dmax}$, i.e. $A_a < A_{dmax}$

⟹ $A_{dmax} < A_a$ ⟹ rotor angle goes past θ_u^{post}

⟹ Continues to accelerate

θ_u^{post} ⟹ "point of no return" ⟹ Transient unstable

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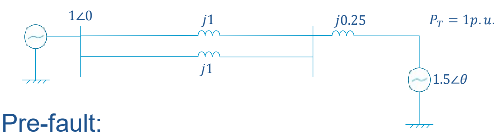
Example



Pre-fault:

$$P_e^{pre} = 2\sin\theta\,, P_m = 1 \Longrightarrow \theta_s^{pre} = 30^o$$

Post-fault:

$$P_e^{post} = \frac{1.5}{1.25}\sin\theta = 1.2\sin\theta \Longrightarrow \theta_s^{post} = 56.4^o$$

$$\theta_u^{post} = 123.6^o$$

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Area computations

$$A_a = \int_{30^o}^{56.4^o} (1 - 1.2\sin\theta)d\theta$$

$$= \int_{0.524}^{0.985} (1 - 1.2\sin\theta)d\theta$$

$$= (\theta + 1.2\cos\theta)\Big|_{0.524}^{0.985} = 0.0856$$

$$A_d^{max} = \int_{0.985}^{2.157} (1.2\sin\theta - 1)d\theta$$

$$= (-1.2\cos\theta - \theta)\Big|_{0.985}^{2.157} = 0.1553$$

$$A_d^{max} > A_a \Longrightarrow Transient\ Stable$$

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Higher loading case

Say $P_T = 1.1$

$$\Longrightarrow \theta_s^{pre} = 0.582$$

$$\theta_s^{post} = 1.16$$

$$\theta_u^{post} = 1.98$$

$$A_a = \int_{0.582}^{1.16} (1.1 - 1.2\sin\theta)d\theta = 0.1135$$

$$A_d^{max} = \int_{1.16}^{1.98} (1.2\sin\theta - 1.1)d\theta = 0.0555$$

$$A_d^{max} < A_a \Longrightarrow Unstable$$

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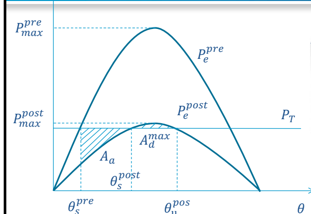
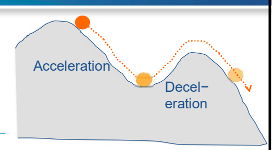
Transient Instability





$$A_a > A_d^{max} \Longrightarrow \begin{array}{c} KE\ keeps\ increasing \\ Rotor\ spins\ faster\ and\ faster \\ \Longrightarrow Instability \end{array}$$

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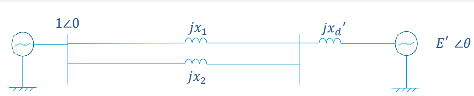
Equal Area Criterion Summary



$$\dot\theta = (\omega - 1)\omega_s$$

$$2H\dot\omega = P_T - P_e \quad - K_D(\omega - 1)$$

$$K_D = 0, t_c = 0$$

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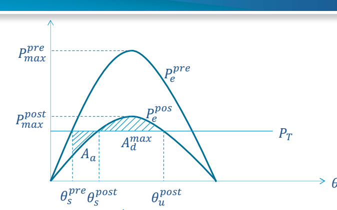
Analytical Criterion



$$A_a = \int_{\theta_s^{pre}}^{\theta_s^{post}} (P_T - P_e^{post})d\theta \propto KE_{acc}$$

$$A_d^{max} = \int_{\theta_s^{post}}^{\theta_u^{post}} (P_e^{post} - P_T)d\theta \propto KE_{dec}^{max}$$

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Stability Concepts

- Small-signal Stability
  - Ability to damp out small perturbations
  - Oscillations?
- Transient stability
  - Recovery from large disturbances
  - Islanding? Voltage collapse?

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