

MPC Trials

IBPSA Project 1 Expert Meeting (Virtual)

WP1.2 Day 1 Session 1

5/7/2021



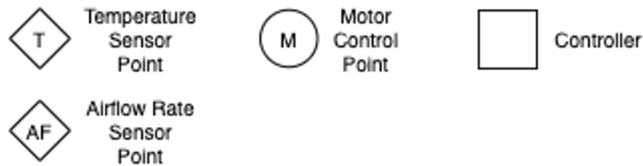
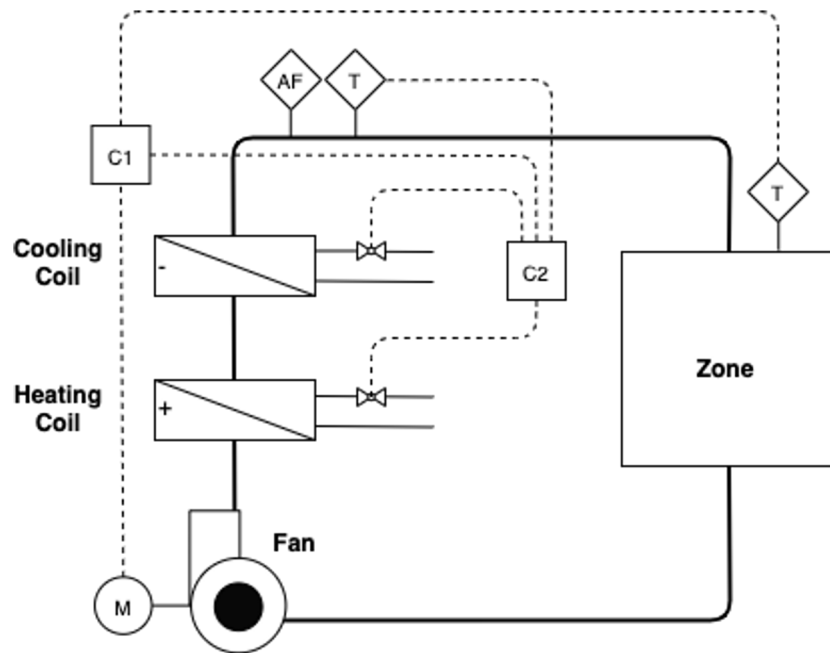
David Blum

Building Technology and Urban Systems
Lawrence Berkeley National Laboratory

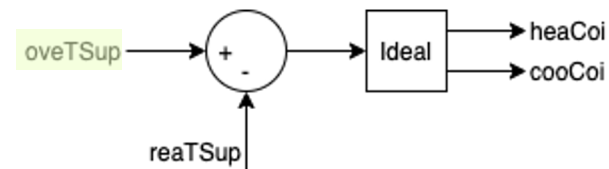
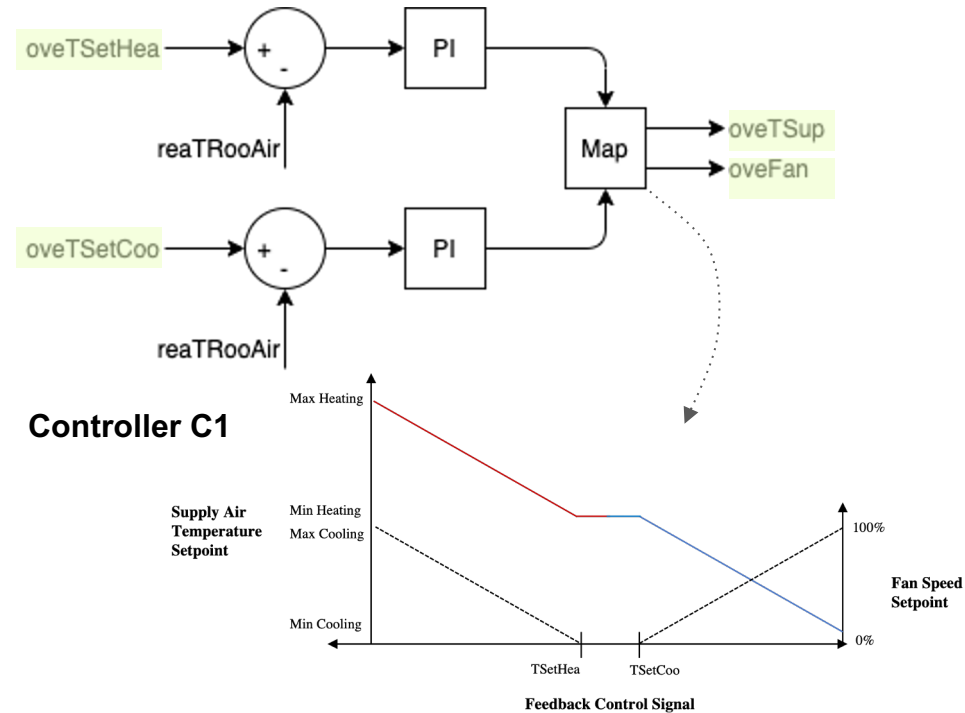
dhblum@lbl.gov

Test Case

bestest_air: (Developer LBNL, Reviewer KU Leuven)
BESTEST Case 900 room model with idealized fan coil unit.



System Schematic



Controller C2

MPC

Demo MPC Test on BESTEST Air Building Type Test Case

- Controller Implementation: MPCPy (Modelica + JModelica)
- Models:
 - Envelope: R3C3
 - Fan: $P_{\text{fan}} = a \cdot V^3 + b \cdot V^2 + c \cdot V + d$
 - Heating: $P_{\text{hea}} = Q_{\text{hea}} / \text{eff}_{\text{hea}}$
 - Cooling: $P_{\text{coo}} = Q_{\text{coo}} / \text{eff}_{\text{coo}}$
- Parameter Estimation: Least squares optimization
- State Estimation: Simple moving horizon
- Control Optimization: Minimize $(E_{\text{fan}} + E_{\text{hea}} + E_{\text{coo}})$
s.t. $T_{\text{Min}} \leq T_{\text{Zon}} \leq T_{\text{Max}}$
 $Q_{\text{Min}} \leq (Q_{\text{coo}} \text{ or } Q_{\text{hea}}) \leq Q_{\text{Max}}$
6 hours
- Horizon: 10 minutes
- Control step: 10 minutes
- System control signals: Fan Speed, SAT Setpoint

Interface

```

%% SETUP TEST CASE
# -----
# Set URL for test case
url = 'http://localhost:5000'
# Set simulation parameters
use_mpc = True
scenario = {'time_period': 'typical_cool_day',
            'electricity_price': 'constant'}
com_step = 600
test_warmup_period=7*24*3600
# -----

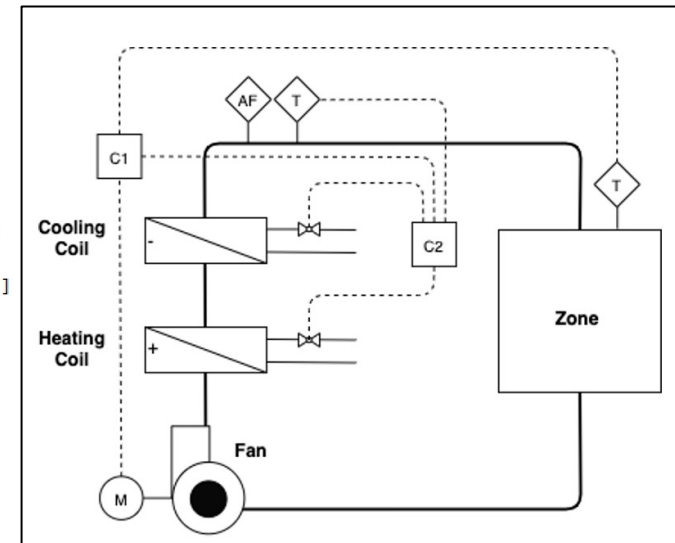
%% TEST CONTROLLER IMPORT
# -----
mpc = controller.controller()
mpc_horizon=6*3600
mpc_warmup_period=8*3600
measurement_points = ['zon_reaPPlu_y', 'zon_reaPLig_y', 'fcu_reaTSup_y',
                      'fcu_reaFanSet_y', 'zon_weaSta_reaWeaTDryBul_y',
                      'zon_weaSta_reaWeaHGloHor_y', 'zon_reaTRooAir_y']
# -----

%% RUN TEST CASE
# -----
# Set communication step
res = requests.put('{0}/step'.format(url), data={'step':com_step})
# Set forecast parameters
res = requests.put('{0}/forecast_parameters'.format(url), data={'horizon':mpc_horizon, 'interval':com_step})
# Run test case
print('\nRunning test case...')
# Initialize u
u = {}
# Initialize boptest
y = requests.put('{0}/scenario'.format(url), data=scenario).json()['time_period']
# Record test start time
start_time = y['time']
# Simulation Loop
while y:
    # Use MPC control after sufficient warmup
    if (y['time'] >= mpc_warmup_period + start_time) and use_mpc:
        # Update results in controller database
        res_his = dict()
        current = y['time']
        start = current - mpc_warmup_period
        for point in measurement_points:
            res_his[point] = requests.put('{0}/results'.format(url),
                                          data={'point_name': point, 'start_time':start, 'final_time':current}).json()[point]
        if 'time' not in res_his:
            res_his['time'] = requests.put('{0}/results'.format(url),
                                          data={'point_name': point, 'start_time':start, 'final_time':current}).json()['time']
        mpc.update_database(res_his, 'historic')
        # Update forecast in controller database
        res_for = requests.get('{0}/forecast'.format(url)).json()
        mpc.update_database(res_for, 'forecast')
        # Compute optimal control
        start_mpc = pd.Timestamp(seconds=current)+pd.to_datetime('1/1/2018')
        final_mpc = start_mpc + pd.Timestamp(seconds=mpc_horizon)
        start_historic_mpc = start_mpc - pd.Timestamp(seconds=mpc_warmup_period)
        mpc.optimize_control(start_mpc, final_mpc, start_historic_mpc)
        # Set control signals
        u = mpc.get_control_setpoints(start_mpc)
    # Advance simulation with input
    y = requests.post('{0}/advance'.format(url), data=u).json()
# -----

%% Get KPIs
# -----
kpis = requests.get('{0}/kpi'.format(url)).json()
print(kpis)

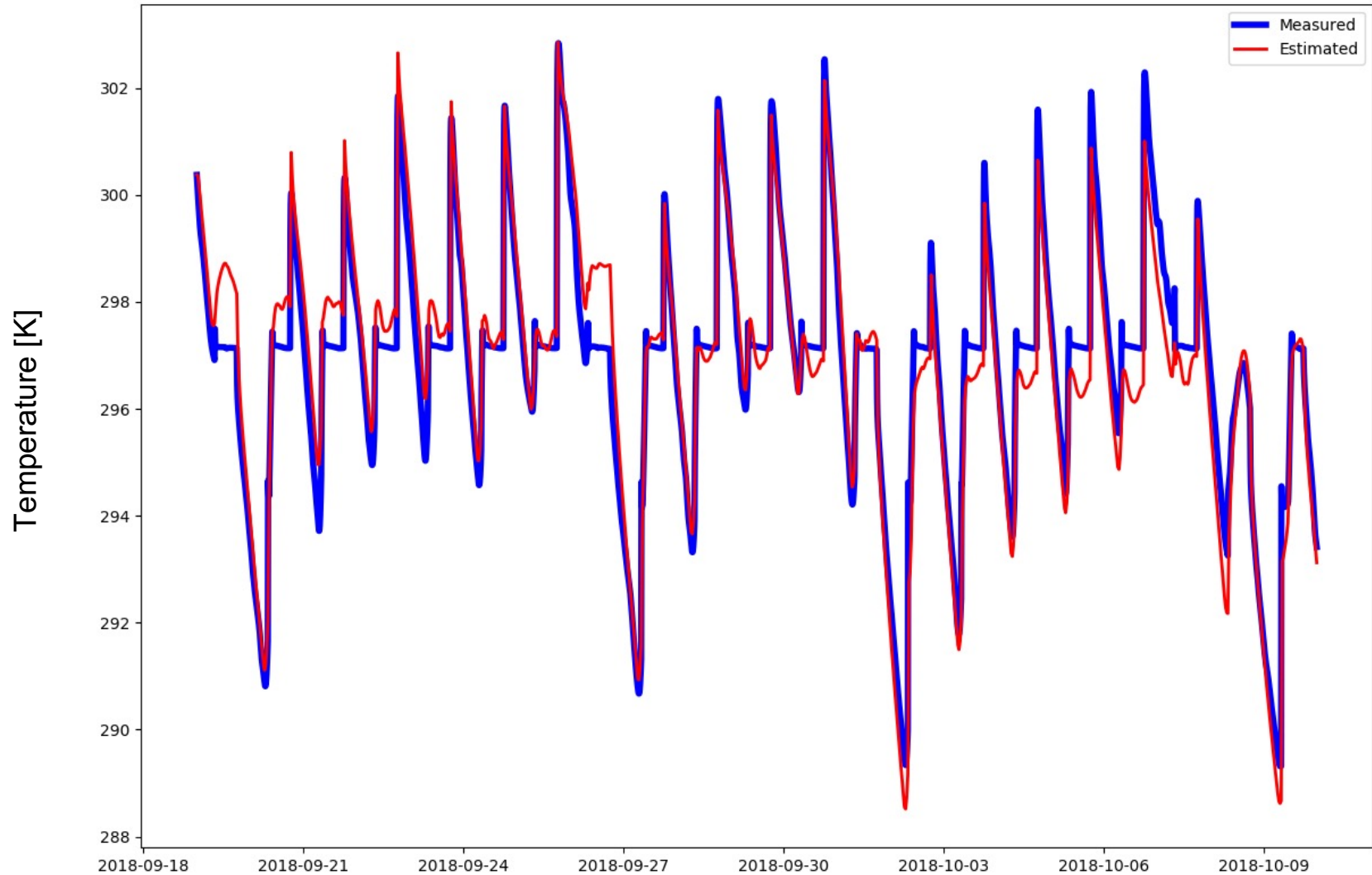
```

- Controller Implementation: MPCPy (Modelica + JModelica)
- Models:
 - Envelope: R3C3
 - Fan: $P_{fan} = a*V^3 + b*V^2 + c*V + d$
 - Heating: $P_{hea} = \frac{Q_{hea}}{eff_{hea}}$
 - Cooling: $P_{coo} = \frac{Q_{coo}}{eff_{coo}}$
- Parameter Estimation: Least squares optimization
- State Estimation: Simple moving horizon
- Control Optimization: Minimize $(E_{fan} + E_{hea} + E_{coo})$
 s.t. $T_{Min} \leq T_{Zon} \leq T_{Max}$
 $Q_{Min} \leq (Q_{coo} \text{ or } Q_{hea}) \leq Q_{Max}$
- Horizon: 6 hours
- Control step: 10 minutes
- System control signals: Fan Speed, SAT Setpoint ³



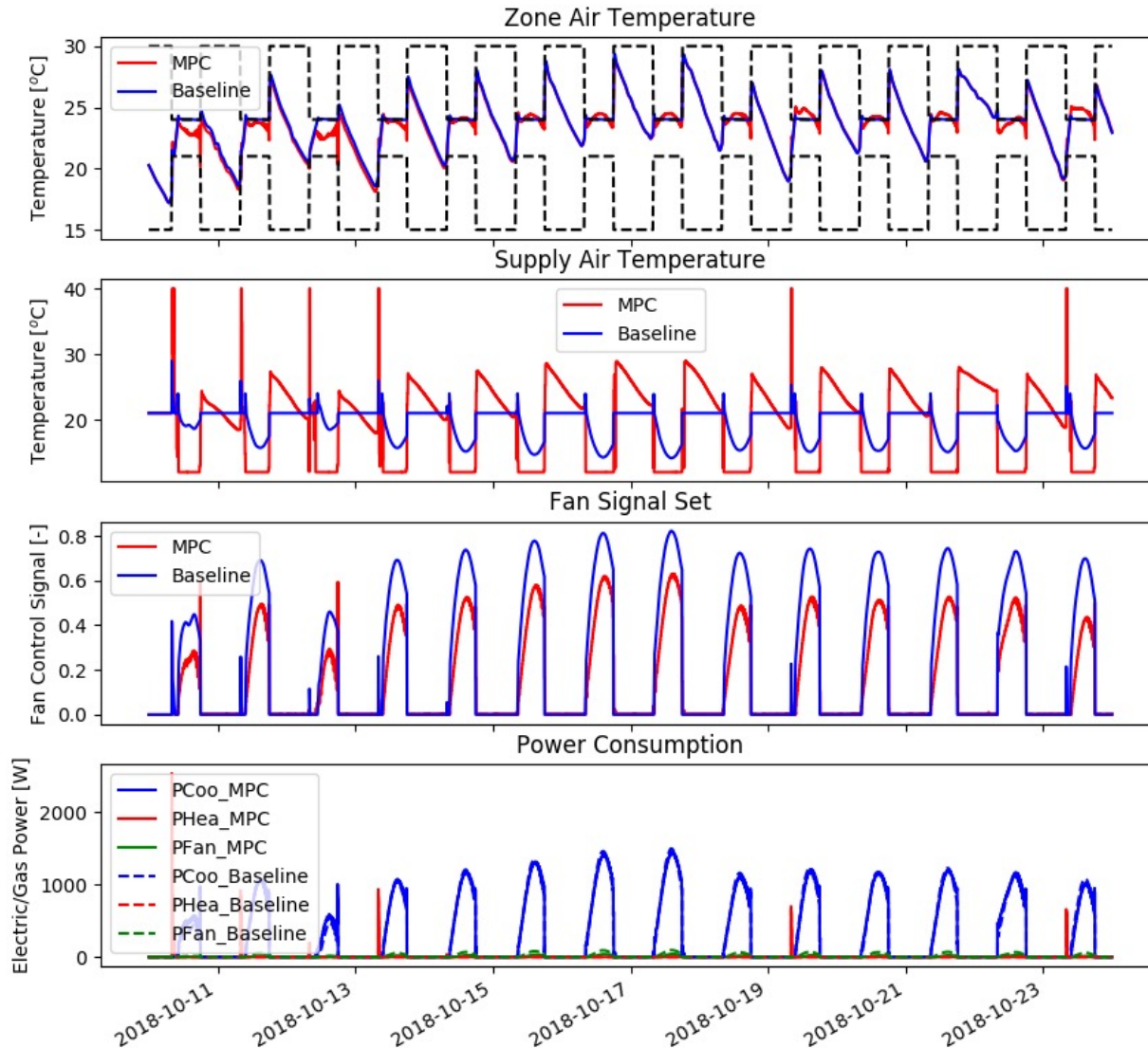
Results – Peak Cool Day Scenario

Parameter Estimation for Envelope Model



Results – Peak Cool Day Scenario

Control



KPI	Baseline	MPC
Energy [kWh]	106.8	105.3
Thermal Discomfort [Kh]	7.7	24.3
Computational Time Ratio	0.00065	0.0066

See also “BOPTREE”:
<https://docs.google.com/spreadsheets/d/1E-5wR7nasW8h6kEtrXnUzcRrEA6f7TlxjbtSdB1Cz3w/edit?usp=sharing>