



ELSEVIER

Contents lists available at ScienceDirect

Control Engineering Practice

journal homepage: www.elsevier.com/locate/conengprac

Control strategy of a dual induction motor: Anti-slip control application

Tahar Achour*, Mustapha Debbou, Maria Pietrzak-David

Université de Toulouse; INPT, UPS, LAPLACE (Laboratoire Plasma et Conversion d'Energie) ENSEEIHT, 2 rue Charles Camichel, BP 7122, F-31071 Toulouse cedex 7, France

ARTICLE INFO

Article history:

Received 18 March 2014

Accepted 9 December 2014

Available online 3 January 2015

Keywords:

Drive control

Cooperative control

Average differential control

Dual induction motors

Railway traction

Anti-slip control

ABSTRACT

The paper deals with a Dual Induction Motor control. A control strategy based on the Average Differential Control (ADC) is developed and adapted to work as an anti-slip control in a railway traction system. In addition to cancel the behaviour deviation between the motors supplied by a single inverter in case of an adhesion loss (or an unbalanced load), the proposed control strategy permits an action on the torque control to cancel the differential torque between the two motors. The control strategy is validated on a laboratory test bench with a Mechanical Railway Traction Load Emulator.

© 2014 Elsevier Ltd. All rights reserved.

1. Introduction

In embedded systems, cost, size and reliability are the main constraints to satisfy. Most applications require multiple drive units according to the desired power. In addition, they are generally coupled together mechanically and/or electrically, hence the importance given to the drive control of these multi-converter/multi-machine systems. A cooperative control of such a system can allow on the one hand reducing the number of control units and sensors used, to better manage the existing interaction between the different units, on the other hand, the robustness and service continuity aspects can be integrated by considering the overall multi-converter/multi-machine architecture for the system control.

In most of the Dual Induction Motor (IM) Controls proposed in the literature (Ando, Sato, Sazawa, & Ohishi, 2003; Bogiatzidis, Safacas, Mitronikas, & Christopoulos, 2012; Bouscayrol et al., 2006; Xu & Shi, 2011; Yu, Xiang, & Bing-jun, 2010), the drive controls are based on a weighted vector control strategy. The control is applied to a virtual motor chosen by the weighting, in other words, by the contribution of each motor to the control.

In the research work presented in Kelecý and Lorenz (1994) a control methodology for single inverter, dual induction motor drives are presented. This control structure is based on the Field

Oriented Control (FOC) and called the Average Differential Control (ADC). Besides to the control of the mean flux and torque through the d - and q -axes respectively, the mean differential variables are used to decrease the behaviour deviation between the motors.

The d -axis is no longer used only for the rotor flux control, but it is also used for the mean differential torque control. The q -axis is used as in the conventional FOC for the mean torque control. This strategy allows us to maintain the differential torque between the two motors as well as to cancel the gap between the motor speeds in case of an unbalanced load.

To improve the control performance of unbalanced load, Xu, Shi, and Li (2013) proposed a control strategy based on the weighted vector control. Comparatively to the study presented in Kelecý and Lorenz (1994), weighted and differential values are used for the control.

In the railway traction sector, to meet the aforementioned requirements, the industry is moving more and more towards a distributed traction system also called Electrical Multiple Units (EMU) (Briginshaw, 2008; Duffy, 2003; Jufer, 2010; Koseki, 2010; Lacôte, 2005; Lee, 2010; Smith, 2001; Uzuka, 2011). The other important point is that this architecture can improve compared to the concentrated traction is energy efficiency with a more efficient regenerative brake system (Sato & Yoshizawa, 2010; Teramoto, Ohishi, Makishima, Uezono, & Yasukawa, 2012).

In railway traction, the traction forces are transmitted to the rail through the contact of the wheels with the rail. So, the transmitted forces depend strongly on the adhesion coefficient μ . The main factor for an unbalanced load in a railway traction system is the adhesion force change. Its properties change greatly according to

* Corresponding author. Fax: +33 5 61 63 88 75.

E-mail addresses: tahar.achour@laplace.univ-tlse.fr (T. Achour), mustapha.debbou@laplace.univ-tlse.fr (M. Debbou), maria.david@laplace.univ-tlse.fr (M. Pietrzak-David).

Nomenclature

Symbols

$\mathbf{v}_s = \begin{bmatrix} v_{sd} \\ v_{sq} \end{bmatrix}$ stator-voltage vector reference frame ($d-q$)

$\mathbf{i}_s = \begin{bmatrix} i_{sd} \\ i_{sq} \end{bmatrix}$ stator-current vector reference frame ($d-q$)

$\mathbf{i}_{mr} = \begin{bmatrix} i_{mrd} \\ i_{mrq} \end{bmatrix}$ magnetizing rotor current vector reference frame ($d-q$)

$\mathbf{e} = \begin{bmatrix} E_d \\ E_q \end{bmatrix}$ electromotive force vector reference frame ($d-q$)

$\mathbf{J} = \begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix}$ symplectic matrix

Φ_r rotor flux vector

L_s, L_r, M_{sr} stator, rotor and mutual inductances

R_s, R_r stator and rotor resistances

$T_r = \frac{L_r}{R_r}$ rotor time constant

σ leakage or coupling factor

n_p number of pole pairs

V_{dc} input DC voltage

R_f, L_f, C_f input filter resistance, inductance and capacitance

v_{cf} filter capacitance voltage

i_{Lf} filter inductance current

P exchanged power between the motors and the filter

k_d, k_q coefficients of managing the dq axes contribution

k_{xd}, k_{xq} coefficients determining a constant contribution of each axis

$\theta_a, \theta_s, \theta_e$ electrical angular position of the reference frame ($d-q$), stator and rotor

$\omega_a, \omega_s, \omega_e$ electrical angular speed of the reference frame ($d-q$), stator and rotor

ω_{mi}, ω_{ri} angular velocities of the motors and wheels

V_t, V_{ri} linear velocities of the train and wheels

μ_i, ν_i adhesion coefficient and slip ratio of the axle i

μ_{maxi} maximum adhesion coefficient of the axle i

$F_{ri/rail}$ the tangential forces between rail and driving wheels

Γ_{em} electromagnetic torque

Γ_{li} the load torque

M_i the fictitious masses reduced to each axes

R_{ri} the wheel radiuses

\mathbf{X} matrices

\mathbf{x} vectors

x, X other variables

\wedge vector product

d/dt denotes a time derivative

Δ denotes a differential value between two variables or constants

$||$ absolute value

R_a, R_b, R_c axis of the three phase rotor

α, β axis of a static reference frame

S_d, S_q, S_o axis of a rotating reference frame

Superscripts

$*$ denotes a reference variable

$\hat{}$ denotes an estimated value

$\bar{}$ denotes an averaged value

Indices

d, q denote the axis of a rotating reference frame

the variation of the adhesion coefficient, which depends on the slip ratio, rail conditions and axle load. As shown in Fig. 1, the adhesion coefficient increases in the adhesion region and decreases in the slip region as a function of the slip ratio ν_s . In case of a worsening of a rail condition (e.g. from dry to wet condition), the value of the maximum adhesion coefficient greatly decreases.

In the works presented in the literature (Choi, 2008; Kadowaki et al., 2007; Park, Kim, & Choi, 2009, 2008; Villagra, D'Andréa-Novell, Fliess, &

Mounier, 2011; Yamazaki, Karino, Nagai, & Kamada, 2005; Yasuoka et al., 2009), the most of the anti-slip algorithms presented are based on estimators, observers or behaviour models with individual traction control. The authors in Bouscayrol et al. (2006) proposed a weighted voltage vector control strategy as an anti-slip strategy of an adhesion loss of one of the two induction motors supplied by a single inverter.

In this article, a drive control of a dual IM used in a railway traction system is proposed. In addition to cancel the behaviour deviation between the IM, it allows to cancel the difference between the motor torques in case of an unbalanced load. This objective is achieved by acting not only on the d -axis as proposed in Kelecly and Lorenz (1994) but also on the q -axis. This second degree of freedom allowed the use of this control structure as an anti-slip control. Compared to the aforementioned anti-slip algorithms, the proposed solution based on the improved ADC control can be applied in case of a distributed traction with a common supply and in case of a simultaneous adhesion loss of the two drive axes. In addition, only the sensors already available for motor control (current, voltage and speed sensors) are used.

Simulations and experiments are carried out to verify the proposed control method. The system and control description are firstly introduced. Then, the design of the control structure is presented and the system stability is discussed. Thereafter, the simulation results of the system behaviour and of the control sensitivity to the parameters are presented and discussed. Finally, the experimental results carried out on a laboratory test bench with a Railway Traction Mechanical Load Emulator are presented.

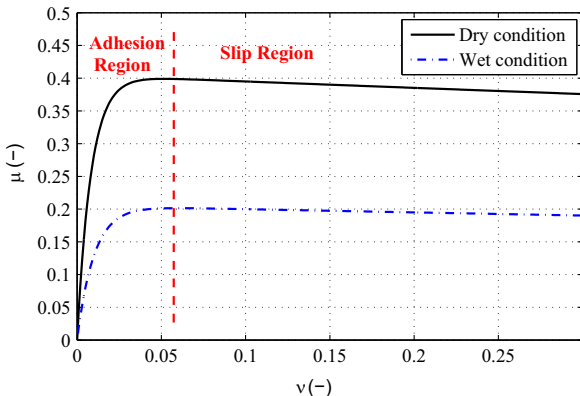


Fig. 1. Characteristics between the adhesion coefficient and the slip ratio for dry and wet conditions.

متن کامل مقاله

دریافت فوری ←

ISIArticles

مرجع مقالات تخصصی ایران

- ✓ امکان دانلود نسخه تمام متن مقالات انگلیسی
- ✓ امکان دانلود نسخه ترجمه شده مقالات
- ✓ پذیرش سفارش ترجمه تخصصی
- ✓ امکان جستجو در آرشیو جامعی از صدها موضوع و هزاران مقاله
- ✓ امکان دانلود رایگان ۲ صفحه اول هر مقاله
- ✓ امکان پرداخت اینترنتی با کلیه کارت های عضو شتاب
- ✓ دانلود فوری مقاله پس از پرداخت آنلاین
- ✓ پشتیبانی کامل خرید با بهره مندی از سیستم هوشمند رهگیری سفارشات