

# An Indirect Adaptive Type-2 Fuzzy Sliding Mode Power System Stabilizer

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**Abstract**— This paper introduces a new indirect adaptive type-2 fuzzy sliding mode controller as a power system stabilizer (PSS) that used to damp out the low frequency oscillations in power systems. The proposed controller design based on the integration of sliding mode control (SMC) and Adaptive type-2 fuzzy control. The type-2 fuzzy logic system is used to approximate the unknown system function and PI control term is used to eliminate chattering action in the design of sliding mode control. Using Lyapunov stability theory, the adaptation laws are developed to make the controller adaptive to take care of the changes due to the different operating conditions occurring in the power system and guarantees stability converge. The robustness of the proposed stabilizer has been tested on a single machine infinite bus model. Nonlinear simulation studies show the successful performance of the proposed AFSMPSS and to show its superiority over other AFSPSS, AFPSS and CPSS stabilizers.

**Keywords**— *sliding mode control; PI term; type -2 fuzzy system; adaptive control; power system stabilizer*

## I. INTRODUCTION

Power systems are complex and highly nonlinear. The change in operating conditions will result in low frequency oscillations that may persist for long periods of time. In some cases, the oscillations will limit the power transfer capability. Power system oscillations are damped by the introduction of a supplementary signal to the excitation system called power system stabilizer (PSS). Early researches deal with lead-lag compensation as a conventional type [1, 2] which are tuned using a linear model of fixed power system in the specific operating point. However, the system dynamic response may regress when the operating point changes to some extent. In addition the power systems are highly nonlinear and the operating conditions could change over a wide range as a result of load changes, line switching and unforeseeable major disturbances such as three phase faults, adaptive controller designs based on nonlinear models are more promising. The basic idea behind adaptive techniques is to estimate the uncertainties in the plant on-line based on measured signals [3,4]. However, adaptive PSSs can only deal with systems of known structure.

This problem is overcome by using artificial intelligence (fuzzy logic, neural networks) based techniques for the design

of PSSs [5-8]. Fuzzy logic provides a tool for using human expert knowledge in addition to mathematical knowledge. It is a model-free approach, which is generally considered suitable for controlling imprecisely defined systems. The parameters of the fuzzy power system stabilizer are kept fixed after the design is completed. The performance of the fuzzy PSS depends on the operating conditions of the power system.

In the last decades, the merits of adaptive control and intelligent techniques such as fuzzy logic have been applied to the designs of adaptive stabilizing controllers [9-14]. Recently, in an effort to improve the robustness of the adaptive fuzzy power system stabilizer a research effort has been engaged in the design of adaptive fuzzy sliding mode controllers [15, 16], which integrates the sliding mode controller design technique into the adaptive fuzzy controller design.

In this paper, an indirect adaptive type-2 fuzzy sliding mode power system stabilizer is designed to damp out the low frequency oscillations in power systems. The proposed stabilizer is initialized using the type-2 fuzzy logic system to approximate the unknown nonlinear functions of the power system model PI control term is used to eliminate chattering action in the design of sliding mode control. By the Lyapunov synthesis approach, adaptation laws are developed to make the fuzzy logic systems adaptive to change in the different operating conditions occurring in the power system. The simulation of the proposed stabilizers concept for a one machine-infinite bus system has shown that the performance of the adaptive type-2 fuzzy sliding mode power system stabilizer (AFSMPSS) is better than that of adaptive type-2 fuzzy synergetic (AFSPSS), adaptive type-2 fuzzy (AFPSS) and the conventional (CPSS) stabilizers.

## II. POWER SYSTEM MODEL

The dynamics of a single machine power system can be represented with a two-axis model [17] as in (1-5).

$$\frac{d\delta}{dt^2} = \omega - \omega_s \quad (1)$$

$$\frac{2H}{\omega_s} \frac{d\omega}{dt^2} = P_m - P_e \quad (2)$$

$$\frac{dE'_d}{dt} = \frac{1}{T'_{qo}} (-E'_d - (x_q - x'_q)I_q) \quad (3)$$

$$\frac{dE'_q}{dt} = \frac{1}{T'_{do}} (-E'_q - (x_d - x'_d)I_d + E_{fd}) \quad (4)$$

$$\frac{dE_{fd}}{dt} = \frac{1}{T_A} (K_A (V_{ref} - V_t + U_s) - E_{fd}) \quad (5)$$

In the design of the power system controller proposed in this paper, the dynamics model of generator can be expressed in the following nonlinear state-space equations:

$$\begin{aligned} \dot{x}_1 &= ax_2 \\ ax_2 &= f(x_1, x_2) + g(x_1, x_2)u \\ y &= x_1 \end{aligned} \quad (6)$$

Where  $a = -1/2H$ ,  $x_1 = \Delta\omega = \omega - \omega_s$  and  $x_2 = \Delta P = P_m - P_e$ ,  $H$  is the per unit machine inertia constant,  $\omega$  is the rotor speed and  $\omega_s$  is the synchronous speed are in per unit,  $P_m$  is the mechanical input power treated as a constant in the excitation controller design, i.e., it is assumed that the governor action is slow enough not to have any significant impact on the machine dynamics and  $P_e$  is the delivered electrical power.  $\underline{x} = [x_1, x_2]^T \in R^2$  is a measurable state vector. The PSS output  $u$  represents the controlling supplementary signal to be designed and  $y = \Delta\omega$  is the output state while  $f$  and  $g$  are nonlinear functions which are assumed to be unknown. (Eq.1) represents the machine during a transient period after a major disturbance has occurred in the system.

### III. SLIDING MODE CONTROL DESIGN

The control objective is to force  $y$  in the system (6) to track a given desired trajectory  $y_d$ . Then the control objective is determine a feedback control  $u = u(\underline{x})$  for the state  $y$  in the system (6) to track a given desired trajectory  $y_d$ ,

The elaboration of an indirect adaptive fuzzy sliding mode controller is presented in the rest of this section [15, 16], to achieve the above control objectives is discussed.

Let the tracking error be defined as:

$$\underline{e} = \underline{y} - \underline{y}_d = [e, \dot{e}]^T \quad (7)$$

and a sliding surface defined as:

$$s(\underline{e}) = k_1 e + \dot{e} = \underline{k}^T \underline{e} \quad (8)$$

Where  $\underline{k} = [k_1, 1]^T$  are the coefficients of the Hurwitzian polynomial  $h(\lambda) = \lambda + k_1$ . If the initial error vector  $\underline{e}(0) = 0$ , then the tracking problem can be considered as the state error vector  $\underline{e}$  remaining on the sliding surface  $s(\underline{e}) = 0$  for all  $t > 0$ . A sufficient condition to achieve this behavior is to select the control strategy such that:

$$\frac{1}{2} \frac{d}{dt} (S^2(\underline{e})) \leq -\eta |s| \quad \eta > 0 \quad (9)$$

From (8) and (9), we have

$$\dot{s} = k_1 \dot{e} + f(\underline{x}) + g(\underline{x})u - \ddot{y}_d. \quad (10)$$

If  $f$  and  $g$  are known, we can easily construct the sliding mode control  $u^* = u_{eq} - u_{sw}$  :

$$u^* = g^{-1}(\underline{x}) [-k_1 \dot{e} - f(\underline{x}) - \eta \text{sgn}(s) + \ddot{y}_d] \quad (11)$$

$$u_{eq} = g^{-1}(\underline{x}) [-k_1 \dot{e} - f(\underline{x}) + \ddot{y}_d] \quad (12)$$

$$u_{sw} = g^{-1}(\underline{x}) [\eta \text{sgn}(s)] \quad (13)$$

However, power system parameters for nonlinear functions are not well known and imprecise; therefore it is difficult to implement the control law (11) for unknown nonlinear system model. Not only  $f$  and  $g$  are unknown but the switching-type control term will cause chattering. An adaptive type-2 fuzzy sliding mode controller using type-2 fuzzy logic system and PI control term is proposed to solve these problems.

### IV. INDIRECT ADAPTIVE IT2 FUZZY SLIDING MODE CONTROL DESIGN

If  $f$  and  $g$  were known, we could easily construct the sliding mode control  $u^*$  introduced in the previous section, however,  $f$  and  $g$  are not known, we thus replace  $f(\underline{x}, t)$  and  $g(\underline{x}, t)$  by the interval type-2 fuzzy logic system  $\hat{f}(\underline{x} | \underline{\theta}_f)$ ,  $\hat{g}(\underline{x} | \underline{\theta}_g)$  which are in the form of (14-15) [18, 19].

$$\begin{aligned} \hat{f}(\underline{x} | \underline{\theta}_f) &= \frac{\hat{f}_l + \hat{f}_r}{2} = \frac{1}{2} \left( \underline{\theta}_{fl}^T \underline{\xi}_l(\underline{x}) + \underline{\theta}_{fr}^T \underline{\xi}_r(\underline{x}) \right) \\ &= \underline{\theta}_f^T \underline{\xi}_f(\underline{x}) \end{aligned} \quad (14)$$

$$\hat{g}(\underline{x} | \underline{\theta}_g) = \frac{\hat{g}_l + \hat{g}_r}{2} = \frac{1}{2} \left( \underline{\theta}_{gl}^T \underline{\xi}_l(\underline{x}) + \underline{\theta}_{gr}^T \underline{\xi}_r(\underline{x}) \right) = \underline{\theta}_g^T \underline{\xi}_g(\underline{x}) \quad (15)$$

to which we append a proportional integral PI control term to suppress the chattering action. The inputs and output of the latter are defined as

$$u_p = k_p h_1 + k_i h_2 \quad (16)$$

Where  $h_1 = s$ ,  $h_2 = \int s dt$ ,  $k_p$  and  $k_i$  are PI control gains. (16) can be rewritten as

$$\hat{p}(\underline{h} | \underline{\theta}_p) = \underline{\theta}_p^T \underline{\psi}(\underline{h}) \quad (17)$$

$\underline{\theta}_p = [k_p, k_i]^T \in R^2$  is an adjustable parameter vector, and  $\underline{\psi}^T(\underline{h}) = [h_1, h_2] \in R^2$  is a regressive vector. We use interval type-2 fuzzy logic systems to approximate the unknown functions  $f(\underline{x})$ ,  $g(\underline{x})$  and design an adaptive PI control term eliminate chattering due to sliding mode control. Hence, the control law becomes:

$$u = \frac{1}{\hat{g}(\underline{x} | \underline{\theta}_g)} \left[ -k_1 \dot{e} - \hat{f}(\underline{x} | \underline{\theta}_f) - \hat{p}(\underline{h} | \underline{\theta}_p) + \ddot{y}_d \right] \quad (18)$$

There for around the sliding surface, control law is introduced as.

$$\hat{u}_p = \begin{cases} \underline{\theta}_p^T \underline{\psi}(\underline{h}) & \text{if } |s| < \varphi \\ \eta \text{sgn}(s) & \text{if } |s| \geq \varphi \end{cases} \quad (19)$$

where is  $\varphi$  the thickness of the boundary layer.

Using the control law in (18), then (10) becomes:

$$\begin{aligned} \dot{s} &= k_1 \dot{e} + f(\underline{x}, t) + g(\underline{x}, t)u - \ddot{y}_d \\ &= f(\underline{x}, t) - \hat{f}(\underline{x} | \underline{\theta}_f) + (g(\underline{x}, t) - \hat{g}(\underline{x} | \underline{\theta}_g))u \\ &\quad - \hat{p}(\underline{h} | \underline{\theta}_p) \end{aligned} \quad (20)$$

The next task, is to replace  $\hat{f}$  and  $\hat{g}$  by type-2 fuzzy logic systems represented in (14-15),  $\hat{p}$  is given by (17) and to develop adequate adaptation laws for adjusting the parameters vector  $\underline{\theta}_f$ ,  $\underline{\theta}_g$  and  $\underline{\theta}_p$  while seeking a zero tracking error. Using the procedure suggested in [28, 29], the parameter vectors of  $\hat{f}(\underline{x} | \underline{\theta}_f)$  and  $\hat{g}(\underline{x} | \underline{\theta}_g)$  will be adapted according to the following rules.

**Theorem 1.** Consider the control problem of the nonlinear system (6). If the control (18) is used, if the interval type-2 fuzzy and PI are adjusted by the adaptive control law (21-25),

the closed-loop system signals will be bounded and the tracking error will converge to zero asymptotically.

$$\dot{\underline{\theta}}_{fl} = \gamma_1 s \underline{\xi}_{fl}(\underline{x}) \quad (21)$$

$$\dot{\underline{\theta}}_{fr} = \gamma_2 s \underline{\xi}_{fr}(\underline{x}) \quad (22)$$

$$\dot{\underline{\theta}}_{gl} = \gamma_3 s \underline{\xi}_{gl}(\underline{x})u \quad (23)$$

$$\dot{\underline{\theta}}_{gr} = \gamma_4 s \underline{\xi}_{gr}(\underline{x})u \quad (24)$$

$$\dot{\underline{\theta}}_p = \gamma_5 s \underline{\psi}(\underline{h}) \quad (25)$$

**Proof.** Define the optimal parameters vector

$$\underline{\theta}_f^* = \arg \min_{\underline{\theta}_f \in \Omega_f} \left( \sup_{\underline{x} \in R^n} \left| \hat{f}(\underline{x} | \underline{\theta}_f) - f(\underline{x}, t) \right| \right) \quad (26)$$

$$\underline{\theta}_g^* = \arg \min_{\underline{\theta}_g \in \Omega_g} \left( \sup_{\underline{x} \in R^n} \left| \hat{g}(\underline{x} | \underline{\theta}_g) - g(\underline{x}, t) \right| \right) \quad (27)$$

$$\underline{\theta}_p^* = \arg \min_{\underline{\theta}_p \in \Omega_p} \left( \sup_{\underline{h} \in R^n} \left| \hat{p}(\underline{h} | \underline{\theta}_p) - u_{sw} \right| \right) \quad (28)$$

Where  $\Omega_f$ ,  $\Omega_g$  and  $\Omega_p$  are constraint sets for  $\underline{\theta}_f$ ,  $\underline{\theta}_g$  and  $\underline{\theta}_p$ , respectively. Define the minimum approximation error:

$$\varepsilon = f(\underline{x}, t) - \hat{f}(\underline{x} | \underline{\theta}_f^*) + (g(\underline{x}, t) - \hat{g}(\underline{x} | \underline{\theta}_g^*))u \quad (29)$$

**Assumption 1** The parameters  $\underline{\theta}_f$ ,  $\underline{\theta}_g$  and  $\underline{\theta}_p$  belong to the constraint sets  $\Omega_f$ ,  $\Omega_g$  and  $\Omega_p$  respectively, which are defined as

$$\Omega_f = \{ \underline{\theta}_f \in R^n : \|\underline{\theta}_f\| \leq M_f \} \quad (30)$$

$$\Omega_g = \{ \underline{\theta}_g \in R^n : 0 < \zeta \leq \|\underline{\theta}_g\| \leq M_g \} \quad (31)$$

$$\Omega_p = \{ \underline{\theta}_p \in R^n : \|\underline{\theta}_p\| \leq M_p \} \quad (32)$$

$M_f$ ,  $\zeta$ ,  $M_g$  and  $M_p$  are positive constants designer specified for estimated parameters' bounds. Assuming that fuzzy  $\underline{\theta}_f$ ,  $\underline{\theta}_g$  and PI control parameter  $\underline{\theta}_p$  do not reach the boundaries.

So, (20) can be written as

$$\begin{aligned}
\dot{s} &= \underline{\phi}_f^T \underline{\xi}(x) + \underline{\phi}_g^T \underline{\xi}(x)u + \underline{\phi}_p^T \underline{\psi}(h) - \hat{p}(h | \underline{\theta}_p^*) + \varepsilon \\
&= \frac{1}{2} \left( \underline{\theta}_{fl}^T \underline{\xi}_{fl}(x) + \underline{\theta}_{fr}^T \underline{\xi}_{fr}(x) \right) + \frac{1}{2} \left( \underline{\theta}_{gl}^T \underline{\xi}_{gl}(x) + \underline{\theta}_{gr}^T \underline{\xi}_{gr}(x) \right) u \\
&\quad + \underline{\phi}_p^T \underline{\psi}(h) - \hat{p}(h | \underline{\theta}_p^*) + \varepsilon
\end{aligned} \quad (33)$$

Where  $\underline{\phi}_f = \underline{\theta}_f^* - \underline{\theta}_f$ ,  $\underline{\phi}_g = \underline{\theta}_g^* - \underline{\theta}_g$ ,  $\underline{\phi}_p = \underline{\theta}_p^* - \underline{\theta}_p$ .

Now let us consider the Lyapunov function candidate

$$\begin{aligned}
V &= \frac{1}{2} s^2 + \frac{1}{4\gamma_1} \underline{\phi}_{fl}^T \underline{\phi}_{fl} + \frac{1}{4\gamma_2} \underline{\phi}_{fr}^T \underline{\phi}_{fr} + \frac{1}{4\gamma_3} \underline{\phi}_{gl}^T \underline{\phi}_{gl} \\
&\quad + \frac{1}{4\gamma_4} \underline{\phi}_{gr}^T \underline{\phi}_{gr} + \frac{1}{2\gamma_5} \underline{\phi}_p^T \underline{\phi}_p
\end{aligned} \quad (34)$$

The time derivative of  $V$  along the error trajectory is:

$$\begin{aligned}
\dot{V} &= s\dot{s} + \frac{1}{2\gamma_1} \underline{\phi}_{fl}^T \dot{\underline{\phi}}_{fl} + \frac{1}{2\gamma_2} \underline{\phi}_{fr}^T \dot{\underline{\phi}}_{fr} + \frac{1}{2\gamma_3} \underline{\phi}_{gl}^T \dot{\underline{\phi}}_{gl} \\
&\quad + \frac{1}{\gamma_4} \underline{\phi}_{gr}^T \dot{\underline{\phi}}_{gr} + \frac{1}{\gamma_5} \underline{\phi}_p^T \dot{\underline{\phi}}_p \\
&= s \left( \frac{1}{2} (\underline{\theta}_{fl}^T \underline{\xi}_{fl}(x) + \underline{\theta}_{fr}^T \underline{\xi}_{fr}(x)) + \frac{1}{2} (\underline{\theta}_{gl}^T \underline{\xi}_{gl}(x) + \underline{\theta}_{gr}^T \underline{\xi}_{gr}(x)) u \right. \\
&\quad \left. + \underline{\phi}_p^T \underline{\psi}(h) - \hat{p}(h | \underline{\theta}_p^*) + \varepsilon \right) + \frac{1}{2\gamma_1} \underline{\phi}_{fl}^T \dot{\underline{\phi}}_{fl} + \frac{1}{2\gamma_2} \underline{\phi}_{fr}^T \dot{\underline{\phi}}_{fr} \\
&\quad + \frac{1}{2\gamma_3} \underline{\phi}_{gl}^T \dot{\underline{\phi}}_{gl} + \frac{1}{\gamma_4} \underline{\phi}_{gr}^T \dot{\underline{\phi}}_{gr} + \frac{1}{\gamma_5} \underline{\phi}_p^T \dot{\underline{\phi}}_p \\
&= \frac{1}{2\gamma_1} \underline{\phi}_{fl}^T (\gamma_1 s \underline{\xi}_{fl}(x) + \dot{\underline{\phi}}_{fl}) + \frac{1}{2\gamma_2} \underline{\phi}_{fr}^T (\gamma_2 s \underline{\xi}_{fr}(x) + \dot{\underline{\phi}}_{fr}) \\
&\quad + \frac{1}{2\gamma_3} \underline{\phi}_{gl}^T (\gamma_3 s \underline{\xi}_{gl}(x)u + \dot{\underline{\phi}}_{gl}) + \frac{1}{2\gamma_4} \underline{\phi}_{gr}^T (\gamma_4 s \underline{\xi}_{gr}(x)u + \dot{\underline{\phi}}_{gr}) \\
&\quad + \frac{1}{\gamma_5} \underline{\phi}_p^T (s \underline{\psi}(h) + \dot{\underline{\phi}}_p) - s \hat{p}(h | \underline{\theta}_p^*) + s \varepsilon \\
&\leq \frac{1}{2\gamma_1} \underline{\phi}_{fl}^T (\gamma_1 s \underline{\xi}_{fl}(x) + \dot{\underline{\phi}}_{fl}) + \frac{1}{2\gamma_2} \underline{\phi}_{fr}^T (\gamma_2 s \underline{\xi}_{fr}(x) + \dot{\underline{\phi}}_{fr}) \\
&\quad + \frac{1}{2\gamma_3} \underline{\phi}_{gl}^T (\gamma_3 s \underline{\xi}_{gl}(x)u + \dot{\underline{\phi}}_{gl}) + \frac{1}{2\gamma_4} \underline{\phi}_{gr}^T (\gamma_4 s \underline{\xi}_{gr}(x)u + \dot{\underline{\phi}}_{gr}) \\
&\quad + \frac{1}{\gamma_5} \underline{\phi}_p^T (s \underline{\psi}(h) + \dot{\underline{\phi}}_p) - s \eta \operatorname{sgn}(s) + s \varepsilon
\end{aligned} \quad (35)$$

Where  $\dot{\underline{\phi}}_{fr} = -\dot{\underline{\theta}}_{fr}$ ,  $\dot{\underline{\phi}}_{fl} = -\dot{\underline{\theta}}_{fl}$ ,  $\dot{\underline{\phi}}_{gr} = -\dot{\underline{\theta}}_{gr}$ ,  $\dot{\underline{\phi}}_{gl} = -\dot{\underline{\theta}}_{gl}$  and  $\dot{\underline{\phi}}_p = -\dot{\underline{\theta}}_p$ .

Substitute (21-25) into (35), then we have

$$\dot{V} \leq s \varepsilon - |s| \eta \leq 0 \quad (36)$$

Since  $\varepsilon$  is being the minimum approximation error, (36) is the best we can obtain. Therefore all signals in the system are bounded. Obviously,  $e(t)$  will be bounded if  $e(0)$  is bounded for all  $t$ . Since if the reference signal  $y_d$  is bounded, then system states  $x$  will be bounded. We need proving that  $s \rightarrow 0$  as  $t \rightarrow \infty$ . Assuming that  $|s| \leq \eta_s$  then (36) can be further simplified to

$$\dot{V} \leq |s| |\varepsilon| - |s| \eta \leq \eta_s |\varepsilon| - |s| \eta \quad (37)$$

Integrating both sides of (37), we have

$$\int_0^t |s| d\tau \leq \frac{1}{\eta} (|V(0)| + |V(t)|) + \frac{\eta_s}{\eta} \int_0^t |\varepsilon| d\tau \quad (38)$$

then we have  $s \in L_1$ . From (36), we know that  $s$  is bounded and every term in (33) is bounded. Hence,  $s, \dot{s} \in L_\infty$ , use of Barbalat's lemma [20]. We have  $s \rightarrow 0$  as  $t \rightarrow \infty$ , the system is stable and the error will asymptotically converge to zero.

The simplified schematic diagram of the proposed power system stabilizer and the interconnection of these techniques are illustrated in Fig.1.

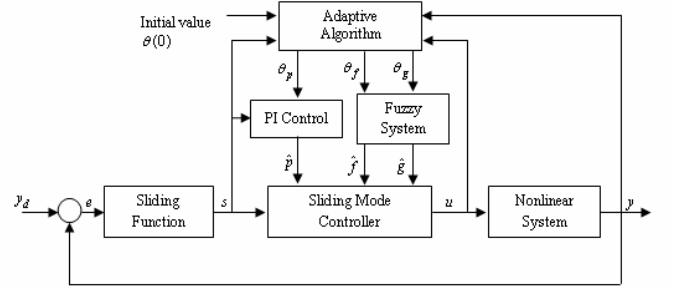


Figure 1. The proposed indirect adaptive fuzzy sliding mode PSS

## V. APPLICATION TO THE SINGLE MACHINE INFINITE-BUS MODEL

A nonlinear power system model consisting of a single machine connected to a infinite bus (SMIB) through a step-up transformer and double circuit of three phase transmission lines is chosen for time domain simulation studies. Details of the system data and the dynamics model of generator are given in [21]. A diagram representation of the power system is shown in Fig.2.

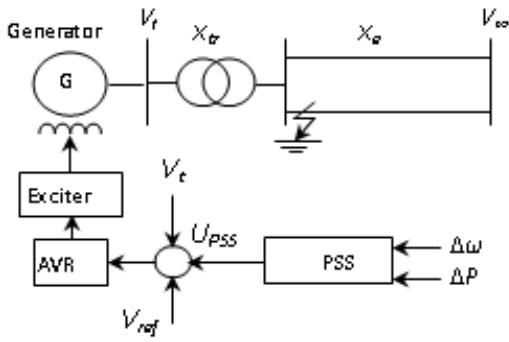


Figure 2. Single Machine Infinite Bus Power System.

Three different operating conditions are used to evaluate the soundness of the approach. A three-phase fault to ground on the transmission line occurring at  $t=0.2$  sec with a duration of 0.07 sec, where considered as the large disturbance in the following nonlinear simulations. In each case, the performance of the proposed indirect adaptive type-2 fuzzy sliding mode power system stabilizer (AFSMPSS) is compared with adaptive type-2 fuzzy synergetic (AFSPSS), adaptive type-2 fuzzy (AFSS) and conventional (CPSS).

1) *First Case:* Normal operating conditions

Operating point :  $P_0=0.9$  pu,  $Q_0=0.3$  pu and  $X_e=0.2$  pu

Fig. 3, show the simulations of the system responses under a three-phase fault for the stabilizers represent speed deviation. In the absence of PSS presents dangerous oscillations that would end up in loss of synchronism, with the stabilizers AFPSS and AFSPSS the damping of oscillations is improved compared to conventional (CPSS). From the figure, it can be clearly seen that the system response for the proposed indirect AFSMPSS seems to be the best response showing rapid oscillations suppression, which indicates adequate damping.

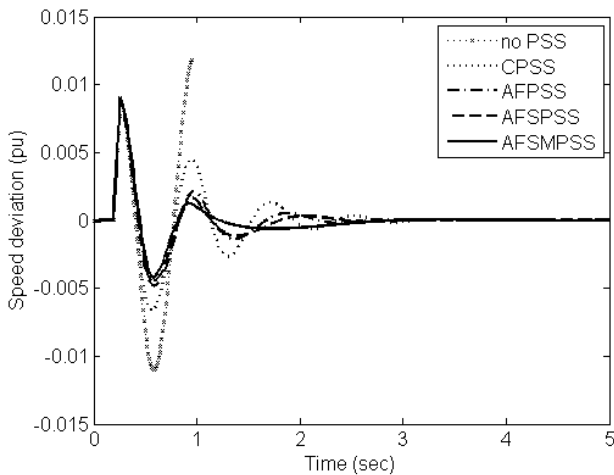


Figure 3. Response to a three-phase fault for the first case.

2) *Second Case:* Heavy reactive load and weak connection

Operating point:  $P_0=0.8$  pu,  $Q_0=0.7$  pu and  $X_e=0.4$  pu.

Here system response is more oscillatory in this case. As observed, the oscillation was damped with the AFPSS, AFSPSS and it was damped with a much faster response with the indirect AFSMPSS as illustrated in Fig. 4.

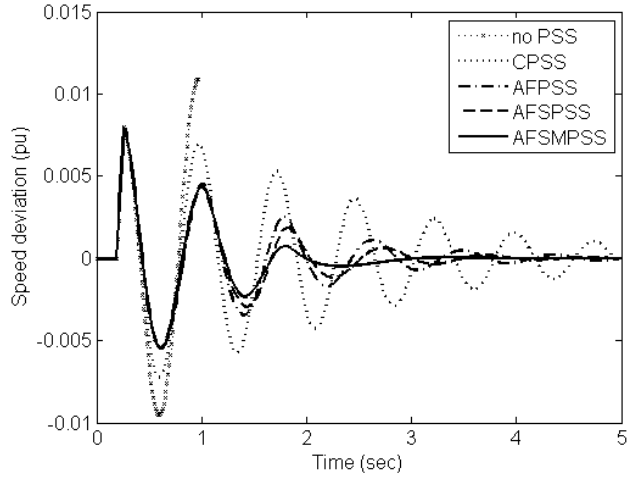


Figure 4. Response to a three-phase fault for the second case.

3) *Third Case:* Importing reactive power

Operating point :  $P_0=0.9$  pu,  $Q_0=-0.3$  pu and  $X_e=0.15$  pu.

In this case, the synchronous machine is absorbing the reactive power and it is easily to lead unstable. From Fig. 5 can be seen that the system response for indirect AFSMPSS exhibits superior damping performance of its author PSSs.

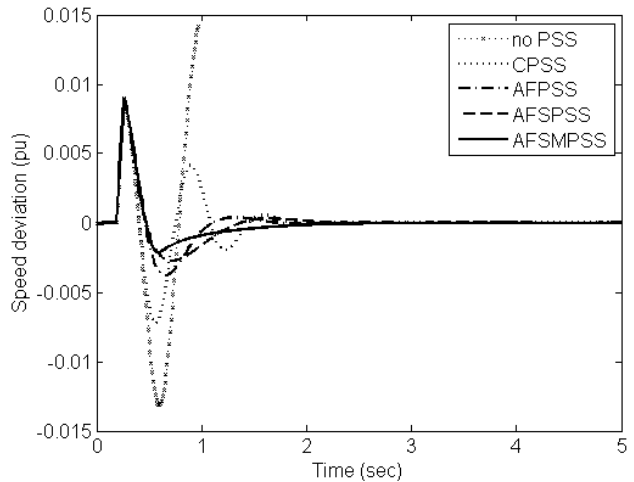


Figure 5. Response to a three-phase fault for the third case.

## VI. CONCLUSION

In this article, a new an indirect adaptive type-2 fuzzy sliding mode power system stabilizer based for design on the approximation of unknown nonlinear function of synchronous machine using the type-2 fuzzy logic system and enhanced by a PI term controller that eliminates chattering in the sliding mode control signal. Adaptation laws are developed based on the Lyapunov synthesis approach.

It's evident from nonlinear simulation studies that an adaptive type-2 fuzzy sliding mode power system stabilizer

shows better performance in a wide range of operating conditions, compared to adaptive type-2 fuzzy, adaptive type-2 fuzzy synergetic and conventional power system stabilizers counterpart by adding enough positive damping in the power system thus rapidly suppressing power flow hindering low frequency oscillations.

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