Distributed Automatic Load-Frequency Control with Optimality in Power Systems

Preprint

Xin Chen,1 Changhong Zhao,2 and Na Li1

1 Harvard University
2 National Renewable Energy Laboratory

Presented at the IEEE Conference on Control Technology and Applications
Copenhagen, Denmark
August 21–24, 2018

Suggested Citation

NREL is a national laboratory of the U.S. Department of Energy
Office of Energy Efficiency & Renewable Energy
Operated by the Alliance for Sustainable Energy, LLC

This report is available at no cost from the National Renewable Energy Laboratory (NREL) at www.nrel.gov/publications.

Conference Paper
NREL/CP-5D00-71123
September 2018

Contract No. DE-AC36-08GO28308
NOTICE

This work was authored in part by the National Renewable Energy Laboratory, operated by Alliance for Sustainable Energy, LLC, for the U.S. Department of Energy (DOE) under Contract No. DE-AC36-08GO28308. Funding provided by the U.S. Department of Energy Office of Energy Efficiency and Renewable Energy Solar Energy Technologies Office. The views expressed in the article do not necessarily represent the views of the DOE or the U.S. Government. The U.S. Government retains and the publisher, by accepting the article for publication, acknowledges that the U.S. Government retains a nonexclusive, paid-up, irrevocable, worldwide license to publish or reproduce the published form of this work, or allow others to do so, for U.S. Government purposes.

This report is available at no cost from the National Renewable Energy Laboratory (NREL) at www.nrel.gov/publications.


Cover Photos by Dennis Schroeder: (left to right) NREL 26173, NREL 18302, NREL 19758, NREL 29642, NREL 19795.

NREL prints on paper that contains recycled content.
Distributed Automatic Load-Frequency Control with Optimality in Power Systems

Xin Chen, Changhong Zhao, Na Li

Abstract—With increasing penetrations of renewable energy resources, power systems face new challenges in balancing supply and demand and maintaining nominal frequency. This paper studies load control to handle these challenges. In particular, a fully distributed automatic load control algorithm, which needs only local measurement and local communications, is proposed. We prove that the control algorithm globally converges to an optimal operating point that minimizes the total disutility of users, restores the nominal frequency and the scheduled tie-line power flows, and respects the thermal constraints of transmission lines. We also show that the convergence holds even when inaccurate system parameters are used in the control algorithm. Last, the effectiveness, optimality, and robustness of the proposed algorithm are demonstrated via numerical simulations.

I. INTRODUCTION

In power systems, generation and load are required to be balanced all the time. Once a mismatch between generation and load occurs, the system frequency will deviate from the nominal value, e.g., 50 Hz or 60 Hz, which may undermine the electric facilities and even cause a system to collapse. Hence, it is crucial to maintain the frequency close to its nominal value. Traditionally, the generator-side control [1] plays a dominant role in frequency regulation, wherein the generation is managed to follow the time-varying load; however, with the increasing integration of renewable energy, it becomes more challenging to maintain the power balance and the nominal frequency because of the increased volatility in non-dispatchable renewable generation such as wind and solar.

To address these challenges, load control has received considerable attention in the recent decade as a promising complement to generator control because controllable loads are ubiquitously distributed in power systems and can respond quickly to regulation signals or changes in frequency. Much research effort has focused on frequency regulation provided by controllable loads, including electric vehicles [3], [4]; heating, ventilating, and air-conditioning systems [5]; battery energy storage systems [6], [7]; and thermostatically controlled loads [8]. Several demonstration projects [9]–[11] verified the viability of load-side participation in frequency regulation. The literature above focuses on modeling and operating the loads for frequency regulation, and it leaves the development of system-wide optimal load control techniques as an unresolved task.

For load-side frequency control, centralized methods [12], [13] need to exchange information over remotely connected control areas, which imposes a heavy communications burden with expanded computational and capacity complexities [14]. This concern motivates a number of studies on distributed control methods. In [15]–[17], load control is implemented by solving a centralized optimization problem using appropriate decomposition methods. The decomposition methods generate optimal control schemes that respect the operational constraints, but their convergence relies on network parameters. In [18], a distributed proportional-integral load controller is designed to attenuate constant disturbances and improve the dynamic performance of the system, whereas operational constraints, such as load power limits and line thermal constraints, are not taken into account. Papers [19]–[21] reverse engineer power system dynamics as primal-dual algorithms to solve optimization problems for load control, and they prove global asymptotic stability of the closed-loop system independently of control parameters; however, the scheme in [19] requires the accurate information of power imbalance or a generator’s shaft angular acceleration, which is hard to obtain in practice. In addition, to implement the scheme in [19], each boundary bus needs to communicate with all the other boundary buses within the same control area, which brings a heavy remote communications burden if two boundary buses in the same area are far from each other.

In this paper, we develop an automatic load control (ALC) method for frequency regulation that can eliminate power imbalance, restore system frequency to the nominal value, and maintain scheduled tie-line power flows to minimize the total disutility of users for load adjustment. Power system frequency dynamics are interpreted as a primal-dual gradient algorithm that solves a properly formulated optimal load control problem, from which the load control algorithm is extracted. In particular, the proposed ALC method integrates four significant merits: 1) The information of aggregate power imbalance is not required in the control process.
II. SYSTEM MODEL AND PROBLEM FORMULATION

A. Dynamic Network Model

Consider a power network delineated by a graph \( G(\mathcal{N}, \mathcal{E}) \), where \( \mathcal{N} = \{1, \ldots, n\} \) denotes the set of buses, and \( \mathcal{E} \subset \mathcal{N} \times \mathcal{N} \) denotes the set of transmission lines connecting the buses. Suppose that \( G(\mathcal{N}, \mathcal{E}) \) is connected and directed, with arbitrary directions assigned to the transmission lines. Note that if \( ij \in \mathcal{E} \), then \( ji \notin \mathcal{E} \). The buses are divided into two types: generator buses and load buses, which are denoted, respectively, by the sets \( \mathcal{G} \) and \( \mathcal{L} \) with \( \mathcal{N} = \mathcal{G} \cup \mathcal{L} \). A generator bus is connected to both generators and loads, whereas a load bus is connected only to loads.

For notational simplicity, all the variables in this paper represent the deviations from their nominal values determined by the previous execution of economic dispatch. We consider the standard direct current (DC) power flow model in which the active power flow on line \( ij \), \( B_{ij} \), is a constant determined by the voltage magnitudes at buses \( i \) and \( j \) (which are assumed to be constant in the DC model) and the reactance of line \( ij \) (which is assumed to be purely inductive in the DC model), and \( \theta_i \) denotes the voltage phase angle at bus \( i \).

The dynamic model of the power network is:

\[
P_{ij} = B_{ij} (\theta_i - \theta_j) \quad \forall ij \in \mathcal{E} \tag{1}
\]

where \( P_{ij} \) is the active power flow on line \( ij \), \( B_{ij} \) is a constant determined by the voltage magnitudes at buses \( i \) and \( j \) (which are assumed to be constant in the DC model) and the reactance of line \( ij \) (which is assumed to be purely inductive in the DC model), and \( \theta_i \) denotes the voltage phase angle at bus \( i \).

The aggregate power of controllable load at bus \( i \) is denoted by \( d_i \), and the difference between the generator mechanical power and the uncontrollable load power at bus \( i \) is denoted by \( P_i^{\text{in}} \). For load buses \( i \in \mathcal{L} \), \( P_i^{\text{in}} \) represents the minus of the aggregate uncontrollable load power.

Equations (2a) and (2b) describe the frequency dynamics at the generator and load buses, respectively. Actually, they both indicate power balance at every time instant of the dynamics, as shown in Figure 1. The damping term \( D_i \omega_i = (D_i^g + D_i^l) \omega_i \) characterizes the total effect of the generator friction and frequency-sensitive loads, and \( P_i^{\text{in}} = P_i^g - P_i^l \) captures any change in net uncontrollable power injection. The line flow dynamics are delineated by (2c). The model (2) assumes that the frequency deviation \( \omega_i \) is small at every bus \( i \). See [21] for a justification of the model (2).

**Remark 1.** The simplified linear model (2) is for the purpose of algorithm design and stability analysis. The ALC algorithm that will be developed later can be applied to real power systems that have more complex dynamics. In Section IV, a high-fidelity power system simulator running a realistic dynamic model is used to test the ALC algorithm.

B. Optimal Load Control Problem

Consider the scenario when step changes occur in \( P^{\text{in}}_i = (P^{\text{in}}_i)_{i \in \mathcal{N}} \). The power imbalance and frequency deviations caused by these step changes will be eliminated through the adjustment of controllable loads \( d = (d_i)_{i \in \mathcal{N}} \). Our control goals are therefore threefold:

1) Restore the system frequency to its nominal value.
2) Rebalance the system power while making each control area absorb its own power change, so that the scheduled tie-line power transfers are maintained.
3) Modulate the controllable loads in an economically efficient way that minimizes the total disutility for adjusting all the loads while respecting the critical operational constraints, including load power limits and line thermal limits.

The second and third control goals can be formulated as the following optimal load control (OLC) problem:

\[
\text{Obj.} \quad \min_{d} \sum_{i \in \mathcal{N}} C_i (d_i) \tag{3a}
\]

s.t. \( d_i = P_i^{\text{in}} - \sum_{j:ij \in \mathcal{E}_i} B_{ij} (\theta_i - \theta_j) + \sum_{k:ki \in \mathcal{E}_i} B_{ki} (\theta_k - \theta_j) \quad \forall i \in \mathcal{N} \tag{3b}
\]
\[ d_i \leq d_i \leq \bar{d}_i \quad \forall i \in \mathcal{N} \]  
\[ P_{ij} \leq B_{ij} (\theta_i - \theta_j) \leq \bar{P}_{ij} \quad \forall i,j \in \mathcal{E} \]

where \( \mathcal{E}_{in} \) denotes the subset of lines that connect buses within the same control area. Constants \( \overline{d}_i \) and \( \underline{d}_i \) are the upper and lower load power limits at bus \( i \), respectively, and \( \overline{P}_{ij} \) and \( \underline{P}_{ij} \) specify the thermal limits of line \( ij \).

The function \( C_i(d_i) \) quantifies the cost, or disutility, for load adjustment \( d_i \). To facilitate the subsequent proof of convergence, we make the following assumption:

**Assumption 1.** The cost function \( C_i(\cdot) \) is strictly convex and continuously differentiable.

The objective (3a) is to minimize the total cost of load control. Equation (3b) guarantees that the power imbalance is eliminated within each control area; it can be shown by adding (3b) over the buses in the same area \( A \), which leads to \( \sum_{i \in A} d_i = \sum_{i \in A} P_i^{in} \). Equations (3c) and (3d) impose the load power constraints and the line thermal constraints, respectively. A load control scheme is considered to be optimal if it leads to a steady-state operating point, which is a solution to the OLC problem (3).

### III. Optimal Automatic Load Control

In this section, a fully distributed ALC scheme is developed for frequency regulation (see Algorithm 1). The basic approach of controller design is reverse engineering, i.e., to interpret the system dynamics as a primal-dual gradient algorithm to solve the OLC problem (3), which has been used in recent literature [19]–[21].

#### A. Reformulated Optimal Load Control Problem

To explicitly take into account the first control goal in Section II-B, i.e., frequency regulation, the OLC problem (3) is reformulated as follows:

\[ \text{Obj. } \min_{d, \omega, P, \psi} \sum_{i \in \mathcal{N}} C_i (d_i) + \sum_{i \in \mathcal{N}} \frac{1}{2} D_i w_i^2 \]

\[ \text{s.t. } d_i = P_i^{in} - D_i \omega_i - \sum_{j : i,j \in \mathcal{E}} P_{ij} + \sum_{k : k,i \in \mathcal{E}} P_{ki} \quad \forall i \in \mathcal{N} \]

\[ d_i \leq d_i \leq \overline{d}_i \quad \forall i \in \mathcal{N} \]

\[ d_i = P_i^{in} - \sum_{j : i,j \in \mathcal{E}_{in}} B_{ij} (\psi_i - \psi_j) + \sum_{k : k,i \in \mathcal{E}_{in}} B_{ki} (\psi_k - \psi_i) \quad \forall i \in \mathcal{N} \]

\[ P_{ij} \leq B_{ij} (\psi_i - \psi_j) \leq \bar{P}_{ij} \quad \forall i,j \in \mathcal{E} \]

where \( \psi_i \) is an auxiliary variable interpreted as the virtual phase angle of bus \( i \), and \( \psi_i = B_{ij} (\psi_i - \psi_j) \) is the virtual power flow on line \( ij \); see [19] where the concepts of virtual phase angle and virtual power flow are first proposed. The vectors \( \omega := (\omega_i)_{i \in \mathcal{N}}, \ d := (d_i)_{i \in \mathcal{N}}, \ P := (P_{ij})_{i,j \in \mathcal{E}}, \) and \( \psi := (\psi_i)_{i \in \mathcal{N}} \) are defined for notational simplicity.

In the reformulated problem (4), the virtual phase angles \( \psi \) and the constraints (4b) and (4d) are introduced so that the primal-dual algorithm of (4) is exactly the power network dynamics under proper control. The equivalence between problems (3) and (4) is established as follows.

**Lemma 1.** Let \( (\omega^*, d^*, P^*, \psi^*) \) be an optimal solution of problem (4). Then \( \omega_i^* = 0 \) for all \( i \in \mathcal{N}, \) and \( d^* \) is optimal for problem (3).

**Proof.** Let \( (\omega^*, d^*, P^*, \psi^*) \) be an optimal solution of (4), and assume that \( \omega_i^* \neq 0 \) for some \( i \in \mathcal{N} \). The optimal objective value of (4) is therefore:

\[ f^* = \sum_{i \in \mathcal{N}} C_i (d_i^*) + \sum_{i \in \mathcal{N}} \frac{1}{2} D_i (w_i^*)^2. \]

Then consider another solution \( \{\omega, d^*, P^*, \psi^*\} \) with \( \omega_i = 0 \) for \( i \in \mathcal{N}, \) \( P_{ij}^o = B_{ij} (\psi_i^* - \psi_j) \) for \( ij \in \mathcal{E}_{in}, \) and \( P_{ij}^o = 0 \) for \( ij \in \mathcal{E} \setminus \mathcal{E}_{in} \). Obviously, this solution is feasible for problem (4), and its corresponding objective value is:

\[ f^o = \sum_{i \in \mathcal{N}} C_i (d_i^*) < f^* \]

which contradicts the optimality of \( (\omega^*, d^*, P^*, \psi^*) \). Hence, \( \omega_i^* = 0 \) for all \( i \in \mathcal{N} \).

Next, note that the constraints (3b) and (4d) take the same form, and that when \( \omega = 0 \) and given \( (d, \psi) \), one can always find \( P \) that satisfies (4b) by taking \( P_{ij} = B_{ij} (\psi_i - \psi_j) \) for \( ij \in \mathcal{E}_{in} \) and \( P_{ij} = 0 \) for \( ij \in \mathcal{E} \setminus \mathcal{E}_{in} \). Therefore, the feasible set of (4) restricted to \( \omega = 0 \) and projected onto the \((d, \psi)\)-space is the same as the feasible set of (3) on the \((d, \theta)\)-space. As a result, for any \((\omega^*, d^*, P^*, \psi^*)\) that is an optimal solution of (4), \( d^* \) is also optimal for (3).

#### B. Automatic Load Control Algorithm

A partial primal-dual gradient method is applied to solve the reformulated OLC problem (4). This method can be exactly interpreted as the dynamics of a power network with load-frequency control. Based on this interpretation, an optimal ALC algorithm is derived.

The Lagrangian function of problem (4) is:

\[ L = \sum_{i \in \mathcal{N}} C_i (d_i) + \sum_{i \in \mathcal{N}} \frac{1}{2} D_i w_i^2 + \sum_{i \in \mathcal{N}} \lambda_i \left( -d_i + P_i^{in} - D_i \omega_i - \sum_{j : i,j \in \mathcal{E}} P_{ij} + \sum_{k : k,i \in \mathcal{E}} P_{ki} \right) \]

\[ + \sum_{i \in \mathcal{N}} \mu_i \left( -d_i + P_i^{in} - \sum_{j : i,j \in \mathcal{E}_{in}} B_{ij} (\psi_i - \psi_j) + \sum_{k : k,i \in \mathcal{E}_{in}} B_{ki} (\psi_k - \psi_i) \right) \]

\[ + \sum_{ij \in \mathcal{E}_{in}} \sigma_{ij}^+ (B_{ij} (\psi_i - \psi_j) - \bar{P}_{ij}) \]

\[ + \sum_{ij \in \mathcal{E}_{in}} \sigma_{ij}^- (B_{ij} (\psi_i - \psi_j) + \underline{P}_{ij}) \]

\[ + \sum_{i \in \mathcal{N}} \gamma_i^+ (d_i - \overline{d}_i) + \sum_{i \in \mathcal{N}} \gamma_i^- (-d_i + \underline{d}_i) \]

(5)
where $\lambda_i, \mu_i \in \mathbb{R}$ are the dual variables associated with the equality constraints (4b) and (4d), and $\gamma_i^+, \gamma_i^- \in \mathbb{R}_+$ are the dual variables associated with the inequality constraints $\epsilon_i$ and $\sigma_i$.

A primal-dual gradient method is given by the following two steps:

**Step 1:** Solve $\min_{\lambda_i} L$ and then $\max_{\lambda_i} L$, which leads to the following:

$$w_i = \lambda_i, \quad \forall i \in N$$

$$0 = d_i - P_i^{in} + D_i \lambda_i + \sum_{j : ij \in E} P_{ij} - \sum_{k : ki \in E} P_{ki}, \quad \forall i \in L$$

**Step 2:** The primal-dual gradient algorithm on the rest of the variables is:

$$\dot{\lambda}_i = \epsilon_{\lambda_i} \left( -d_i + P_i^{in} - D_i \lambda_i - \sum_{j : ij \in E} P_{ij} + \sum_{k : ki \in E} P_{ki} \right)$$

$$\dot{P}_{ij} = \epsilon_{P_{ij}} (\lambda_i - \lambda_j)$$

$$\dot{d}_i = \epsilon_d \left( -C_i (d_i) + \lambda_i + \mu_i - \gamma_i^+ + \gamma_i^- \right)$$

$$\dot{\psi}_i = \epsilon_{\psi_i} \left( \sum_{j : ij \in E_i} (\mu_j - \mu_i - \sigma_{ij}^+ + \sigma_{ij}^-) B_{ij} \right)$$

$$\dot{\gamma}_i^+ = \epsilon_{\gamma_i^+} \left[ d_i - \bar{d}_i \right]_{\gamma_i^+}$$

$$\dot{\gamma}_i^- = \epsilon_{\gamma_i^-} \left[ -d_i + \bar{d}_i \right]_{\gamma_i^-}$$

$$\dot{\mu}_i = \epsilon_{\mu_i} \left( -d_i + P_i^{in} - \sum_{j : ij \in E} B_{ij} (\psi_j - \psi_i) \right)$$

$$\dot{\sigma}_{ij}^+ = \epsilon_{\sigma_{ij}^+} \left[ B_{ij} (\psi_j - \psi_i) - P_{ij} \sigma_{ij}^+ \right]$$

$$\dot{\sigma}_{ij}^- = \epsilon_{\sigma_{ij}^-} \left[ -B_{ij} (\psi_j - \psi_i) + P_{ij} \sigma_{ij}^- \right]$$

where (7a) is for $i \in G$, (7b) is for $ij \in E$, (7c)-(7g) are for $i \in N$, and (7h)-(7i) are for $ij \in E_i$.

Let $\epsilon_{\lambda_i} = 1/M_i$ and $\epsilon_{P_{ij}} = B_{ij}$. Then the partial primal-dual gradient algorithm (6)-(7) can be equivalently written as the ALC algorithm (8) together with the network dynamics (2). In (8b), $\mu_i$ is the abbreviation of the expression $\mu_i = \frac{\epsilon_{\lambda_i} + \epsilon_{\mu_i}}{\epsilon_{\lambda_i}} - \gamma_i^+ + \gamma_i^-$. The notations containing $\epsilon$ represent arbitrarily selected positive constant step sizes. The operator $\lceil x \rceil_y$ means positive projection [24], which equals $x$ if either $x > 0$ or $y > 0$, and 0 otherwise; it ensures $\sigma_{ij}^+, \sigma_{ij}^-, \gamma_i^+, \gamma_i^- \geq 0$.

Because the instant change $P_i^{in}$ of the uncontrollable power injection is usually unknown in practice, a new variable, $r_i$, is introduced to substitute $\mu_i$:

$$r_i = K_i \frac{\epsilon_{\mu_i}}{\epsilon_{\lambda_i}} - \frac{K_i}{\epsilon_{\lambda_i}} \lambda_i$$

where $K_i$ is a positive constant. In this way, the necessity to know $P_i^{in}$ is circumvented.

---

### Algorithm 1: Automatic Load Control

$$\dot{d}_i = \epsilon_d \left( -C_i (d_i) + \frac{\epsilon_{\lambda_i} + \epsilon_{\mu_i}}{\epsilon_{\lambda_i}} \omega_i + \frac{\epsilon_{\mu_i}}{K_i} r_i - \gamma_i^+ + \gamma_i^- \right)$$

$$\dot{\psi}_i = \epsilon_{\psi_i} \left( \sum_{j : ij \in E_i} (\mu_j - \mu_i - \sigma_{ij}^+ + \sigma_{ij}^-) B_{ij} \right)$$

$$\dot{\gamma}_i^+ = \epsilon_{\gamma_i^+} \left[ d_i - \bar{d}_i \right]_{\gamma_i^+}$$

$$\dot{\gamma}_i^- = \epsilon_{\gamma_i^-} \left[ -d_i + \bar{d}_i \right]_{\gamma_i^-}$$

$$\dot{\mu}_i = \epsilon_{\mu_i} \left( -d_i + \sum_{j : ij \in E} B_{ij} (\psi_j - \psi_i) \right)$$

$$\dot{\sigma}_{ij}^+ = \epsilon_{\sigma_{ij}^+} \left[ B_{ij} (\psi_j - \psi_i) - P_{ij} \sigma_{ij}^+ \right]$$

$$\dot{\sigma}_{ij}^- = \epsilon_{\sigma_{ij}^-} \left[ -B_{ij} (\psi_j - \psi_i) + P_{ij} \sigma_{ij}^- \right]$$

The implementation of algorithm (8) is illustrated in Figure 2. In the physical (lower) layer, each bus $i$ measures its own frequency deviation $\omega_i$ and the power flows $(P_{ki}, P_{ij})$ on its adjacent lines. In the cyber (upper) layer, each bus $i$ exchanges the information $(\mu_i, \psi_i)$ with its neighboring buses. Then following algorithm (8), each bus $i$ updates the...
variables $\psi_i, \gamma_i, \sigma_i, r_i$ and computes its load adjustment $d_i$. Next, the control command $d_i$ is sent back to the physical layer and executed by the load modulation device. Afterward, the system frequency and power flows respond to the physical law (2). In this manner, the combination of network dynamics (2) and the proposed control algorithm (8) forms a closed loop. In addition, because only local measurement and local communications are required in this process, the proposed ALC algorithm is performed in a fully distributed manner.

Further, the proposed algorithm (8) will converge to a steady-state operating point that is optimal in the sense that it solves the reformulated OLC problem (4). This claim is restated formally as the following theorem.

**Theorem 1.** The proposed ALC algorithm (8) together with the network dynamics (2) asymptotically converges to a point $(\hat{d}^*, \omega^*, P^*, \psi^*, r^*, \sigma^*)$, where $(\hat{d}^*, \omega^*, P^*, \psi^*)$ is an optimal solution of problem (4).

A challenge in implementing (8e) is that the damping coefficient $D_i$ is in general hard to know exactly. It is shown below that the proposed control (8) is robust to inaccuracy in $D_i$ in the sense that the closed-loop system still converges to an optimal solution of (4) if the inaccuracy in $D_i$ is small enough and some additional conditions are met.

**Theorem 2.** Assume that the following conditions are met:

i) For $i \in N$, the cost function $C_i(d_i)$ is $\alpha$-strongly convex and second-order continuously differentiable, i.e., $C_i \in C^2$ with $C_i''(d_i) \geq \alpha > 0$, in the interior of its domain $(\bar{d}_i, \overline{d}_i)$, and $C_i(d_i) \to +\infty$ as $d_i \to \overline{d}_i$ or $\overline{d}_i \leftarrow d_i$.

ii) For $i \in N$, the function $C_i'$ is Lipschitz continuous with Lipschitz constant $L > 0$.

iii) Infinitely large step sizes $\epsilon_d$ are used for (8a), which is then reduced to the following algebraic equation:

$$-C_i'(d_i) + \frac{\epsilon_{\lambda_i} + \epsilon_{\mu_i}}{\epsilon_{\lambda_i}} \omega_i + \frac{\epsilon_{\mu_i}}{K_i} r_i - \gamma_i^+ + \gamma_i^- = 0.$$ 

iv) An inaccurate $\hat{D}_i = D_i + \delta a_i$ is used instead of $D_i$ in (8e), and the inaccuracy $\delta a_i$ satisfies:

$$\delta a_i \leq 2 \left( \frac{\epsilon}{L} - \sqrt{\frac{d_i^2 + d_i^* D_{\min}}{d_i^2 + d_i^* D_{\min}}} \right),$$

where $\epsilon := 1/L$ and $D_{\min} := \min_{i \in N} D_i$.

Then the closed-loop system (2), (8) converges to a point $(\hat{d}^*, \omega^*, P^*, \psi^*, r^*, \sigma^*)$, where $(\hat{d}^*, \omega^*, P^*, \psi^*)$ is an optimal solution of problem (4).

Because of the space limit, the proofs of Theorems 1 and 2 are provided in the longer version of this paper [25].

**Remark 2.** The conditions imposed in Theorem 2 are mostly for the purpose of theoretical analysis. That means these conditions are conservative. As shown in the following case studies, the proposed load control algorithm is effective even when the inaccuracy in $D_i$ is large.

**IV. Case Studies**

The effectiveness and robustness of the proposed ALC algorithm is demonstrated in numerical simulations. In particular, the performance of the ALC under step and continuous power changes is tested, and the cases with inaccurate damping coefficients are demonstrated. The impact of noise in measurements is also studied numerically.

**A. Simulation Setup**

The 39-bus New England power network in Figure 3 is tested. The simulations are run on Power System Toolbox (PST) [26]. Compared to the analytic model (2), the PST simulation model is more complicated and realistic, which involves the classic two-axis subtransient generator model, the IEEE Type DC1 excitation system model, the alternating current (AC) power flow model, and different types of load models. Detailed configuration and parameters of the simulation model are available online [27].

Ten generators located at Bus 30 to Bus 39. To simulate continuous changes in power supply, four photovoltaic (PV) units are added to Bus 1, Bus 6, Bus 9, and Bus 16. Bus 1 to Bus 29 are load buses with a total active power load of 6.2 GW. Every load bus has an aggregate controllable load, and the disutility function for load control is:

$$C_i (d_i) = c_i \cdot d_i^2$$

where the cost coefficients $c_i$ are set to 1 per unit (p.u.) for Bus 1 to Bus 5, and they are set to 5 p.u. for other load buses. The adjustable load limits are set as $\overline{d}_i = -d_i = 0.4$ p.u., with the base power being 100 MVA. In addition, the loads are controlled every 250 ms, which is a realistic estimate of the time-resolution for load control [28]. The damping coefficient $D_i$ of each bus is set to 1 p.u. In the proposed controller, the step sizes $\epsilon$ and the constants $K_i$ are all set to 0.5 p.u.
B. Step Power Change

At time $t = 1$ s, step increases of 1 p.u. in load occur at Bus 1, Bus 6, Bus 9, and Bus 16. With or without ALC, the system frequency is illustrated in Figure 4. It can be observed that the power network is not capable of bringing the frequency back to the nominal value without ALC. In contrast, the proposed ALC mechanism can restore the system frequency to the nominal value. Figures 5 and 6 present the load adjustments and the total cost of load control under ALC, respectively. It is observed that loads with lower cost coefficients $c_i$ tend to make larger adjustments bounded by their upper limits. This phenomenon indicates that the load adjustments are calculated for system-wide efficiency although the calculations are performed in a distributed way. As a result, the total cost of ALC converges to the minimum of the OLC problem (3) or (4) in the steady state.

C. Continuous Power Change

We next study the performance of ALC under continuous power changes. To this end, the PV generation profile of a real power system located within the territory of Southern California Edison is used as the power supply of each of the four PV units. The original 6-second data of PV outputs are linearly interpolated to generate power outputs every 0.01 second, which is consistent with the resolution of the PST dynamic simulation. The PV power outputs during 10 minutes are shown in Figure 7.

Figures 8 and 9 illustrate the dynamics of system frequency and voltage magnitudes, respectively. It can be observed that ALC can effectively maintain the nominal frequency under time-varying power imbalance. With real-time frequency deviation and power mismatch used in the control process, ALC can respond promptly to the lasting power fluctuations. Also, from Figure 9, it is observed that the rise in voltage caused by PV generation is alleviated by ALC. The reason is that the power imbalance is absorbed by ubiquitously distributed loads to mitigate the effect of

![Fig. 4. The frequency dynamics under step power changes.](image)

![Fig. 5. The load adjustments under ALC.](image)

![Fig. 6. The trajectory of the total cost of ALC.](image)

![Fig. 7. The PV power outputs.](image)

![Fig. 8. The frequency dynamics under continuous power changes.](image)
power oversupply on voltage. In summary, the ALC scheme not only maintains system frequency but also improves the dynamics of voltage magnitudes.

D. Impact of Inaccurate Damping Coefficients

This part is devoted to understanding the impact of inaccurate damping coefficients on the performance of ALC. Let the damping coefficient $\tilde{D}_i$ used by the controller have the following relationship with the accurate $D_i$:

$$\tilde{D}_i = k \cdot D_i$$

where $k$ is a uniform scaling factor for all the buses $i \in \mathcal{N}$. The factor $k$ is tuned to test the performance of ALC under step power changes. Figure 10 compares the frequency dynamics under ALC with different $k$.

As shown in Figure 10, the convergence of the system frequency becomes slower when smaller damping coefficients are used. As the used damping coefficients approach zero, the frequency can be stabilized but cannot be restored to the nominal value. This observation can be explained as follows. When $D_i = 0$, problem (4) imposes no restriction on the system frequency. As a result, only the power imbalance is eliminated, but the frequency cannot be restored. In contrast, when larger damping coefficients are used, the convergence of the frequency dynamics becomes faster at the cost of increased oscillations. As the damping coefficients increase to 30 times the actual values, the system frequency becomes unstable. In summary, ALC works well under moderate inaccuracies in the damping coefficients $D_i$.

E. Impact of Measurement Noise

We now study how the noise in local measurement affects the performance of ALC. Recall that the implementation of ALC relies on local measurements of frequency deviation $\omega_i$ and adjacent power flows $(P_{ki}, P_{ij})$ at every bus $i \in \mathcal{N}$.

First, consider the noise $\xi_{\omega_i}$ in the measurement of $\omega_i$, which is assumed to follow the Gaussian distribution, i.e., $\xi_{\omega_i} \sim \mathcal{N}(0, \sigma_{\omega_i}^2)$. The measured frequency deviation is thus $\tilde{\omega}_i = \omega_i + \xi_{\omega_i}$. The standard deviation $\sigma_{\omega_i}$ is tuned to test the performance of ALC under step power changes. In the simulations, the noise $\xi_{\omega_i}$ is generated independently over time and across buses, with the Gaussian distribution truncated within the $\pm 3\sigma$ interval to avoid the tail effect. The resultant frequency dynamics are shown in Figure 11.

Next, we inject noise $\xi_{P_{ij}}$ into the measurement of power flow, which also follows the Gaussian distribution, i.e., $\xi_{P_{ij}} \sim \mathcal{N}(0, \sigma_{P_{ij}}^2)$, The frequency dynamics under different levels of such noise are shown in Figure 12.

Figures 11 and 12 show that the system frequency can be restored to the nominal value under measurement noise.
Moreover, the frequency presents oscillations that increase with the level of noise.

V. CONCLUSION

Based on the reverse engineering approach, we developed a fully distributed ALC mechanism for frequency regulation in power systems. The combination of ALC and power network dynamics was interpreted as a partial primal-dual gradient algorithm to solve an optimal load control problem. As a result, relying purely on local measurement and local communications, ALC can eliminate power imbalance and restore the nominal frequency with minimum total cost of load adjustment, while respecting operational constraints such as load power limits and line thermal limits. Numerical simulations of the 39-bus New England system showed that ALC can maintain system frequency under step or continuous power changes, and it is robust to inaccuracy in damping coefficients as well as measurement noises.

REFERENCES


Fig. 12. The frequency dynamics with noise in power flow measurement.