Contents

About the editor xv
Preface xvii
Acknowledgments xxix
Abbreviations and terminologies xxxi

1 Electrical safety 1
Benjamin Moosburger, Christian Vögerl, Tilo Püschel and Jörg Irzinger
1.1 Electrical safety 1
1.1.1 Lightning and surge protection for wind turbines 1
1.2 The electrical installation as protection against electrical hazards 21
1.2.1 General types of power supply systems 23
1.2.2 Residual-current monitoring (RCM) 26
1.2.3 Insulation monitoring (IMD – insulation monitoring device) 28
1.2.4 Protection of the power-supply system and the wind turbine 30
1.3 Conclusion 33
References 34

2 Generator design for geared turbines 37
Henri Arnold
2.1 Introduction and basics 37
2.1.1 Short history of electrical machines 37
2.1.2 Introduction to geared concepts 39
2.1.3 Why do we need speed variability? 40
2.1.4 The advantage of mid and high-speed generator concepts 42
2.1.5 Dimensioning and law of growth 43
2.1.6 Stator connection 45
2.1.7 Rotating magnetic fields 48
2.1.8 Complex phasors for time harmonic signals 49
2.1.9 Complex space vectors (CSV) 51
2.2 Induction generator (IG) 53
2.2.1 Basics 53
2.2.2 Grid connected IG in stationary operation (DOL) 57
2.2.3 Speed variable IG in stationary operation using VFD 65
2.2.4 Dynamic operation 72
2.3 Double-fed induction generator (DFIG) 76
2.3.1 Basics 76

2.3.2 DFIG in stationary operation 78
2.3.3 Dynamic operation 84
2.4 Salient pole synchronous generator (SPSG) 85
2.4.1 Basics 85
2.4.2 SPSG in stationary operation 88
2.4.3 Dynamic operation 92
2.5 Permanent magnet synchronous generator (PMSG) 96
2.5.1 Basics 96
2.5.2 PMSG in stationary operation 99
2.5.3 Dynamic operation 101
References 104

3 Generator design for direct-drive turbines 107
Tobias Muik and Stephan Jöckel
3.1 Introduction 107
3.2 Basic aspects for designing direct-drive generators for wind turbines 108
3.2.1 Basic design requirements 108
3.2.2 Major aspects for minimizing the levelized cost of energy (LCoE) 113
3.2.3 Other important aspects for designing direct-drive generators 124
3.3 Scaling laws of direct-drive generators 134
3.3.1 Basic assumptions for scaling 135
3.3.2 Scaled results for generator diameter 135
3.3.3 Scaled results for generator losses and efficiency 135
3.3.4 Scaled results for generator masses 137
3.3.5 Conclusions from the scaling exercise: segmentation as the future of the direct drive? 141
3.4 Stator winding topologies for direct-drive generators 142
3.4.1 Definition of symmetrical m_s-phase stator windings 142
3.4.2 Definition of the winding factor and current layer of a stator winding 148
3.4.3 Stator windings topologies with particular reference to low-speed permanent magnet synchronous generators 149
3.4.4 Conclusion 159
3.5 Permanent magnet rotor topologies for direct drive generators 159
3.5.1 Boundary conditions 160
3.5.2 The spoke magnet rotor 161
3.5.3 Surface-mounted magnets 162
3.5.4 Simple interior magnets 163
3.5.5 V-shape interior magnets 165
3.5.6 Modified air gap dimension for V-shape magnets 166
3.5.7 Comparison of the results 167

3.6 Optimization strategies on V-shape magnets 170
3.6.1 Deriving an appropriate solution with interior V-shape magnets 171
3.6.2 Combining a continuous rotor iron yoke with concentrated stator windings 176
3.7 Summary 180
3.8 Outlook 180
3.8.1 Evolution of gearboxes and medium-speed concepts 180
3.8.2 Raw materials 181
3.8.3 Alternatives to permanent-magnet excitation – conventional direct-current excitation? 182
3.8.4 Alternatives to permanent-magnet excitation – high-temperature super-conductivity (HTS)? 182
References 185

4 Main converter design 187
Holger Groke and Norbert Hennchen
4.1 Brief historical background 187
4.2 Electrical drive train 189
4.2.1 General assembly 190
4.2.2 Generator 190
4.2.3 Main converter 192
4.2.4 Filter components 208
4.2.5 Active- and reactive-power feeding 210
4.2.6 Relevant standards 214
4.2.7 Transformer and switchgear 215
4.3 Design example 216
4.4 Future trends and developments 225
References 226

5 Grid compliance and electrical system characterization 229
Torben Jersch
5.1 State-of-the-art grid compliance 229
5.2 Scope of grid code compliance testing 230
5.2.1 Power quality 230
5.2.2 Steady state operation 230
5.2.3 Capability 231
5.2.4 Active power control behavior 231
5.2.5 Power of the active power control with frequency increase 231
5.2.6 Behavior in the event of grid faults 232
5.2.7 Disconnection from grid 232
5.3 Methods for compliance testing – field test 232
5.3.1 Field test – detailed view of the FRT tests 232
5.3.2 Classification of the field tests to the overall development of the WT 233

5.4 Test benches for grid compliance testing 234
5.4.1 Emulate realistic conditions on test benches 234
5.4.2 Design basics of DyNaLab drive unit 235
5.4.3 Electrical design 235
5.4.4 Evaluation of the DyNaLab tests 237
5.5 Methods for compliance testing – HiL-GridCoP 238
5.5.1 Drivetrain design of Hil-GridCoP test bench 238
5.5.2 Electrical design and impedance emulation 240
5.5.3 Superposition by the current of the turbine 240
5.5.4 Conclusion 243
5.5.5 Resume 244
5.6 Where is grid compliance testing heading? 244
5.7 Testing on lower V-levels to reduce costs 245
5.8 Harmonic measurement methods 246
5.9 Grid emulators – technology limits for high frequencies 247
5.10 Harmonic measurement on test benches – PQ4Wind test bench 248
5.10.1 Control the impedances of the test bench 250
5.11 New requirements for wind farm models 250
5.12 EMT model requirements 251
5.13 Component-based units certification 252
5.14 Outlook 254
References 254

6 X-Hardware-in-the-loop test methods for validation 257
Adam Zuga, Mohsen Neshati, Florian Hans, Nils Johannsen and Oliver Feindt
6.1 Introduction 257
6.2 Mechanical hardware-in-the-loop (MHIL) 265
6.3 Power hardware-in-the-loop (PHIL) 279
6.3.1 Basic structure of a PHIL simulation 279
6.3.2 Stability and accuracy of PHIL-systems 285
6.3.3 Practical aspects of PHIL testing 288
6.4 Controller hardware-in-the-loop (CHIL) 289
6.4.1 Test concepts 290
6.4.2 Software simulation 291
6.4.3 Hardwired simulation 294
6.4.4 Fieldbus simulation 296
6.4.5 Combined simulation 297
6.4.6 Farm simulation 298
6.5 Outlook and future developments 300
References 303

7 Wind turbine control and automation 309
Nils Johannsen
7.1 Introduction 310
7.2 Design process 313
7.3 Industrial control systems 316
7.3.1 Industrial PCs 317

7.3.2 I/O modules 319
7.3.3 Fieldbus 321
7.4 Safety system 325
7.5 Control cabinets 328
7.6 Software application 332
7.6.1 Basic functions 333
7.6.2 Supervisory control 339
7.6.3 Operational control 346
7.7 Subsystem control 354
7.7.1 Control cabinets 355
7.7.2 Hydraulic and cooling systems 356
7.7.3 Tower, nacelle, and hub 357
7.7.4 Pitch and rotor 358
7.7.5 Gearbox, generator, and shafts 359
7.7.6 Converter, transformer, and switchgear 361
7.7.7 Yaw system 362
7.7.8 Meteorology 363
7.7.9 Monitoring and protection systems 364
7.8 Monitoring and maintenance 365
7.8.1 Remote access 366
7.8.2 Data recording 366
7.8.3 Farm communication 368
7.8.4 Remote communication 369
7.8.5 Predictive maintenance 371
7.8.6 Computer security 372
7.9 Conclusions and outlook 374
References 376

8 Structural health monitoring 381
Carles Colomer Segura, Carsten Ebert and Peter Kraemer
8.1 Motivation 381
8.1.1 Goals of structural health monitoring 381
8.1.2 What is the difference between condition monitoring and structural health monitoring? 382
8.1.3 Relevant standards and guidelines 384
8.2 Methods and monitoring principles 385
8.3 Types and goals of monitoring 388
8.3.1 Rotor blades and pitch bearings 388
8.3.2 Drivetrain and nacelle 392
8.3.3 Tower and foundation 392
8.3.4 Additional considerations for offshore foundations 395
8.4 Requirements to common monitoring sensors 399
8.4.1 Acceleration sensors 399
8.4.2 Inclination sensors 400
8.4.3 Strain sensors 400
8.5 Practical considerations for implementing SHM – example for monitoring of offshore foundations 401
8.5.1 Definition of valuable KPIs 403

8.5.2 Comparing monitoring results to design 404
8.6 The lifecycle of an SHM solution 405
8.6.1 Formal requirements for monitoring solution providers 407
References 408

9 Advanced concepts for control of wind turbine and wind farm systems 411
Tobias Meyer and Niklas Requate
9.1 Ecological impact of wind energy 412
9.2 Potential for reduced CO_2eq. emissions from wind farms 414
9.2.1 Reducing CO_2eq.: decrease the material effort of a turbine 415
9.2.2 Improving kWh: increase the lifetime-energy production 416
9.3 System-wide control for an entire wind farm 420
9.3.1 Structuring the multiple levels of control 421
9.3.2 Turbine control as actuator for higher-level wind farm system control 421
9.3.3 Value optimization 423
9.4 Optimal operational planning as input for wind farm flow control and turbine control 424
9.4.1 Optimization 426
9.4.2 Surrogate model setup 427
9.4.3 Classification of operation-influencing conditions 429
9.4.4 Scheduling for long time horizon 429
9.4.5 Continuous update of operational planning 433
9.4.6 Short-term adaptation and override of planning 434
9.5 Evaluating the technical and economic benefit of advanced control concepts 435
References 437

10 Integration of local energy systems 443
Christoph Kaufmann, Carlos Cateriano Yáñez, Aline Luxa, Marina Nascimento Souza and Georg Pangalos
10.1 Introduction 443
10.2 Low-inertia systems and future requirements for the integration of wind turbines 444
10.3 Definition of local energy systems 447
10.4 Design of local energy systems by optimal sizing 452
10.5 Control of local energy systems 461
10.5.1 System level control of local energy systems 461
10.5.2 Component level control of LES 465
10.6 Stability of local energy systems 471
10.6.1 Characteristics of LES 471
10.6.2 Stability of LES 472
10.6.3 Stability analysis methods 475
10.7 Outlook 478
References 478

Index 485