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# Coordinated Secondary Control for Balanced Discharge Rate of Energy Storage System in Islanded Microgrids

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**Abstract**— A coordinated secondary control based on a novel autonomous currents sharing control strategy for balanced discharge rate of energy storage systems in islanded microgrid (MG) is proposed in this paper. The coordinated secondary controller is able to regulate the output power of distributed generating (DG) systems according to their state-of-charge by adjusting the virtual resistances of their voltage controlled inverters. This controller can not only provide the faster response and accurate output current sharing control, but also avoid the potential operation failure resulting from the over current and unintentional outage of DGs. Thus, the stability and reliability of islanded MG can be improved. The eigenvalues and root locus with the proposed controller are presented to design the parameters as well as analyzing the system stability. Simulation results based on Matlab/simulink are presented in order to verify the effectiveness of the proposed controller.

**Index Terms**—Coordinated secondary control, energy storage system, balanced discharge rate, microgrid

## I. INTRODUCTION

NOWADAYS, the environmental issues, uncertainty of the prices for fossil fuels, concerns about the security of supply and the liberalization of the electricity markets result in a great change of the power system, the small scaled distributed generators is more promising comparing to traditional central power plant [1]. Microgrid (MG) has been proposed for several years as its capability of integrating different types of renewable energy sources [2].

Hierarchical control for MG has been proposed in order to standardize their operation and functionalities. The various functionalities such as voltage and frequency restoring, load sharing, resynchronization with the main grid, as well as the power flow exchanged between MG and the utility grid are classified and defined into three levels [3]. Moreover, more advanced and comprehensive functions for MGs can be achieved by combining the communication technology with the hierarchical control theory. A novel secondary control is proposed in [4] for improving the reactive power sharing performance among voltage controlled inverters (VCI) and restoring the frequency and amplitude deviations. A harmonic suppression control strategy based on secondary control for MG is proposed in [5]. A compensation control strategy based on secondary control scheme for unbalanced voltage of the point of common coupling

(PCC) is represented in [6].

The MG defined by the Consortium for Electric Reliability Technology Solutions (CERTS) should able to supply the sensitive local load without the supporting of utility grid [7]. Therefore, the energy storage system (ESS) of MG should be charged either by the utility grid or the renewable energy sources in MG. Besides, the ESS should be discharged for peak shaving or supporting the local loads during the grid failure and electrical shortage to enhance the system stability and reliability [8]. However, there is a tradeoff between costs and the system reliability since the ESS is usually one of the most expensive components in practice [9]. A particle swarms optimization (PSO) based optimal capacity planning algorithm for ESS to reduce contract capacity of MG is proposed in [10].

Another issue is the sustainability of the islanded MG, which is dominantly decided by the balanced power exchange among distributed generation systems (DGs), ESSs and loads. Some previous works indicate that control capability of the ESS is limited by energy capacity of the storage device. If there are only the ESSs are involved in stabilizing and reliability of the MG, it may result in operation failure. Because the available electrical energy from ESS is affected by charging conditions, the ambient temperature, the charging and discharging current, as well as the ageing problem [11], [12]. The conventional power sharing control strategies mainly focus on the equal power sharing among different DG units. However, in fact, the ESSs in different DGs will have different discharge rate according to their state-of-charge (SoC). The powerless DG will be shut down when its SoC is below the threshold, while the rest of DGs have to supply more power for the local loads. This situation probably cause over current and outage, furthermore, degrading the stability and reliability of the MG due to the cask effect. To avoid this operation failure, the output power of the DG units should be coordinated in terms of their SoC. Some coordinated controllers are proposed for AC and DC MG [13]-[17]. For example, an ESS frequency bus-signaling of based autonomous active power control strategy is proposed in [13] for ac-islanded microgrids in order to achieve power management in a decentralized manner. However, these proposed controllers are all based on the droop control which has the relative slow transient response due to the low pass filter.

Therefore, a novel coordinated secondary control for balanced discharge rate of ESS in islanded MG is proposed in this paper. An autonomous current-sharing controller is employed in primary control to ensure the rapid and accurate loads sharing performance for the paralleled VCIs. The coordinated secondary controller is able to regulate the output power of DGs according to their SoC by adjusting the virtual resistances of the VCIs. This controller can not only provide the faster response and accurate output current sharing control, but also avoid the potential operation failure resulting from the over current and unintentional outage of DGs. Thus, the stability and reliability of islanded MG can be improved. The eigenvalues and root locus with the proposed controller are presented to design the parameters as well as analyzing the system stability. Simulation results based on Matlab/simulink are presented in order to verify the effectiveness of the proposed controller.

## II. THE ISLANDED MICROGRID

### A. The islanded microgrid

The configuration of an island MG is shown in Fig. 1. In daylight, the ESSs can operate in either charging or discharging mode according to the output power of PV panels and the consumption. The main function of ESS during the day is to balance the power between the renewable energy sources and local loads. While in the night, the ESSs will become the grid forming unit to maintain the common bus voltage and frequency, supply the local loads and fulfill the peak shaving functionality due to the lack of solar energy. In this situation, only the ESSs are involved in stabilizing and reliability of the islanded MG. In order to avoid the potential operation failure of MG and DGs discussed above, the output power of the DG units should be coordinated to share the load in terms of their SoC.

### B. The characteristic of ESS

The valve-regulated lead acid (VRLA) battery is considered for ESS in this paper, since it can prove high number of charge-discharge cycles, low price, deep discharges and its practical use.

One of the most important issues of VRLA battery is the contradiction between the depth of discharge (DOD) and life-cycle as shown in Fig. 2. It can be seen that the DOD of VRLA battery decreases exponentially with the increasing of life-cycle. Therefore, SoC is usually limited to prevention of over discharge in practice. However, as the nonlinear characteristic and the unmeasurable of SoC, some complex models and advanced algorithms are developed for the accurate SoC prediction [18]-[19].

Another issue is the relationship of the rated capacity and the discharge current of VRLA battery as depicted in Fig. 3. It can be seen that the capacity of battery declines exponentially with the increasing of the discharge current. This phenomenon means that the total available electrical energy in VRLA battery may change according to the discharge condition even the batteries have the same initial SoC. Therefore, the ESS with smaller discharge current and balancing discharge rate may

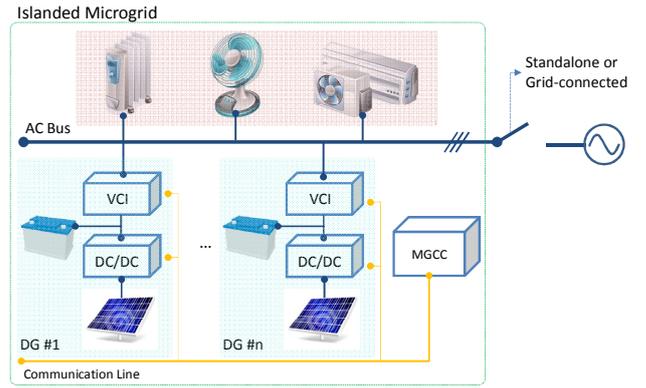


Fig. 1. The diagram of the islanded MG.

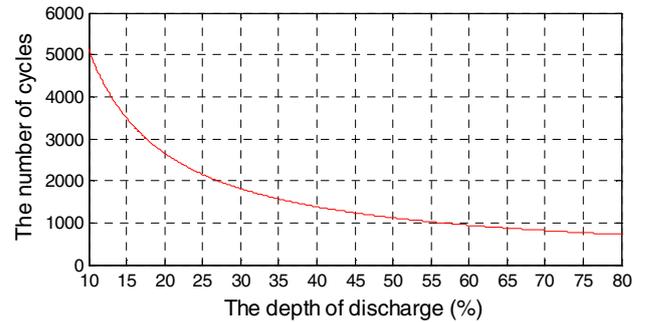


Fig. 2. The relationship between DOD and life cycles.

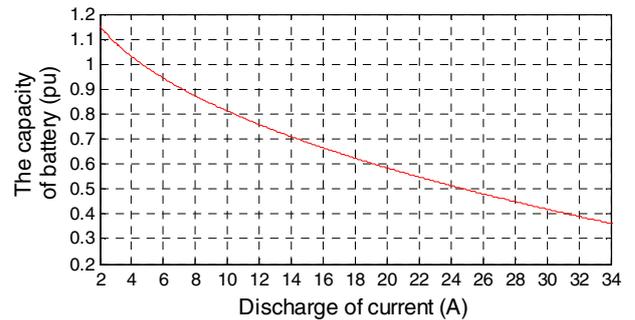


Fig. 3. The relationship between discharge current and the rated capacity.

output more power compared to the equal power sharing control based system.

### C. The power sharing control of inverter

The autonomous current-sharing control strategy employed in primary control of this paper is depicted in Fig. 4. The controller consists of a virtual resistance loop ( $R_{vir}$ ), a synchronous reference frame-based phase locked loop (SRF-PLL), a DC link voltage feed-forward loop, and the conventional P+R inner current and voltage loops ( $G_i$  and  $G_v$ ) that generates a PWM signal to drive the IGBTs of the inverter. The current and voltage of inductor and capacitor are sampled and transformed to the stationary reference frame respectively.

The voltage reference  $v_o^*$  is generated by combining the amplitude reference ( $|v_o^*|$ ) and the phase ( $\theta$ ) generated by a SRF-PLL. The SRF-PLL synchronizes all the inverters to the same frequency ( $\omega^*$ ). Even though

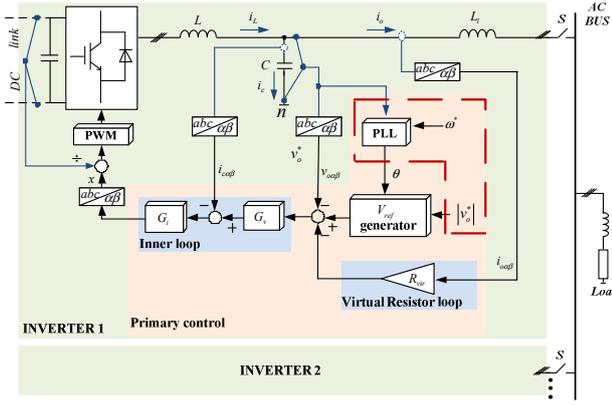


Fig. 4. The autonomous current-sharing control strategy.

the SRF-PLL is trying to synchronize the inverter with the common AC bus when supplying reactive loads, the current flowing through the virtual resistance will create unavoidable voltage drop that will cause the rising of frequency of the SRF-PLL. This inherent mechanism endows a droop characteristic in each inverter instead of adopting droop control loop. Therefore, the relationship between  $I_{o\alpha}$ ,  $I_{o\beta}$  and  $R_{vir}$  can be generalized and expressed for a number  $N$  of converters as:

$$\begin{aligned} I_{o\alpha 1} R_{vir1} &= I_{o\alpha 2} R_{vir2} = \dots = I_{o\alpha N} R_{virN} \\ I_{o\beta 1} R_{vir1} &= I_{o\beta 2} R_{vir2} = \dots = I_{o\beta N} R_{virN} \end{aligned} \quad (1)$$

The output  $\alpha$  and  $\beta$  axis currents of paralleled inverters are inversely proportional to their virtual resistances. It can be easily observed that current sharing performance is only influenced by the output impedance ratio instead of the output impedance value of these parallel inverters.

### III. THE PROPOSED BALANCED DISCHARGE RATE CONTROL STRATEGY

As discussed above, the focus of the conventional power sharing control strategy in MG is to guarantee the equal power sharing among different DG units. Therefore, the identical virtual impedance  $R_{vir}$  is usually employed for all the DG units. However, the rated capacities and SoC values of ESSs in DGs are usually different. The discharge rate of  $DG_i$  ( $\eta_i$ ) can be defined as following:

$$\eta_i = \frac{d}{dt} SoC_i = -\frac{k}{C_{bati}} P_{invi} \quad (2)$$

where  $k=1/3600$ ;  $C_{bati}$  is the rated capacity of ESS;  $P_{invi}$  is the output active power of  $DG_i$ . It can be seen that the discharge rate is influenced by the different rated capacities of ESSs and the output power of  $DG_i$ . Thus, the discharge rate ( $\eta_{equ}$ ) can be adjusted to an identical value by regulating the virtual resistances ( $R_{vir}$ ) based on their different SoC since the load current sharing ratio among DGs is dominated by the virtual resistances ratio. The control principle is shown in Fig. 5.

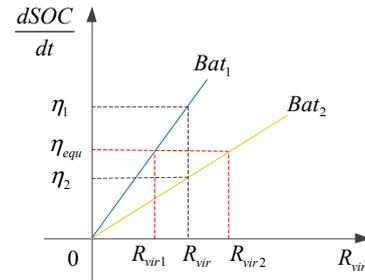


Fig. 5. The control principle for balancing discharge rate.

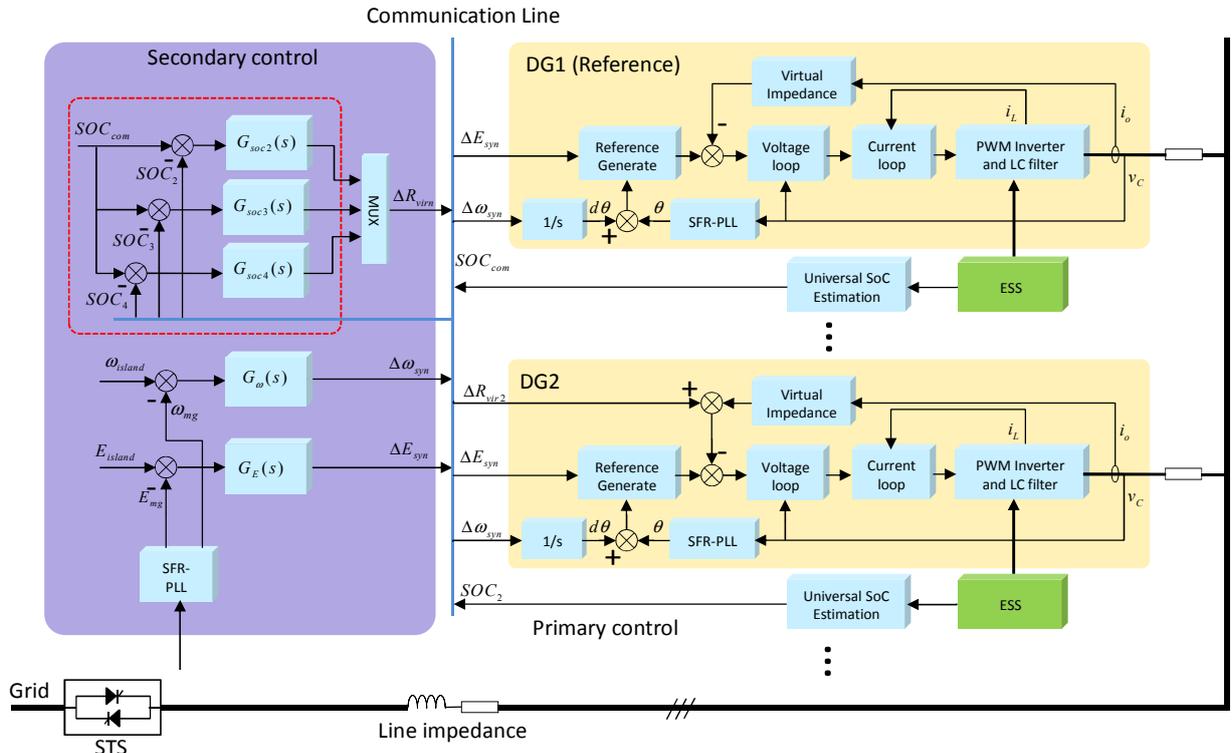


Fig. 6. The detailed control diagram of the proposed coordinated control strategy.

The detailed control scheme of the proposed coordinated secondary control strategy is shown in Fig. 6. The  $\Delta\omega_{syn}$  and  $\Delta E_{syn}$  are used for synchronization. A universal SoC estimation method is employed. The results of SoC estimation loop are fed back to secondary coordinated controller through communication line. Hypothetically, each ESS is fully charged at beginning, which means each initial SoC equals to 1. For balancing the discharge rate among DGs, an additional coordinating control loop is added in the secondary control level. Firstly, one of the DGs is selected as the common reference ( $SoC_{com}$ ). Then the rest of DGs adjust their virtual resistances based on the differences between  $SoC_i$  and the common reference  $SoC_{com}$  by a PID controller expressed as follows:

$$\Delta R_{vir_i} = k_p (SoC_{com} - SoC_i) + k_i \int (SoC_{com} - SoC_i) dt + k_d \frac{d(SoC_{com} - SoC_i)}{dt} \quad (3)$$

where  $k_p$ ,  $k_i$  and  $k_d$  are the parameters of PID controller. In order to depress the power oscillation among DGs, the output of the PID controller will be regarded as an incremental control part. Therefore, the virtual resistances of each DG can be presented as follows:

$$R_{vir_i} = R_{vir\_base} + \Delta R_{vir_i} \quad i = 2, 3, 4, \dots, N \quad (4)$$

#### IV. SMALL SIGNAL MODEL AND STABILITY ANALYSIS

In order to analysis the system stability and parameters sensitivity, the small-signal model of the proposed coordinated secondary controller for balanced discharge rate has been developed in this section.

The consumption of the electrical energy of ESS<sub>i</sub> can be represented by the integration of the output active power of DG<sub>i</sub> ( $P_{invi}$ ), as shown in Fig. 7. Therefore, the SoC of ESS<sub>i</sub> can be calculated as follows:

$$SoC_i = 1 - \frac{k}{C_{bati}} \int P_{invi} dt \quad (5)$$

where  $k = 1/3600$ ;  $C_{bati}$  is the rated capacity of ESS<sub>i</sub>.

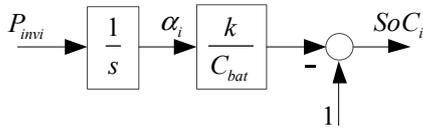


Fig. 7. The simplified model of the relationship between SoC and the output power.

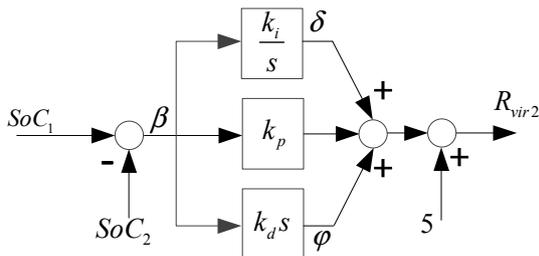


Fig. 8. Structure of the proposed coordinated secondary controller.

The small signal model can be derived as follows:

$$\Delta \hat{\alpha}_i = \Delta P_{invi} \quad (6)$$

The output equation of  $SoC_i$  can be written as follows:

$$SoC_i = \frac{\alpha_i k}{C_{bati}} \quad (7)$$

If there are two DGs in the MG, the coordinated secondary controller for balanced discharge rate can be shown in Fig. 8.

The small signal equation of variables  $\beta$  and  $\delta$  are described in (8) according to Fig.8.

$$\begin{cases} \Delta \hat{\beta} = \frac{1}{k_d} \Delta \varphi = \frac{k}{C_{bat2}} \Delta P_2 - \frac{k}{C_{bat1}} \Delta P_1 \\ \Delta \hat{\delta} = k_i \Delta \beta = \frac{k_i k}{C_{bat2}} \Delta \alpha_2 - \frac{k_i k}{C_{bat1}} \Delta \alpha_1 \end{cases} \quad (8)$$

Since the base value of virtual resistances of DG<sub>1</sub> and DG<sub>2</sub> are set to 5Ω, the relationship between  $\Delta P_1$  and  $\Delta P_2$  can be represented as follow:

$$\Delta P_1 = \left( \Delta P_2 + \frac{P_2 \Delta \delta}{5} + \frac{\delta \Delta P_2}{5} + \frac{2k_d k P_2}{5C_{bat2}} \Delta P_2 - \frac{k_d k P_1}{5C_{bat1}} \Delta P_2 + \frac{k_p P_2 \Delta \beta}{5} + \frac{k_p \beta \Delta P_2}{5} \right) / \left( 1 + \frac{k_d k}{5C_{bat1}} P_2 \right) \quad (9)$$

The complete state space model of MG can be derived as (10) by combining (6) ~ (9).

$$\Delta \hat{X} = A \Delta X + B u \quad (10)$$

where  $\Delta \hat{X} = [\Delta \alpha_1 \quad \Delta \alpha_2 \quad \Delta \beta \quad \Delta \delta]^T$ ,

$$A = \begin{bmatrix} 0 & 0 & \frac{k_p P_2 C_{bat1}}{5C_{bat1} + k_d k P_2} & \frac{P_2 C_{bat1}}{5C_{bat1} + k_d k P_2} \\ 0 & 0 & 0 & 0 \\ 0 & 0 & \frac{-k k_p P_2}{5C_{bat1} + k_d k P_2} & \frac{-k P_2}{5C_{bat1} + k_d k P_2} \\ \frac{-k_i k}{C_{bat1}} & \frac{k_i k}{C_{bat2}} & 0 & 0 \end{bmatrix}$$

The system parameters are given in Table I.

Fig. 9 shows the trace of root locus when  $k_p$  increases from 100 to 1500 while  $k_d$  changes from 1 to 100. It can be seen that the dynamic response and oscillation damping performance of the system are improved as  $k_p$  increases from 100 to 1500. But finally, the dynamic response will decrease as the dominant modes move close toward the imaginary axis. As  $k_d$  increasing, the

TABLE I  
THE PARAMETER OF SMALL SIGNAL MODEL

Parameter	Values	Parameter	Values
$k_i$	1000	$C_{bat1}$	100 Wh
$k_p$	500	$C_{bat2}$	200 Wh
$k_d$	10	$P_2$	1600 W
$k$	1/3600	$P_1$	800 W
$R_{vir1}$	5 Ω	$R_{vir2}$	5 Ω

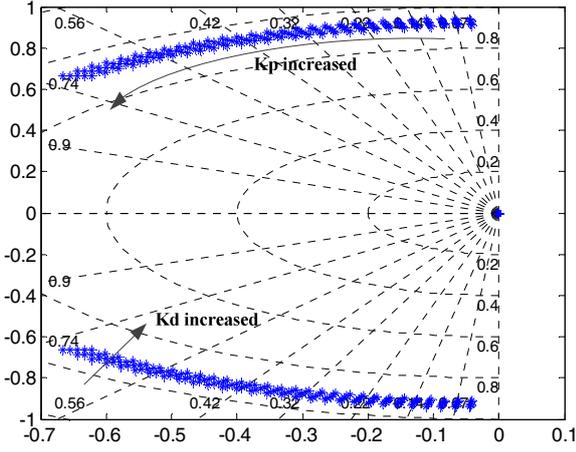


Fig. 9. Trace of nodes as function of  $1 \leq k_d \leq 100$  and  $100 \leq k_p \leq 1500$ .

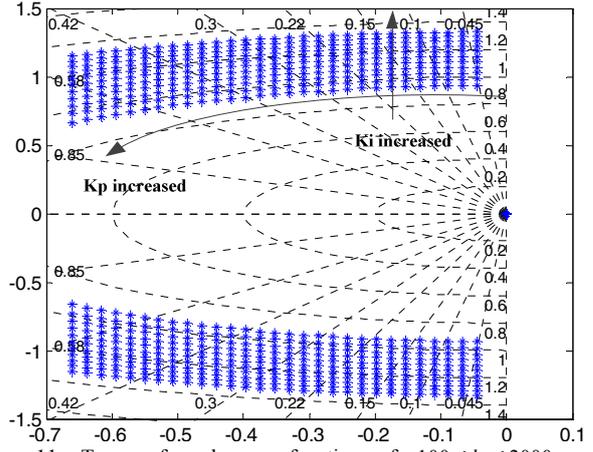


Fig. 11. Trace of nodes as function of  $100 \leq k_i \leq 2000$  and  $100 \leq k_p \leq 1500$ .

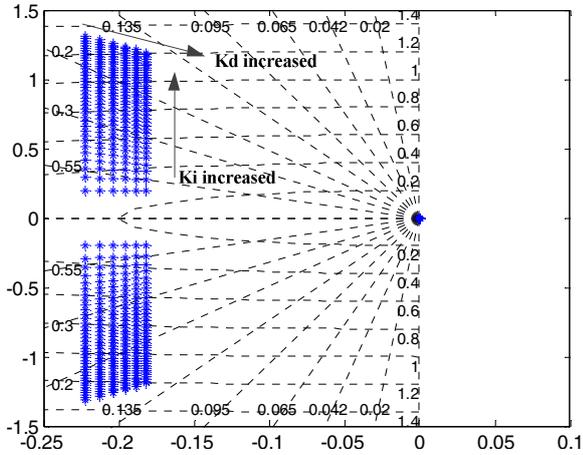


Fig. 10. Trace of nodes as function of  $1 \leq k_d \leq 300$  and  $100 \leq k_i \leq 2000$ .

Fig. 10 shows trajectories of the modes in function of  $k_d$  increases from 1 to 300 while  $k_i$  increases from 100 to 2000. It can be seen that the complex poles trend to become the dominant modes, resulting in a near second order behavior. The imaginary parts of modes increase and move toward to the imaginary axis as  $k_d$  and  $k_i$  increasing, which will make the system become more oscillatory.

Fig. 11 shows the trajectories of the modes in function of  $k_i$  increases from 100 to 2000 while  $k_p$  increases from 100 to 1500. It can be seen that when the parameters increasing, the dominant modes move apart from imaginary axis which will improve the system dynamic response and oscillation damping performance.

## V. SIMULATION AND VERIFICATION

In order to compare and evaluate the performance of the proposed coordinated secondary control for balanced discharge rate, simulations based on MATLAB/Simulink are conducted. The simulation model is composed of three DGs with different ESS capacities, a constant load ( $Load_{con}$ ), and a dynamic load ( $Load_{dyn}$ ) for step up and step down test. The parameters of simulation models are listed in Table II. In this comparison, the control parameters for both conventional control and the

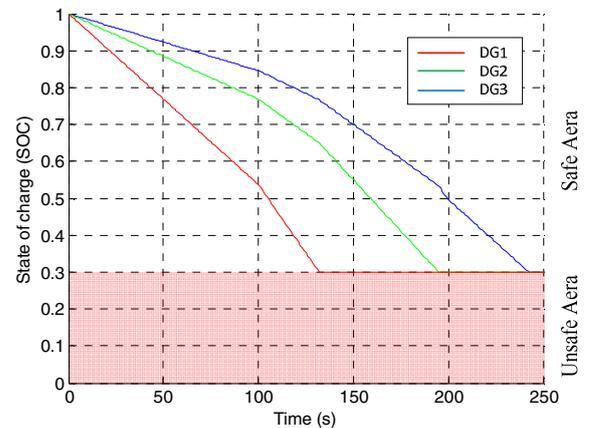
Parameter	Values	Parameter	Values
$DG_1$	4.5 kW	$C_{bat2}$	200 Wh
$DG_2$	4.5 kW	$C_{bat3}$	300 Wh
$DG_3$	4.5 kW	$Load_{con}$	5000 W
$C_{bat1}$	100 Wh	$Load_{dyn}$	3000 W

proposed control are all the same.

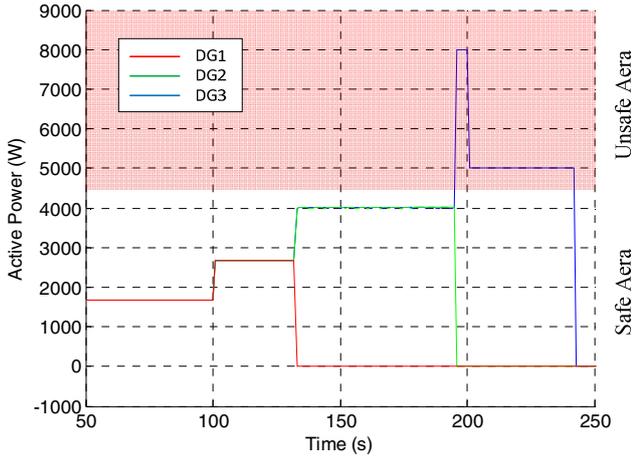
Before the comparison simulation, some assumptions need to be set. The first is the ESS<sub>i</sub> for each DG is fully charged initially, thus all SoC<sub>i</sub> are equal to 1. Then  $Load_{con}$  sharing ratio among DGs is set to equal in conventional control simulation.  $Load_{dyn}$  is connected and disconnected at 100s and 200s respectively. The threshold of SoC is assigned to 0.3 which means the DG<sub>i</sub> has to be shut down to protect the ESS<sub>i</sub> when SoC<sub>i</sub> is below 0.3.

### A. The simulation results with the traditional controller

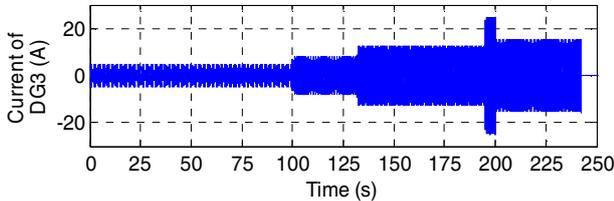
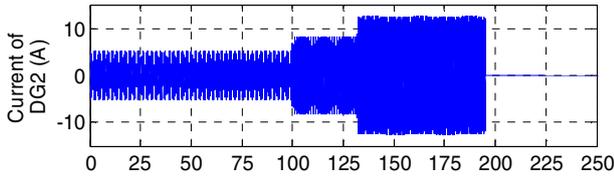
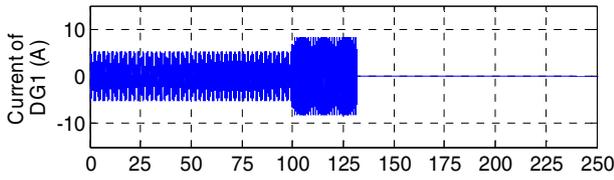
The comparative simulation results with the conventional control strategy are shown in Fig. 12. It can be seen that output active power of each DG is controlled equally to share the loads with the traditional controller. Thus, the SoC of each DG decreases with different rates, since the rated capacities of ESSs are different.



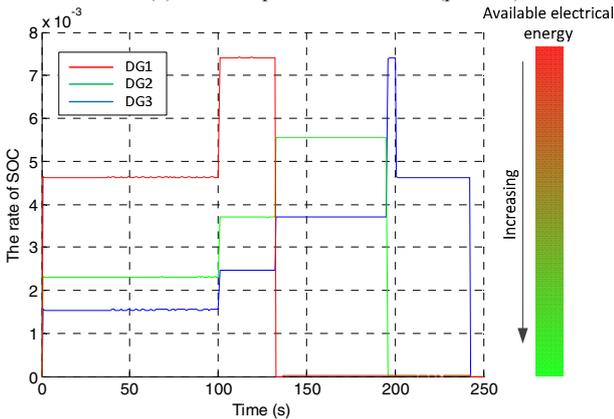
(a) The SOC of ESSs.



(b) The active power of DGs.



(b) The output currents of DGs (phase A).



(d) The change rate of SOC.

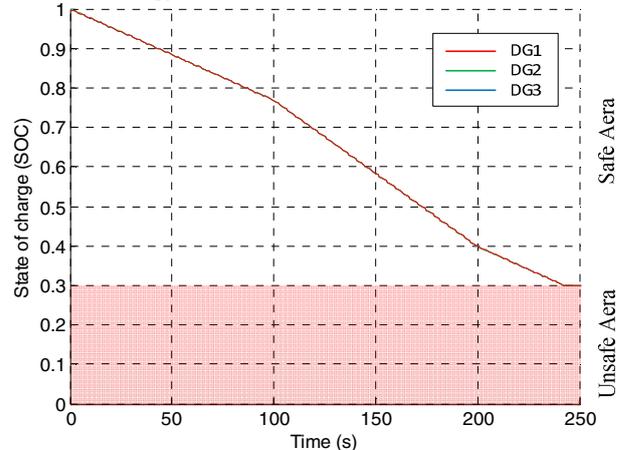
Fig. 12. The simulation results with the conventional control strategy.

In this test, the  $DG_1$  has the smallest ESS capacity. Therefore, the SoC of  $DG_1$  decreases fastest with the unified output current. Then, the  $DG_1$  is shut down at 131s when  $SoC_1$  reaches 0.3, as shown in Fig. 12(a). Meanwhile, the output of  $DG_2$  and  $DG_3$  increase immediately to support the local loads as shown in Fig. 12 (b) and (c). At 193s, the  $DG_2$  is shut down due to the

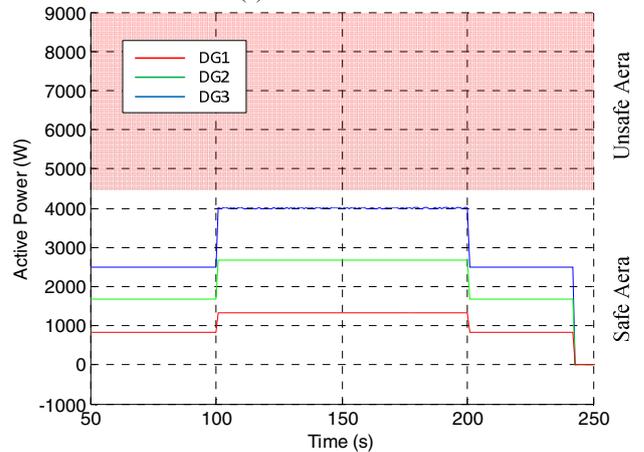
$SoC_2$  is less than 0.3. The output power of  $DG_3$  increases to 8kW which is far over its rated capacity since it has to take over all the local loads after 193s. Obviously, there is serious risk that will result in operation failure due to the over current in the real application. Therefore, the rated capacities of all the DGs have to be increased for allowance in order to avoid jeopardizing the reliability of MG. Moreover, in practice, the faster the DGs discharge, the less the electrical energy can be obtained totally as shown in Fig. 12 (d).

### B. The simulation results with the proposed controller

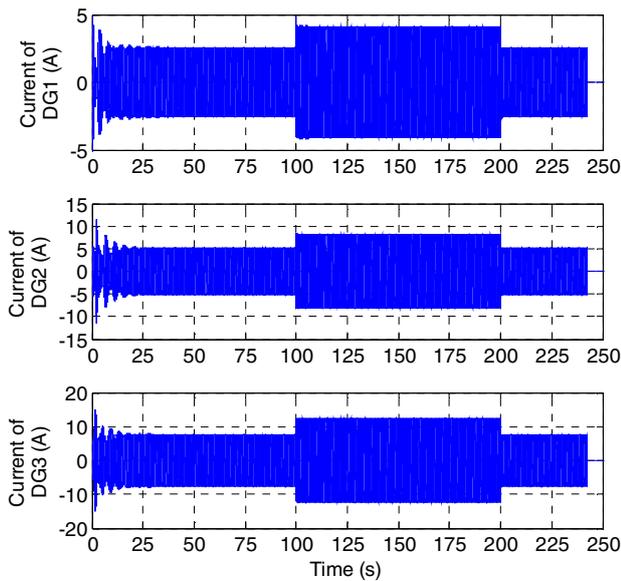
The simulation results with the proposed control strategy are shown in Fig.13. The virtual resistances of  $DG_2$  and  $DG_3$  are regulated based on the outputs of the proposed coordinated secondary controller. In this way, these three SoC values decrease with the same gradient and reach the protection threshold simultaneously as shown in Fig. 13(a). It can be seen that the output active power and output current of DG units are different according to their SoC respectively, as shown in Fig. 13(b) and (c). Note that, there is no over current happens in Fig. 13(b). In other words, the operation failure can be effectively prevented. Thus, the redundant capacities of DGs and the costs can be reduced, and the reliability of MG can be increased. Furthermore, the discharge rate of ESS with the proposed controller in Fig. 13(d) is lower than the discharge rates in Fig. 12(d), which means more electrical energy can be obtain from ESS.



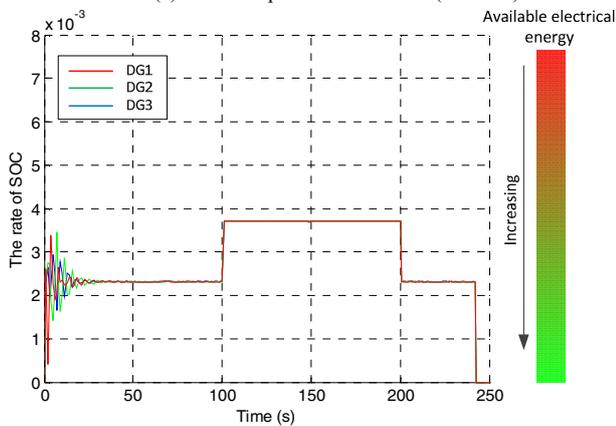
(a) The SOC of ESSs.



(b) The active power of DGs.



(c) The output current of DGs (Phase A).



(d) The change rate of SOC

Fig. 13. The simulation results with the proposed coordinated secondary controller.

## VI. CONCLUSIONS

A novel coordinated secondary control based on an autonomous currents sharing control strategy for balanced discharge rate of ESS in islanded MG is proposed in this paper. This controller can avoid the potential operation failure, provide the faster response and accurate output current sharing control, and improve the stability and reliability of islanded MG. The eigenvalues and root locus with the proposed controller are presented to design the parameters as well as analyzing the system stability. Simulation results based on Matlab/simulink verify the effectiveness of the proposed controller.

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