

Interactive Power Systems Simulator User's Manual

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Contents

1	Introduction	3
2	Using IPSYS	6
2.1	Data Types	7
2.2	Built in Operators and Functions	12
2.3	Scripts and Functions	18
2.4	Power Systems Functions	22
2.5	Input/Output and Miscellaneous Functions	27
3	Matlab Interface	29
3.1	Introduction	29
3.2	Matlab Interface Data	30
3.3	Matlab Interface Functions	33
4	GIPSYS Interface	35
4.1	Entering a New Network	36
4.2	Running IPSYS Algorithms	38
5	IPSYS Examples	40
5.1	Linear Algebra	41
5.1.1	Checking Rank and Condition Number	41
5.1.2	Sensitivity Matrix Extraction	41
5.1.3	Matrix Decomposition and Clustering	42
5.2	Power Flow Examples	44
5.2.1	Example 1	44
5.3	DC Optimal Power Flow - Flexible Generation	48
5.4	DC Optimal Power Flow - Flexible Load	53

5.5	DC Optimal Power Flow - Flexible Generation and Load . . .	55
6	Matlab Examples	58
6.1	Matlab Input Output	58
6.2	Matlab Functions	62
7	Notes, Bugs, TODO list	64
A	Installation	67
B	Description of the PTI Load Flow Data Format	68
C	Power Flow Review	73
D	Optimal Power Flow Review	77
E	DC Optimal Power Flow Review	79

Chapter 1

Introduction

Academic research frequently suffers from programming limitations of general purpose programming languages such as Fortran, C/C++, as well as interpreted languages such as Matlab. General programming languages provide the ultimate flexibility at the price of long development cycles and are difficult to maintain once the access to the original developers is not available anymore. On the other hand, interpreted languages provide significant development and maintenance flexibility at the price of programming features and frequently \$ price. After surveying both approaches to scientific programming, it seemed that it could be possible to have the best of the both worlds, that is an interpreted language expandable with natively coded modules and ability to call native functions from the interpreter and even the interpreter functions from the native functions and all that for a small price in flexibility and short learning curve. The result of this conclusion is a generic Application Programming Interface (API) framework. Appropriate power systems functionality is added to this framework producing Interactive Power Systems Simulator or IPSYS for short. The framework allows adding new special purpose modules independently of existing modules and using the built in Command Line Interface (CLI) or develop custom Graphical User Interface (GUI). The both of these approaches are used for a development of a power systems simulator and their use is described in this manual along the generic framework features.

The Interactive Power System Simulator (IPSYS) is a scripting tool used to define, manipulate, and analyze electrical power systems described using Power Technologies, Inc. input data format as described in [4]. A user

can interact with a single or multiple power systems through IPSYS shell, Matlab interface (MIPSYS), or a single network using a GUI interface (GIPSYS). IPSYS libraries can be used for developing different purpose interactive programs using the C++ programming language. Power networks are completely modeled as objects and can be operated on through a set of message passing methods. Separate power network objects can be interfaced by setting the power generation in one of the systems and matching load in the adjacent system. Determining the level of power exchange can be done either using the IPSYS shell or C++ programming. This User Manual describes IPSYS, MIPSYS, and GIPSYS functionality; application Programming Interface (API) is described in a different manual.

IPSYS shell interface features can be grouped in four distinctive parts: data types, general type operators and functions, program control and scripting, and specialized power systems routines. IPSYS supports real number, matrix, and character string variables. All of these data types can be entered interactively, with a script, or in the case of matrices from a file. Power system networks are modeled as separate objects that can be read in from a file, manipulated, modified, simulated, optimized, and the resulting system can be stored in an external file. Multiple power system networks are stored at the global scope and as such can be accessed from any built in or scripting function. General purpose operators and functions include usual arithmetic and logical operators, transcendental, and linear algebra functions. Any other functions can be added to this set provided that the function parameters operate on available data types and the result is also an available data type. Program flow control structures provide enough functionality for a complete procedural programming language. This includes logical tests, looping, and input and output functionality. User functions defined as ipsys scripts or C++ functions are supported with input and output arguments passed by value. From users' perspective, there is no difference between ipsys and C++ functions. Due to the object oriented power system modeling, data and functional encapsulation are provided by the power system objects. Power systems functions include AC power flow, implementation of different optimal power flow algorithms, as well as a programmatic way to manipulate the networks being simulated. The optimization routines use commercial library (IMSL) but they could use any other commercial and non commercial C/C++/F77 library.

GIPSYS adds to IPSYS a GUI interface from which a network can be entered, modified and a few common algorithms executed. GIPSYS is a semi independent front end library developed for a different purpose and illustrates the flexibility with which new modules with very little interdependence can be added to the framework. The only difference between IPSYS run without GUI and with GUI is that the GUI version does not handle more than one network at the time.

MIPSYS is the Matlab interface to IPSYS back end routines. Since Matlab provides much richer general computational language capabilities, the only IPSYS routines that are exported to Matlab are the power systems specific which are not part of Matlab. This development branch uses an older IPSYS version and is abandoned in favor of IPSYS and GIPSYS user interfaces and ability to export power system networks to Matlab environment.

Chapter 2

Using IPSYS

In this chapter, IPSYS data structures, operators, program control, and programming are discussed in detail. These are the core features that are available for power systems functions and GIPSYS use both of which are discussed in subsequent chapters.

IPSYS CLI is started by simply typing `ipsys.exe` command at the command prompt provided that the the IPSYS executable is in the systems PATH. Exiting from IPSYS is done by typing `quit` command:

```
prompt$ ipsys
*****
          Interactive Power Systems Simulator
          Carnegie Mellon University
          Aug 25 2007 08:49:46
*****
ipsys> quit;
prompt$
```

After started, IPSYS is accepting commands as described in the rest of this manual. The following sections introduce IPSYS data types, operators, commands and includes the reference information.

2.1 Data Types

IPSYS uses real number, matrix, and character string variables as well as a number of predefined constants,. The following is the list of predefined constants:

Constant Symbol	Constant Value
M_E	e
M_LOG2E	$\log_2(e)$
M_LOG10E	$\log_{10}(e)$
M_LN2	$\ln(2)$
M_LN10	$\ln(10)$
M_PI	π
M_PI_2	$\frac{\pi}{2}$
M_PI_4	$\frac{\pi}{4}$
M_1_PI	$\frac{1}{\pi}$
M_2_PI	$\frac{2}{\pi}$
M_2_SQRTPI	$\frac{2}{\sqrt{\pi}}$
M_SQRT2	$\sqrt{2}$
M_SQRT1_2	$\sqrt{\frac{1}{2}}$
RAND_MAX	RAND_MAX

Table 2.1: Common mathematical constants

Real variables can be introduced through an interactive command or script and follows the standard real number format:

```
ipsys> a = 2.5;  
ipsys> b = cos(M_PI);
```

A matrix can be entered from the command line:

```
ipsys> a = [1, 2,3; 4, 5, 7; 9, 7, 4];
```

or from a file:

```
ipsys> a = Matrix('3x3.mat');
```

where 3×3 .mat file contains:

```
3 3
1 2 3
4 5 7
9 7 4
```

or a constant matrix can be defined as:

```
ipsys> a = Matrix(3,3,M_PI);
ipsys> printf("%6.3f ",a);
a = [
  3.142  3.142  3.142 ;
  3.142  3.142  3.142 ;
  3.142  3.142  3.142
]
```

If a matrix is entered from the command line, entries can be real variables or expressions, for example:

```
ipsys> a = [M_PI, cos(M_PI_2); 0, 1/2];
ipsys> printf("%7.3f",a);
a = [
  3.142  0.000;
  0.000  0.500
]
```

When a matrix is read from an ASCII data file, the first two integers are the number of rows and the number of columns of the matrix and the rest are the matrix entries. There can be more than enough matrix entries, but it is an error if there are fewer than $rows \times columns$ entries ($3 \times 3 = 9$ in the example). Numbers in the data file can be arranged in any way and can be either in floating point or integer number format. Matrix entry indexing is one based, meaning that row and columns counting starts from 1. The following script swaps matrix entries $a(1,1)$ and $a(2,2)$:

```
ipsys> tmp = a(1,1);
ipsys> a(1,1) = a(2,2);
ipsys> a(2,2) = tmp;
```

In the case of the matrix data type, IPSYS also allows for a matrix block extraction or assignment. For example, if “test.mat” contains a 8×7 matrix:

```

ipsys> t = Matrix("test.mat");
ipsys> printf("% 3g ",t);
t = [
  1  2  3  4  5  6  7 ;
  8  9 10 11 12 13 14 ;
 15 16 17 18 19 20 21 ;
 22 23 24 25 26 27 28 ;
 29 30 31 32 33 34 35 ;
 36 37 38 39 40 41 42 ;
 43 44 45 46 47 48 49 ;
 50 51 52 53 54 55 56
]

```

the following commands show how matrix block extraction can be used:

```

ipsys> a = t([1,2,3],[2,3]);
ipsys> printf("% 3g ",a);
a = [
  2  3 ;
  9 10 ;
 16 17
]

```

```

ipsys> a([1,2],[1,2]) = t([7,8],[6,7]);
ipsys> printf("% 3g ",a);
a = [
  48 49 ;
  55 56 ;
  16 17
]

```

```

ipsys> printf("% 3g ",t(2,[1,2,3,4,5,6,7]));
[
  8  9 10 11 12 13 14
]

```

Note that the index matrices are actually row vectors and that indexing is one based. To index contiguous matrix elements, Range function can be used to generate index range. For example, the first two rows of a matrix can be extracted as:

```

ipsys> a = Matrix("shiljak.mat");
ipsys> printf("%6.3f ",a(Range(1,2),Range(1,Cols(a))));
[
  0.000  0.000  0.010  0.000  2.150  0.000  0.040  0.000 ;
  0.070  1.100  0.030  0.000 -0.060 -0.020  0.000  0.250
]

```

IPSYS provides function for construction of constant and identity matrices. Following commands calculate the inverse of matrix a:

```

ipsys> a = [1,2,3;4,5,4;3,2,1];
ipsys> i = Idn(3);
ipsys> printf("% 3.2f ", i/a);
[
  0.38 -0.50  0.88 ;
 -1.00  1.00 -1.00 ;
  0.87 -0.50  0.37
]
ipsys> printf("% 3.2f ", a*i/a);
[
  1.00 -0.00 -0.00 ;
 -0.00  1.00 -0.00 ;
  0.00  0.00  1.00
]

```

Identity, transposed, and constant matrices can be constructed as follows:

```

ipsys> a = Matrix("3x3.mat");
ipsys> printf("% 3.2g ",a);
a = [
  1  2  3 ;
  4  5  6 ;
  7  8  9
]
ipsys> printf("% 3.2g ",Trn(a));
[
  1  4  7 ;
  2  5  8 ;
  3  6  9
]

```

```

]
ipsys> printf("% 3.2g ",Idn(3));
[
  1  0  0 ;
  0  1  0 ;
  0  0  1
]

```

Character strings in IPSYS are defined by double quotes:

```
ipsys> a = '1234.234';
```

In this example, 1234.234 is a character string and any numerical manipulation will cause an error. In addition to the ASCII character set, IPSYS recognizes escaped characters `\t` as a tab and `\n` as a new line. The following IPSYS string variable prints out as:

```
ipsys> str = "Here are 2 tabs\t\t and a new line\n";
ipsys> printf(str);
Here are 2 tabs           and a new line

```

This completes the discussion of IPSYS data types. These data types are sufficient for procedural programming commonly used for scientific purposes.

2.2 Built in Operators and Functions

IPSYS interprets the usual arithmetic operators and one argument functions of different data types in an intuitive way. Addition, subtraction, multiplication, and division can be used with real numbers, matrices and a combination of both. The only requirement is that the matrix/matrix operations have compatible dimensions. When a two argument operator is applied to a real number and a matrix, the operator is applied element-wise. That is, the operation is between the scalar and each of the matrix elements. For example:

```
ipsys> a = [1,2;3,4];
ipsys> printf("% 2.3f ", 1/a);
[
  1.000  0.500 ;
  0.333  0.250
]
ipsys> printf("% 3.3g ", 2*a*2);
a = [
  4  8 ;
  12 16
]
ipsys> printf("% 3.3g ", a/2);
a = [
  0.5  1 ;
  1.5  2
]
```

Examples of matrix/matrix operations:

```
ipsys> a = [1,2;3,4];
ipsys> b = [2,3;5,7];
ipsys> printf("% 3.3g ", a*b);
[
  12 17 ;
  26 37
]
ipsys> printf("% 3.3f ", (a/b)*(b/a));
[
```

```

1.000  0.000 ;
-0.000  1.000
]
ipsys> printf("% 3.3f ", a-c);
Incorrect argument dimensions: Matrix::sub(Matrix &)
Line 23: printf("% 3.3f ", a-c);

```

General purpose functions include:

cos(real or matrix)	Returns cos(); argument is in radians
sin(real or matrix)	Returns sin(); argument is in radians
tan(real or matrix)	Returns tan(); argument is in radians
abs(real or matrix)	Returns abs()
exp(real or matrix)	Returns natural exponent
srand(real or none)	Seeds random number generator
rand()	Returns a random integer between 0 and RAND_MAX
min(real or matrix)	Returns minimum entry in a matrix
max(real or matrix)	Returns maximum entry in a matrix
Rows(matrix)	Returns number of rows of a matrix
Cols(matrix)	Returns number of columns of a matrix
Range(real,real)	Returns a row vector of integer numbers in the range
Rank(matrix)	Returns rank of a matrix
Cond(matrix)	Returns condition number of a matrix
Idn(real)	Returns identity matrix of requested dimension
Trn(matrix)	Returns transpose of a given matrix
EDec(matrix,real)	Returns epsilon decomposition of a matrix
Clust(matrix,real)	Returns clustered matrix
Matrix(string)	Returns a matrix read from file

Table 2.2: General purpose functions

Single argument math functions can take either a real number or a matrix. In the case of a matrix input, function is applied to each matrix entry. The four arithmetic operations have the usual meaning for real numbers. If one of the operands is a matrix, the result depends on which of the operands is the matrix. For addition/subtraction, if both operands are matrices, they must be of the same dimensions and the result is the regular matrix addition/subtraction. If one of the operands is a matrix and the other one is a

real number, the addition/subtraction is done element wise. That is, it is equivalent to addition/subtraction of two matrices where one of the matrices has all the elements equal to the real number operand. Two real number multiplication also has the usual meaning. If one of the operands is a real number and the other one is a matrix, the result is the matrix multiplied by a constant. Division has the usual interpretation for real numbers. If one of the operands is a matrix and the other one is a real number, the operation is done element wise. Since division is not commutative, either the real number or matrix elements can be the divisor. In the case of division, there can also be a combination of two matrices of different dimensions. Depending on the dimensions of the matrices, the result can be a solution of a single system of linear equations, a number of linear equations, or a Least Square Estimation (LSE). Matrices still must satisfy dimension requirements to be able to perform these operations. The following example finds a solution of a single system of linear equations $AB = X$; A is 3x3 and B is 3x1. This is a determined system of equations.

```
ipsys> a = Matrix("3x3.mat");
ipsys> a(2,2) = -1;
ipsys> b = [1;1;1];
ipsys> printf("% 3.2f ",b/a);
[
-0.50 ;
 0.00 ;
 0.50
]
```

Next is an example of the solution of a system $Ax = B$ where A is 3x3 and B 3x2. This is still a determined system of equations.

```
ipsys> b = [1,2;1,3;1,4];
ipsys> printf("% 3.2f ",b/a);
[
-0.50 -0.50 ;
 0.00 0.00 ;
 0.50 0.83
]
```

Note that one of the solutions is the same as in the previous example. The following is an example of an over determined system of equations. The solution is an LSE approximation.

```
a = [1, 2, 3;5, 4, 2; 7, 6, 4; 1, 2, 9];
ipsys> printf("Rank(a) = %g \n",Rank(a));
Rank(a) = 3
b = [1;1;1;1];
ipsys> printf("% 3.2f ",b/a);
[
-0.38 ;
 0.65 ;
 0.01
]
```

The result of this operation is the LSE approximation of the solution. Note that the rank of a must be equal to the number of columns for this operation to be possible. These results are typical for QR decomposition used to solve systems of equations.

IPSYS also provides enough of the common programming constructs to be able to write general purpose scripts. This includes condition tests, IF-THEN-ELSE conditional execution, WHILE, and FOR loops. With these basic constructs, one should be able to perform other program flow controls. Condition tests and logical operators implemented by IPSYS:

==	Equality test
<	Less than test
>	Greater than test
<=	Less than or equal test
>=	Greater than or equal test
!=	Not equal test
&&	Logical AND operator
	Logical OR operator

Table 2.3: General purpose logical operators

Typical script with conditional tests:

```

ipsys> a = 0;
ipsys> if(a == 0){
    b = 1.0;
} else {
    b = 1/a;
}
ipsys> printf("%g\n",a);
0

```

IPSYS understands usual program flow control constructs. Loops are implemented using "while" and "for" constructs and the tests with "if-then-else" logical test. All the logical operators are discussed in section 2.2. The following is an example of typical use of test and looping in IPSYS:

```

ipsys> a = 0;
ipsys> b = 10;
ipsys> while(a < 5 && b > 0){
    printf("a = %g\tb = %g\n",a,b);
    a = a + 1;
    b = b - 1;
}
a = 0    b = 10
a = 1    b = 9
a = 2    b = 8
a = 3    b = 7
a = 4    b = 6

```

Another way of looping through a series of calculations is by using for loops:

```

ipsys> for(i = 0; i < 5; i = i + 1){
    printf("% 3.2g \n", i/5);
}
0
0.2
0.4
0.6
0.8

```

Flow control using continue, break, and goto statement are not implemented since they are not necessary. Switch/case statement can be emulated with with a more flexible if/else if construct:

```
ipsys> a = M_PI;
ipsys> if(a == M_PI_2)
    printf("a is %g\n", M_PI_2);
else if(a == M_PI)
    printf("a is %g\n", M_PI);
else
    printf("a is not known\n");
a is 3.14159
```

Previous examples use printf function which is part of the I\O and is described in more detail in section [2.5](#).

2.3 Scripts and Functions

There are two mechanisms to automate and expand IPSYS capabilities. One is by using include statement and the other one is by writing new scripting and/or hard coded functions. New scripting functions can be either typed from the command prompt or more commonly using the include statement.

Include statement simply includes a file that is automatically interpreted as an IPSYS script. An include function can contain any statements that might be used during an interactive IPSYS session. Such script files can be used for function definition, repetitive data entry, and/or execution. As an example, the following is the execution of an include statement:

```
ipsys> #include "Solve.ipsi";
c = [
  0.93  1.32 ;
-1.81  0.43 ;
  0.75  0.44
]
```

where Solve.ipsi file contents is:

```
a = rand(3,3);
b = rand(3,2);
c = b/a;
printf("%5.2f ",c);
```

In this case, include is executed at the top level and the created variables are global:

```
ipsys> lsVars();
stack level: 0
      [a,      00A095F8]          [a,      3x3 matrix]
      [b,      00A096C8]          [b,      3x2 matrix]
      [c,      00A09888]          [c,      3x2 matrix]
```

IPSYS can use scripting and built in (hard coded) functions. From users' perspective they are the same. Users can program both scripting and built in (C++) functions. However, built in functions must be defined in IPSYS and added to a lookup table in addition to compiling and linking the function.

These process is straight forward and explained in more details in the API Manual. Scripting functions must be defined before used. Once defined without any errors, scripting functions are compiled into execution trees. Scripting functions can call built in functions and built in functions could easily call scripting functions. Scripting function can be defined anywhere within IPSYS session but the recommended method is by using include statement. A function is defined similar to Matlab functions. The following example illustrates all of the function definition and calling features. LinSolve function is defined in LinSolve.ipsi file as:

```
function [x,y] = LinSolve(a,b){
    if(Rows(b) != Rows(a)){
        printf("Incompatible dimensions\n");
        return 0;
    }
    if(Rank(a) != Cols(a)){
        printf("Rank deficient matrix a.\n");
        return 0;
    }
    x = b/a;
}
```

and included in IPSYS workspace with:

```
#include "LinSolve.ipsi";
```

Now, LinSolve() function can be called in three different ways:

```
ipsys> #include "LinSolve.ipsi";
ipsys> a = rand(3,3);
ipsys> b = rand(3,2);
ipsys> [sol] = LinSolve(a,b);
ipsys> printf("% 5.2f ",sol);
sol = [
    0.73  0.83 ;
    1.94  0.48 ;
   -1.80 -0.51
]
ipsys> printf("% 5.2f ",LinSolve(a,b));
[
```

```

0.73  0.83 ;
1.94  0.48 ;
-1.80 -0.51
]
ipsys> [sol,non] = LinSolve(a,b);
ipsys> printf("% 5.2f \n",non);
0.00

```

LinSolve() is defined to return two variables. Calling function can use both variables, just one of them, or none. Return variables are assigned to variables in calling function's memory space from left to right. In addition, if only one variable is transferred, it must be the left most one and in that case it does not need brackets as shown above. Also, if the function does not return any variable, the default return value is zero. The following function is perfectly acceptable and useless but it does produce a zero as the return value:

```

ipsys> function [] = zero(){
};
ipsys> printf("%g\n",zero());
0

```

Each IPSYS function uses its own memory space and recursive calls can be used as expected. The following example defines a recursive Fibonacci function and shows its use:

```

ipsys> #include "fib.ipsi";
ipsys> f = fib(14);
ipsys> printf("%g\n", f);
233
ipsys>

```

where fib.ipsi file contains:

```

function [f] = fib(n){
    if(n <= 1){
        return 0;
    } else if (n == 2){
        return 1;
    } else {

```

```
    return (fib(n-2) + fib(n-1));  
  }  
}
```

Application Programming Interface (API) and development of natively compiled functions is described in the API "User's Manual". As far as function user is concerned, there is no difference between calling a scripting function or compiled function.

2.4 Power Systems Functions

IPSY is based on the framework potentially providing interactive interface for many different problems. To differentiate between different algorithm types, power systems functions are prefixed with SSNet meaning steady state network. Power systems functions can be grouped into two groups: network input/output functions and network computational functions. Each input/output function can be used for both input and/or output by allowing for optional inputs. That is, if the function is to be used just to get an output from the net, the optional arguments are omitted. If the same function is to be used as an input to the net, the optional arguments contain the input values.

IPSY network functions use a part of PTI23 data described in [4]. Currently, IPSY uses bus, generator, switched shunts, and transformer adjustment data. However, both switched shunts and transformers are used as fixed elements, that is their settings are not adjusted to control either bus voltage or branch real power flow. Power system input/output function description:

Function Name	Function Description
SSNet	Defines a network from a PTI file and optional supply and demand files
SSNetGen	Sets real power generation level
SSNetGenST	Sets generator status
SSNetLoad	Sets real and reactive load level
SSNetVolt	Sets voltage magnitude and angle of a bus
SSNetShunt	Sets shunt value on a given bus in a given system
SSNetPrint	Prints out PTI23 network data
SSNetPrintFlows	Prints out power flows
SSNetJac	Returns power flow jacobian
SSNetG	Returns G part of admittance matrix
SSNetB	Returns B part of admittance matrix
SSNetCost	Returns productions cost

Table 2.4: Power system input/output functions

Power system output functions calling options and return values:

Function Name	Required Arguments	Optional Arguments	Return Values
SSNet	1) net name 2) input file 3) supply file 4) demand file		(0??)
SSNetGen	1) net name 2) bus number 3) generator ID	4) new P 5) new Q	1) old P 2) old Q
SSNetGenST	1) net name 2) bus number 3) generator ID	4) new ST	1) old ST
SSNetLoad	1) net name 2) bus number 3) load ID	4) new P 5) new Q	1) old P 2) old Q
SSNetVolt	1) net name 2) bus number	3) new mag 4) new ang	1) old Vmag 2) old Vang
SSNetShunt	1) net name 2) bus number	3) new Gl 4) new Bl	1) old Gl 2) old Bl
SSNetPrint	1) net name		0
SSNetPrintFlows	1) net name	1) output file	0
SSNetJac	1) net name		1) Jacobian
SSNetG	1) net name		1) matrix G
SSNetB	1) net name		1) matrix B
SSNetCost	1) net name		1) cost

Table 2.5: Power system input/output functions arguments

The implemented power system algorithms are described in Table 2.4. Power system algorithm calling options and return values are shown in Table 2.6. SSNet function requires four arguments where some or all of the last two can be empty strings.

Functions SSNetGen, SSNetGenST, SSNetLoad, SSNetVolt, and SSNetShunt are used to get, set, or get old and set new values. For example, the following command at the same time reads the old generator status value and sets the

Function Name	Function Description
SSNetNRPF	Newton-Raphson power flow
SSNetDCOPFFlexG	DC OPF with dispatchable generation
SSNetDCOPFFlexD	DC OPF with dispatchable demand
SSNetDCOPFFlexGD	DC OPF with dispatchable generation and demand
SSNetDF	returns distribution factors matrix
SSNetDCFL	returns calculated DC flows using distribution matrix
SSNetMakeSens	calculates sensitivity matrices
SSNetDPgDT	Returns $\frac{\partial P_g}{\partial \theta}$ and index vectors
SSNetDPgDVg	Returns $\frac{\partial P_g}{\partial V_g}$ and index vectors
SSNetDPgDVI	Returns $\frac{\partial P_g}{\partial V_l}$ and index vectors
SSNetDPIDT	Returns $\frac{\partial P_l}{\partial \theta}$ and index vectors
SSNetDPIDVg	Returns $\frac{\partial P_l}{\partial V_g}$ and index vectors
SSNetDPIDVI	Returns $\frac{\partial P_l}{\partial V_l}$ and index vectors
SSNetDQIDT	Returns $\frac{\partial Q_l}{\partial \theta}$ and index vectors
SSNetDQIDVg	Returns $\frac{\partial Q_l}{\partial V_g}$ and index vectors
SSNetDQIDVI	Returns $\frac{\partial Q_l}{\partial V_l}$ and index vectors
MatrixLMPSG	Returns LMPS while optimizing flexible generation
MatrixLMPSD	Returns LMPS while optimizing flexible demand
MatrixLMPSGD	Returns LMPS while optimizing flexible generation and demand

IPSYYS Power system algorithms

new value:

```
ipsys> st4 = SSNetGenST("b6",4,"'1 ' ",0);
ipsys> printf("previous generator on bus 4, id 1 status was %g\n",st4);
previous generator on bus 4, id 1 status was 1
```

while the next example just reads the status of the same generator:

```
ipsys> st4 = SSNetGenST("b6",4,"'1 ' ");
ipsys> printf("current generator on bus 4, id 1 status is %g\n",st4);
current generator on bus 4, id 1 status is 0
```

The following group of functions calculate various sensitivity matrices. For efficiency reasons, SSNetMakeSens() must be called to actually calculate all of the sensitivities for the current operating conditions. Afterward, a sensitivity matrix can be obtained using an appropriate function. All of these functions

return a sensitivity matrix and two index vectors defining the sensitivities. For example:

```
ipsys> [dpgdvl, i, j] = SSNetDPgDV1("b6");
ipsys> printf("%g\t%g\n",i(1,1),j(1,1));
1      2
```

means that $dpgdvl_{1,1} = \frac{\partial P_{g1}}{\partial V_{i_2}}$. The only purpose of displaying the indexes is for the users benefit. Indexes are used for original bus and should not be used for indexing internal data structures. All of the sensitivity functions take a Net variable as single argument and can be reliably used only after calling SSNetMakeSens first.

The next group of calculates Locational Marginal Prices (LMP) while optimizing either the flexible supply,demand, or both. For example, SSNetLMPG("all", [3, 1, 0.1]) finds nodal LMPs of network named "all" when line 1 → 3 is congested using 0.1 increment and flexible supply. The first vector entry is the node to which the price reference node is connected. The second argument is the price reference node, and the third argument is the transmission constraint increment used to calculate Lagrangian multipliers. It is very important that the line is either congested or not for the both values of the transmission limit. That is, a line should be either congested for both values of the transmission limit or for none. In the later case, all the LMP values should be equal. Similarly, SSNetLMPSD("all",[3,1,0.1]); calculates the LMPs assuming that the generation is fixed and the demand is flexible. SSNetLMPSGD("all",) calculates the LMPs assuming that both generation and demand are flexible. The same transmission congestion considerations should be observed as in the previous two functions.

Function Name	Required Arguments	Optional Arguments	Return Values
SSNetNRPF	1) net name	2) [Pm,Qm,Iter]	1) [rank,Pm,Qm,Iter]
SSNetDCOPFFlexG	1) net name		1) cost?
SSNetDCOPFFlexD	1) net name		1) cost?
SSNetDCOPFFlexGD	1) net name		1) cost?
SSNetDF	1) net name		1) distribution factors
SSNetDCFL	1) net name		1) DC power flows 2) source buses 3) destination buses
SSNetMakeSens	1) net name		1) 0?
SSNetDPgDT	1) net name		1) $\frac{\partial P_g}{\partial \theta}$ matrix
SSNetDPgDVg	1) net name		1) $\frac{\partial P_g}{\partial V_g}$ matrix
SSNetDPgDVl	1) net name		1) $\frac{\partial P_g}{\partial V_l}$ matrix
SSNetDPIDT	1) net name		1) $\frac{\partial P_l}{\partial \theta}$ matrix
SSNetDPIDVg	1) net name		1) $\frac{\partial P_l}{\partial V_g}$ matrix
SSNetDPIDVl	1) net name		1) $\frac{\partial P_l}{\partial V_l}$ matrix
SSNetDQlDT	1) net name		1) $\frac{\partial Q_l}{\partial \theta}$ matrix
SSNetDQlDVg	1) net name		1) $\frac{\partial Q_l}{\partial V_g}$ matrix
SSNetDQlDVl	1) net name		1) $\frac{\partial Q_l}{\partial V_l}$ matrix
MatrixLMPSG	1) net name 2) row vector with two adjacent nodes and increment		1) bus indexes and LMPS optimizing generation
MatrixLMPSD	1) net name 2) row vector with two adjacent nodes and increment		1) bus indexes and LMPS optimizing demand
MatrixLMPSGD	1) net name 2) row vector with two adjacent nodes and increment		1) bus indexes and LMPS optimizing generation and demand

Table 2.6: IPSYS power system algorithms calling options and return values

2.5 Input/Output and Miscellaneous Functions

The API framework used for IPSYS can easily provide any functionality the native C/C++ programming language provides. IPSYS implements screen and file input/output, internal data structures listing, and some additional miscellaneous functions.

As demonstrated throughout the previous examples, results can be displayed using built in `printf` function. Similarly, `fprintf` function is used to write to a file rather than to the screen. Both of these functions are similar to C functions with the same names. Additionally, `printf` can print out a single matrix using given format applied to each matrix entry. Format string is just the regular C `printf` format string. Printing to a file is done using `fprintf` which can also print a single matrix like `printf`. `fprintf` takes a file name as an argument rather than a file descriptor. To be able to write to a file, file must first be opened with `fopen` function which does not return file descriptor but makes it globally visible using the file name. After writing to a file, the file should be closed with `fclose`. Writing a matrix of random numbers between 0 and 1 in Matlab format to a file could be performed as:

```
ipsys> srand();
ipsys> fopen("rand5x5.m","w");
ipsys> fprintf("rand5x5.m","%7.3f", rand(5,5)/RAND_MAX);
ipsys> fclose("rand5x5.m");
```

resulting in `rand5x5.m` file:

```
$ more rand5x5.m
[
  0.847  0.033  0.614  0.009  0.236;
  0.344  0.085  0.877  0.334  0.322;
  0.203  0.757  0.817  0.044  0.927;
  0.707  0.197  0.395  0.833  0.822;
  0.240  0.449  0.085  0.933  0.971
]
```

Table 2.7 lists I/O functions and some miscellaneous functions. Functions `lsConsts`, `lsVars`, `lsFuncs`, and `lsMem` list the available constants, variables

Function Name	Required Arguments	Optional Arguments	Return Value
printf	1) format string	2) one or more variables	1) number of chars printed
fprintf	1) file name 2) format string	3) one or more variables	1) number of chars printed
fopen	1) file name 2) mode string		1) success (1) or failure (0)
fclose	1) file name		1) success (1) or failure (0)
lsConsts			1) number of conststnt
lsVars			1) number of variables
lsFuncs			1) number of functions
lsMem			1) number of objects
clsVars		1) variable list	1) number of deleted variables
clsFuncs		1) functions list	1) number of deleted functions
sleep		1) milliseconds	1) milliseconds sleeping

Table 2.7: Input/Output and Miscellaneous Functions

used, scripting functions defined, and the number of objects in memory. `clsVars` and `clsFuncs` can be used to clear variables or functions from IPSYS memory; if they are used without any arguments, all of the variables or functions are cleared.

Sometimes, when IPSYS CLI controls the GUI display from a loop, it is needed to slow down the display of the results on the GUI network. For this purpose, `sleep` function is implemented which takes the number of milliseconds during which the execution should be paused.

Chapter 3

Matlab Interface

3.1 Introduction

Matlab Interactive Power Systems Simulator (MIPSYS) consists of algorithms described in 2.4. MIPSYS uses an older version of IPSYS algorithms and its further development has been abandoned in favor of GUI interface and its ability to export GIPSYS networks to Matlab environment. All of the functionality provided by ipsys is also available through Matlab. Although there are other packages which have similar functionality, all of them are rather difficult to use and integrate with the rest of Matlab. Matlab interface to ipsys algorithms is designed with user friendliness in mind more than efficiency. Both ipsys and Matlab interface are designed using object oriented approach. While ipsys defines system as an object and operates on it, Matlab passes an object around from a function to a function. Due to Matlab design, all the data is passed by value. This could result in lots of data copying between function calls. Rather than using lots of static data and be able to analyze a single system at the time, the performance penalty is accepted for the sake of flexibility and user friendliness. The main interface design decisions were to use array of structures to define a network in Matlab and to use pairs of Matlab/C++ mex functions to interface Matlab functions with regular C++ functions. Since Matlab does not use namespaces, a convention is introduced where Matlab files in this package start with pl_, C++ mex interface files with cpp_ and regular C++ functions not used in Matlab are the same as before. Results using Matlab and ipsys should be exactly the same since they are using the same code.

3.2 Matlab Interface Data

Matlab maps data read from a PTI23 file into a structure consisting of arrays of network objects. That is, a net object has an array of buses, generators, branches, etc. and each element of an array contains all of the data defined in the PTI23 file for that particular element. For example, a six bus network is defined in b6.p23 input file and its main structure in Matlab is given as: while, for example, array of buses is given as: The convention used for

Field Δ	Value
Title1	'0 100.00 / Wed Feb 9 21:12:42 2005'
Title2	'GIPSYS'
Title3	"
IC	0
SBASE	100
bus	<1x6 struct>
gen	<1x6 struct>
branch	<1x9 struct>
swing	1
pvlndx	[2;5]
pqlndx	[3;4;6]

Figure 3.1: Six Bus Data Structure

naming structure elements is that all the elements read in from the input file are capitalized and any additional data is named with small letters. User is free to change already existing elements or add new data. Description of the capitalized elements can be found in Appendix B. Small letter variable naming should be obvious and is listed in the following tables for network elements actually used in this software: The mandatory data that the cpp-functions expect to be present in the network structure is the data read from the PTI input file. There can also be additional information needed for a particular algorithm. This additional data can include various cost

Field ▲	Value
I	6
IDE	3
PL	0
QL	0
GL	0
BL	0
AREA	1
VM	1
VA	0
NAME	"Bus 6 "
BASKV	0
ZONE	1
i	1
qmax	29997
qmin	-29997
pg	300
qg	60
gens	[4;5;6]
vaub	45
valb	-45
vmub	1.05
vmlb	0.95

Figure 3.2: Bus 6 Data Structure

functions but user can freely keep any appropriate information within the data structures. Currently, in addition to the bus record discussed above, this software uses generator and branch records from the input PTI input file and cost function files. Since this is work in development, there are possibilities to define data not used by any algorithms yet. This will be discussed in the function calling section. Table 3.1 lists elements not read from the PTI input file but used in currently implemented algorithms. While ipsys scripting language used special functions to manipulate network data, Matlab allows direct access to all of the network structures. As with all Matlab programming, vectorizing should be used as much as possible to improve the performance.

	Additional network data
swing	Internal index of the swing bus
pvIndx	Internal indexes of the PV buses
pqIndx	Internal indexes of the PQ buses
	Additional bus data
i	Internal numbering index
qmax	Maximum available VAR at the bus
qmin	Minimum available VAR at the bus
pg	Real generation at the bus
qg	Reactive generation at the bus
vaub	Upper voltage phase limit in degrees
valb	Lower voltage phase limit in degrees
vmub	Upper voltage pu magnitude limit
vmlb	Lower voltage pu magnitude limit
plt	Upper load limit at the bus
plb	Lower load limit at the bus
	Additional generator data
i	Internal generator index
ireg	Internal index of a controlled bus
pgcost	Coefficients of a real power cost polynomial
	Additional branch data
i	Internal "from bus" index
j	Internal "to bus" index

Table 3.1: Additional Data

3.3 Matlab Interface Functions

Matlab interface to ipsys back end algorithms provides data input/output and calculation functions. The input/output functions read and write data from PTI23 network and cost polynomial files. Any subsequent reading, modification, or deletion of the data is done through Matlab. The included algorithms are the same ones as in ipsys and should give exactly the same results. This section describes all of the interface function and similar descriptions can be viewed from Matlab using help function.

The design behind the Matlab interface uses a two step approach. User has access to pl_ functions which in turn call cpp_ functions. This way, a user has a two chances to process the input and/or output data, once in Matlab pl_ file and in cpp_ file before the data is passed to back-end functions. This should allow considerable data control. Even without changing pl_ files, a complete reconfiguration of a network can be done from Matlab allowing a wide range of experiments to be performed. Whenever a back-end function is called through pl_/cpp_ calling mechanism, the entire network is passed to the back-end functions and treated as a brand new study case. In Matlab, it is very difficult if not impossible to pass data to dynamically linked functions by reference. This causes performance penalty but in this case it also ensures that a network is always treated as completely new one.

There is a potential problem with functions returning the Jacobian and admittance matrix. The problems is the internal bus and branch indexing. If a computation depends on these two matrices and their ordering, order the buses in an increasing order starting with the slack bus in the PTI23 input file. In that case back-end internal ordering will be the same as in the network structure formed by Matlab input routine. The sensitivity and clustered matrices are not a problem contain indexes in the first row and column as they do in ipsys. Table 3.2 contains the list of all the functions. Use help function in Matlab for the detailed description of input and output parameters and the examples in chapter 6 for a quick start.

Function Name	Input	Output
Data I/O Functions		
pl_pti23Net	PTI 23 file name	Network structure
pl_printPGCostStr	Net structure	P_g cost functions string
pl_printPLCostStr	Net structure	P_l cost functions string
pl_printRawStr	Net structure	PTI 23 string
pl_NetFlows	Net structure	Net flows string
Power Flow Algorithms		
pl_Admitt	Net structure	Net admittance matrix
pl_DFFlows	Net structure	distribution factors flow
pl_DFfactors	Net structure	distribution factors
pl_DPgDT	Net Structure	$\frac{\partial P_g}{\partial \theta}$ matrix
pl_DPgDVg	Net structure	$\frac{\partial P_g}{\partial V_g}$ matrix
pl_DPgDVI	Net structure	$\frac{\partial P_g}{\partial V_l}$ matrix
pl_DPIDT	Net structure	$\frac{\partial P_l}{\partial \theta}$ matrix
pl_DPIDVg	Net structure	$\frac{\partial P_l}{\partial V_g}$ matrix
pl_DPIDVI	Net structure	$\frac{\partial P_l}{\partial V_l}$ matrix
pl_DQIDT	Net structure	$\frac{\partial Q_l}{\partial \theta}$ matrix
pl_DQIDVg	Net structure	$\frac{\partial Q_l}{\partial V_g}$ matrix
pl_DQIDVI	Net structure	$\frac{\partial Q_l}{\partial V_l}$ matrix
pl_GSPF	Net structure	Gauss-Seidel power flow
pl_Jacobian	Net structure	Net Jacobian
pl_NRPF	Net structure	Newton-Raphson power flow
OPF Algorithms		
pl_DCOPFFlexD	Net structure	DCOPF with flexible P_d
pl_DCOPFFlexG	Net structure	DCOPF with flexible P_g
pl_DCOPFFlexGD	Net structure	DCOPF with flexible P_g and P_d
pl_LMPSD	Net structure, node connected to ref.	LMPS with flexible P_d
pl_LMPSG	node, ref. node, increment	LMPS with flexible P_g
pl_LMPSGD	same as pl_LMPSD	LMPS with flexible P_g and P_d
Miscellaneous Functins		
pl_MClust	Real matrix	Clustered matrix
pl_netUpdate	Net structure	Updates network variables

Table 3.2: Matlab Interface Functions

Chapter 4

GIPSYS Interface

GIPSYS provides a GUI interface to all of the IPSYS functionality. However, GIPSYS GUI editor can be used to edit only a single network at the time. GIPSYS consists of IPSYS CLI interface, script editor, and GUI power systems network editor. IPSYS CLI interface is the same CLI interpreter described in chapter 2 with one difference. When entering multi line data or commands, user must use SHIFT+RETURN or ENTER key to end each line except the last one which is ended with the usual RETURN key. This requirement is due to unexpected parser design restrictions but it will also allow for much better error handling and reporting. The script (plain text) and GUI editors are almost independent modules or libraries developed independently. The framework's modular design makes addition of new modules and interfaces quite easy. GIPSYS functionality is achieved through a number of menu entries and the CLI interface with the rest of IPSYS. GIPSYS GUI design follows standard GUI interface as much as possible including file opening, saving, closing, and exporting to other formats and/or graphics. Edit menu includes adding new system elements such as buses, branches, etc. but copying, cutting, and pasting is not implemented yet. Run menu allows running the most common IPSYS algorithms. View menu provides zooming in/out, snap-on, and choosing element label. Figure 4.1 shows all three parts of the graphical user interface.

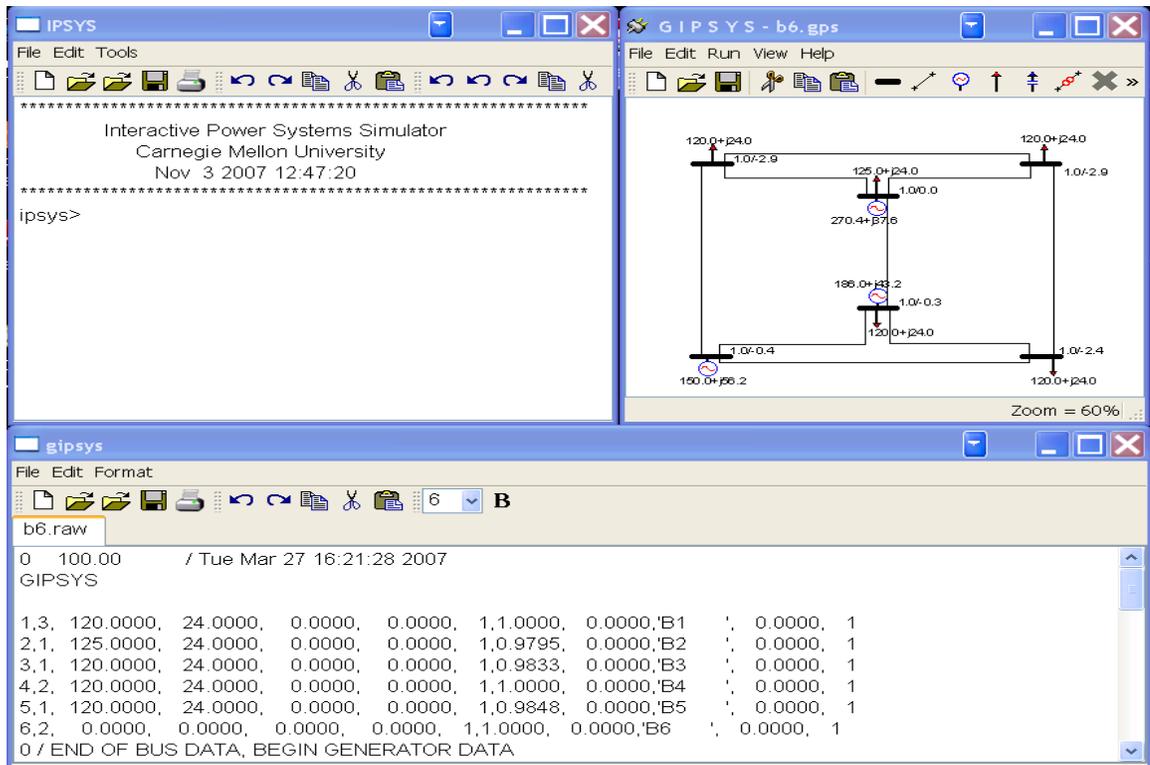


Figure 4.1: GIPSYS windows

4.1 Entering a New Network

At the start up, GIPSYS presents user with the CLI command window from which text script and GUI editors can be opened. Text editor can be used to open multiple text scripts at the same time while the GUI editor can be used to edit a single network at the time. This network can also be accessed from the CLI window using net name "gnet". The network editor is started and closed from the main window with Tools→Start GUI and Tools→Close GUI. To edit or start a new scrip use File→Open Script or File→New Script.

A new network can be entered with File→New, CTRL+N, or clicking on New icon on the network editor tool bar. Once the user is presented with the blank GIPSYS screen, network elements and connections can be entered by first clicking on the element type on the tool bar or Edit menu and then clicking at the desired location on the screen. Elements can be arranged

on the screen by dragging them around with the mouse. Two buses can be connected with a branch by clicking on the branch edit menu entry and then clicking on from and to bus in the network. A branch can be broken into segments by first clicking on the branch to select it and then SHIFT+RIGHT CLICK at the location of the desired joint. After the branch has one or more joints, they can be dragged around with the mouse to arrange branch path in a visually pleasing way. Elements can be attached to buses by choosing an element and then clicking on the bus with which the element is associated. Typical start of a new network is shown in Figure 4.2. All system elements

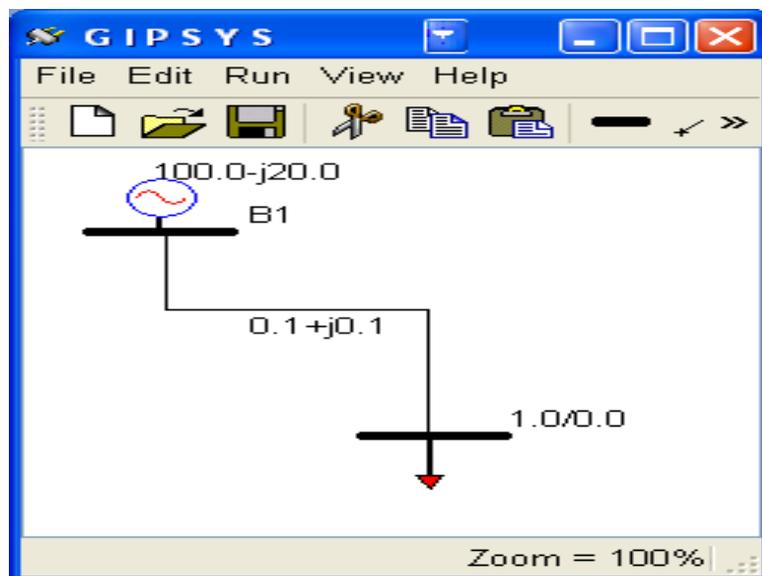


Figure 4.2: New GIPSYS defined network

can have its typical measurements as a label and buses can have custom labels as well. This is done by using right mouse click on an element. Element parameters dialog can be accessed by pressing right mouse button on an element and choosing Properties from the pop up menu or by using left double click. Edit→Preferences defines the initial label option for each element. GIPSYS GUI follows standard GUI design and users can expect similar features as in other applications with GUI interface. Network can be saved by using File→Save As or clicking on the standard save icon on the tool bar. It is users responsibility to provide one and only one slack bus for each network.

A network entered in the GUI editor window does not have to be saved to be able to use it. Of course, the changes will not be available for the next session unless they are saved on the hard drive. GUI editor can export the edited network to PTI23 format files and two additional files containing demand and generator cost functions. These files can be used with non-GUI IPSYS interface described in chapter 2 or to use it with another package that understands the PTI23 format. GUI editor can also export the network as a picture for inclusion in publications and to Matpower format. The export functions can be accessed with File→Export menu entry.

4.2 Running IPSYS Algorithms

Once a network is opened, it can be used either to run common algorithms from the GUI editor interface or from the GUI CLI interface. The text interface provides much finer control over the execution of the algorithms than the GUI interface can. Whatever is done through the GUI or command window is reflected in both environments. For example if the Newton-Raphson power flow is run from the command window by issuing NRPF() command, the results are reflected in the GUI window after the power flow is executed. Similarly, if the Newton-Raphson power flow is executed from the GUI menu, the IPSYS network object is modified accordingly. This setup allows for interesting and flexible visual demonstrations of how network might evolve. For example, if loads are modified and power flow is run from within a loop, voltage level changes can be observed visually on the GUI display using labels. Pause function can be used to slow down the execution to be able to observe the output. To preserve data consistency during execution, GUI window is disabled while CLI is executing a command and similarly, CLI window is disabled while GUI command is executing.

Since the entire internal representation of the network (GUI and CLI) is updated with every change, network can be continuously and programmatically changed and manipulated through functions and scripts. The disadvantage of this design approach is that the network can be, and is frequently during editing, in an invalid state, for example slack bus is missing, existence of isolated buses, etc. This is not a problem as long as an operation is not performed that requires a well defined network. Various commercial packages address this by separating editing and running with Edit and Run

mode. This is a good solution but limits what can be done using scripts. Accidentally, these packages also have limited scripting capabilities.

Chapter 5

IPSYS Examples

This chapter shows some examples how some of the major IPSYS features introduced in the previous chapter can be used. The first section illustrates linear algebra capabilities such as matrix input, matrix manipulation, general purpose functions, and linear algebra algorithms available. The second section demonstrates input/output facilities. The rest of the examples deal with power systems manipulation and analysis. Implementation details and the theory behind this algorithms can be found in the appendices. All of the examples will use the following data files:

1. b3.raw is three bus PTI raw data file
2. b3.sup generator cost curves
3. b3.dmd demand cost curves data
4. b6.raw six bus PTI raw data file
5. b6.sup generator cost curves
6. b6.dmd demand cost curves

and should be included with this manual. The examples emphasize power systems features more than how to use IPSYS interface, which should be intuitive enough.

All of the algorithms are implemented using dense matrix methods from [IMSL](#) library [3] version 6.0 academic edition, and [Template Numerical Toolkit \(TNT\)](#) [5].

5.1 Linear Algebra

This section demonstrates general numerical and linear algebra ipsys features.

5.1.1 Checking Rank and Condition Number

This example shows how a matrix can be constructed element by element and checked for the condition number and rank:

```
ipsys> h = Matrix(5,5,0);
ipsys> for(i = 1; i <= Rows(h); i = i+1){
    for(j = 1; j <= Cols(h); j = j+1){
        h(i,j) = 1/(i+j-1);
    }
}
ipsys> printf("\n%g\n", Cond(h));

476607
ipsys> printf("\n%g\n", Rank(h));

5
```

5.1.2 Sensitivity Matrix Extraction

In the power systems operations it is important to be able to extract parts of a matrix. For example, some of the sensitivity matrices that ipsys calculates can be extracted from the Jacobian matrix. Here is an example of how $\frac{\partial Q_i}{\partial \theta}$ can be extracted from the Jacobian matrix:

```
ipsys> SSNet("b6", "b6.raw", "", "");
ipsys> SSNetNRPF("b6", [0.000001, 0.000001, 50]);
ipsys> jac = SSNetJac("b6");
ipsys> dqldt = jac(Range(6, Rows(jac)), Range(1, 5));
ipsys> SSNetMakeSens("b6");
ipsys> printf("%g  ", SSNetDQ1DT("b6"));
[
-6.0712  0.0268085  0  0  0.877069  ;
-0.0268085  -1.2  0  0.190515  0  ;
0  -0.190515  0.725736  -1.2  0.664779
```

```

]
ipsys> printf("%g  ", dqldt);
dqldt = [
-6.0712  0.0268057  0  0  0.877071  ;
-0.0268057  -1.20001  0  0.190516  0  ;
0  -0.190516  0.725739  -1.20001  0.664782
]

```

According to the above example, SSNetDQIDT function is not really necessary but is provided for user's convenience.

5.1.3 Matrix Decomposition and Clustering

Epsilon decomposition and clustering can be used replacing one large network with a few smaller, loosely coupled networks [8]. IPSYS provides two, almost equivalent function for this task. The first one, Clust(mat,eps) implements a general network clustering algorithm described in [6] which takes a weighted undirectional graph and a weight threshold below which connections are ignored. This function returns a clustered matrix resulting from ignoring small, below eps threshold, connections and two vectors of the original matrix coordinates. Figure 5.1 illustrates this approach to system reduction. The second function, EDec(mat,eps), calculates the same decomposition but it returns a matrix with number of rows equal to the number of clusters where each row contains row indexes of the original matrix. These two functions give equivalent results except possibly different permutations within a cluster. EDec() combined with SSNetJac(), and SSNetNRPF() was used in [8] to decompose and analyze the standard IEEE test network RTS-1996.

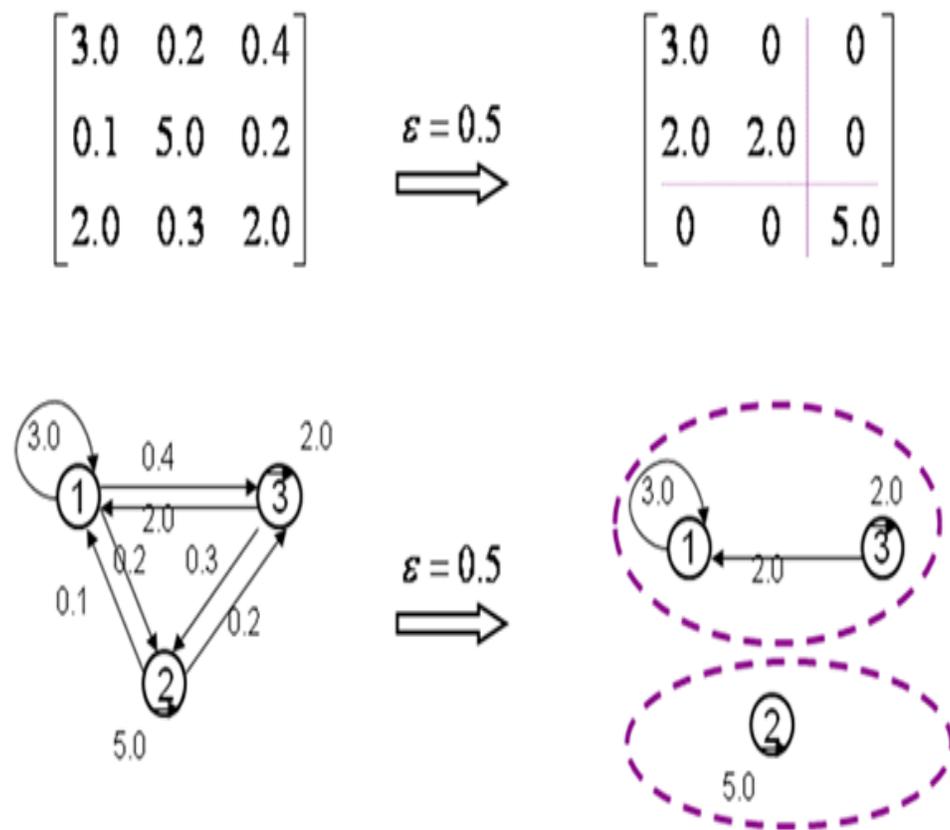


Figure 5.1: Network clustering

5.2 Power Flow Examples

5.2.1 Example 1

The six bus network shown in figure 5.2 is used for the next 4 examples. The examples start with a simple one and progressively become more complex. The first example is just a power flow runs for a couple of different operating points. First, calculate the generation cost for the first operating point:

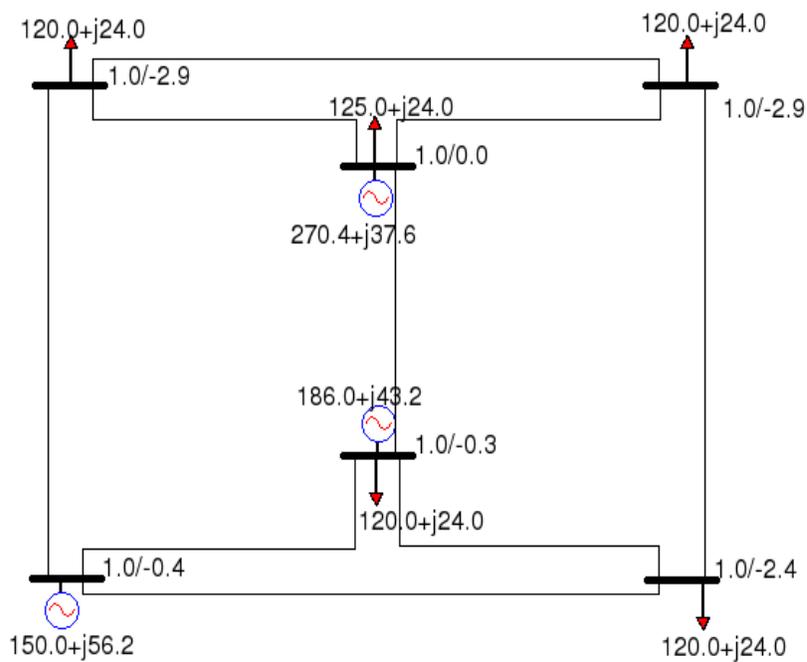


Figure 5.2: Six bus system

```
ipsys> SSNet("b6", "b6.raw", "b6.sup", "b6.dmd");  
ipsys> SSNetNRPF("b6");  
ipsys> Pg4 = SSNetGen("b6", 4, "'1 '");  
ipsys> Pg6 = SSNetGen("b6", 6, "'1 '");
```

```

ipsys> Pg1 = SSNetGen("b6",1,"'1 '");
ipsys> GenCost = SSNetCost("b6");
ipsys> printf("Pg1 = %7.2f\tPg4 = %7.2f\tPg6 = %7.2f\tGenCost = %7.2f\n",Pg1,Pg4
,Pg6,GenCost);
Pg1 = 272.20    Pg4 = 186.36    Pg6 = 148.03    GenCost = 580.91

```

Now, change the generator output of the generator on bus four and calculate the generation cost again:

```

ipsys> SSNetGen("b6",4,"'1 '",150);
ipsys> SSNetNRPF("b6");
ipsys> Pg1 = SSNetGen("b6",1,"'1 '");
ipsys> Pg4 = SSNetGen("b6",4,"'1 '");
ipsys> Pg6 = SSNetGen("b6",6,"'1 '");
ipsys> GenCost = SSNetCost("b6");
ipsys> printf("Pg1 = %7.2f\tPg4 = %7.2f\tPg6 = %7.2f\tGenCost = %7.2f\n",Pg1,Pg4
,Pg6,GenCost);
Pg1 = 308.91    Pg4 = 150.00    Pg6 = 148.03    GenCost = 585.23

```

Newton-Raphson Power Flow solution for the second operating point is:

```

=====
                        Solution Output
=====

```

Input data file:

```

0    100.00          / Tue Mar 27 16:21:28 2007
GIPSYS

```

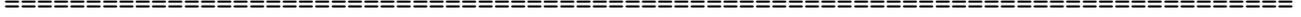
From Bus	Volt. Mag.	Volt. Angle	Mw Load	Mvar Load	Mw Gen.	Mvar Gen.
1	1.00000	0.00000	120.00	24.00	308.91	0.00

2	39.73	-19.09				
3	113.13	31.09				
4	36.05	0.33				
2	0.98112	-3.43660	125.00	24.00	0.00	0.00
1	-37.78	21.03				
3	-5.00	-9.71				
6	-82.22	-35.32				
3	0.98608	-3.28854	120.00	24.00	0.00	0.00
1	-113.13	-24.21				
2	5.00	9.78				
5	-11.87	-9.57				
4	1.00000	-1.03295	120.00	24.00	150.00	0.00
1	-36.05	0.33				
5	65.97	19.20				
6	0.08	0.00				
5	0.99095	-2.94059	120.00	24.00	0.00	0.00
3	11.87	9.69				
4	-65.97	-16.84				
6	-65.89	-16.84				
6	1.00000	-1.03526	0.00	0.00	148.03	0.00
2	82.22	39.47				
4	-0.08	0.00				
5	65.89	19.20				

Mw gen = 606.942
Mvar gen = 0.000
Mw load = 605.000
Mvar load = 120.000
Total I2R Mw losses = 1.942
Total I2X Mvar losses = 18.532
Generation Cost = 585.227777

=====

End of Output



5.3 DC Optimal Power Flow - Flexible Generation

In the previous example, generation cost was calculated for a couple of operating points. In this example, a cost dependency on the generators on buses four and six will be shown. The same network 5.2 is used for this example. Bus number one is the slack bus and its generation cost is accounted for but it is not shown in the graph due to dimensional limitations. Both generators on buses four and six are varied between 50MW and 300MW. The script file used to generate the graph data is:

```
SSNet("b6", "b6.raw", "b6.sup", "");
fopen("b6.dat", "w");

for(pg4 = 50; pg4 <= 300; pg4 = pg4+10){
  for(pg6 = 50; pg6 <= 300; pg6 = pg6+10){
    SSNetGen("b6", 4, "'1 '", pg4);
    SSNetGen("b6", 6, "'1 '", pg6);
    SSNetNRPF("b6");
    fprintf("b6.dat", "%g\t%g\t%g\n", pg4, pg6, SSNetCost("b6"));
  }
  fprintf("b6.dat", "\n");
}
fclose("b6.dat");
```

The cost graph is shown in figure 5.3. A user can easily generate such graphs to get a feel for how cost depends on a couple of generators and maybe estimate the minimal cost operating point. If there is a large number of generators that can be used to minimize the generation cost, IPSYS DCOPFFlexG function can be used instead and for the same network it is given by:

```
ipsys> SSNet("b6", "b6.raw", "b6.sup", "");
ipsys> SSNetDCOPFFlexG("b6");
```

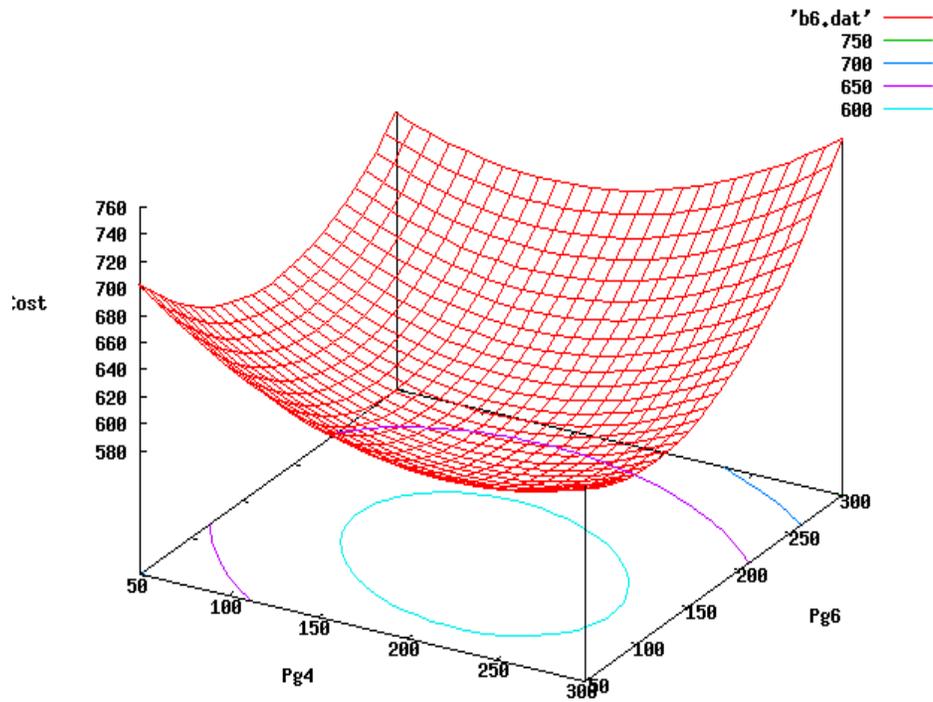


Figure 5.3: Production cost profile

The minimal cost point found using DCOPFFlexG() function:

```
=====
                        Solution Output
=====
```

Input data file:

```
0 100.00 / Tue Mar 27 16:21:28 2007
GIPSYS
```

```
From Volt. Volt. Mw Mvar Mw Mvar
```

Bus	Mag.	Angle	Load	Load	Gen.	Gen.
To	Mw	Mvar				
Bus	Flow	Flow				
1	1.00000	0.00000	120.00	24.00	305.00	59.02
2	2.14	8.74				
3	17.74	21.73				
4	-134.80	4.55				
2	0.98914	0.38268	125.00	24.00	0.00	0.00
1	-2.06	-8.66				
3	30.62	0.18				
6	-153.56	-15.51				
3	0.98918	-0.51387	120.00	24.00	0.00	0.00
1	-17.74	-21.34				
2	-30.62	0.30				
5	-71.64	-2.96				
4	1.00000	3.86468	120.00	24.00	150.00	47.74
1	134.80	4.55				
5	79.06	18.91				
6	-33.86	0.29				
5	0.99133	1.57948	120.00	24.00	0.00	0.00
3	71.64	5.59				
4	-79.06	-15.60				
6	-112.58	-13.98				
6	1.00000	4.83466	0.00	0.00	150.00	48.50
2	153.56	27.68				
4	33.86	0.29				
5	112.58	20.53				

Mw gen = 605.000

```

Mvar gen           = 155.262
Mw load            = 605.000
Mvar load          = 120.000
Total I2R Mw losses = 0.081
Total I2X Mvar losses = 35.275
Generation Cost    = 583.025000

```

```

=====
                          End of Output
=====

```

This is the DC optimal power flow with flexible generation minimizing production cost. Since it uses the DC approximation of the AC network, the AC power flow, SSNetNRPF, should be run at this point. The power flows print out shows a small difference in the cost:

```

=====
                          Solution Output
=====

```

Input data file:

```

0 100.00 / Tue Mar 27 16:21:28 2007
GIPSYS

```

From Bus	Volt. Mag.	Volt. Angle	Mw Load	Mvar Load	Mw Gen.	Mvar Gen.
1	1.00000	0.00000	120.00	24.00	306.91	36.41
2	39.41	-18.87				
3	112.40	30.98				
4	35.10	0.31				
2	0.98120	-3.40520	125.00	24.00	0.00	0.00
1	-37.50	20.78				

3	-4.66	-9.64				
6	-82.84	-35.14				
3	0.98611	-3.26720	120.00	24.00	0.00	0.00
1	-112.40	-24.18				
2	4.66	9.70				
5	-12.26	-9.51				
4	1.00000	-1.00557	120.00	24.00	150.00	43.49
1	-35.10	0.31				
5	65.79	19.18				
6	-0.69	0.00				
5	0.99096	-2.90781	120.00	24.00	0.00	0.00
3	12.26	9.64				
4	-65.79	-16.83				
6	-66.47	-16.81				
6	1.00000	-0.98583	0.00	0.00	150.00	58.55
2	82.84	39.35				
4	0.69	0.00				
5	66.47	19.20				

Mw gen	=	606.908
Mvar gen	=	138.444
Mw load	=	605.000
Mvar load	=	120.000
Total I2R Mw losses	=	1.909
Total I2X Mvar losses	=	18.452
Generation Cost	=	585.146048

=====
 End of Output
 =====

The AC power flow should also be used after DCOPF to check the operating point feasibility by checking the SSNetNRPF return values (Jacobian rank, number of iterations, and P/Q mismatches).

5.4 DC Optimal Power Flow - Flexible Load

If there is demand control implemented, there should be a way to account for the demand flexibility. This Example shows such a hypothetical situation. DCOPFFlexD() example uses the same b6.raw as the above example. Ipsys script is very similar to the previous example:

```

ipsys> SSNet("b6","b6.raw","b6.sup","b6.dmd");
ipsys> SSNetDCOPFFlexD("b6");
ipsys> SSNetPrintFlows("b6");

```

and the DCOPFFlexD() result is:

```

=====
                        Solution Output
=====

Input data file:

0   100.00           / Tue Mar 27 16:21:28 2007
GIPSYS

From  Volt.      Volt.      Mw      Mvar      Mw      Mvar
Bus  Mag.        Angle     Load    Load     Gen.    Gen.
-----
To    Mw          Mvar
Bus  Flow        Flow
-----

      1  1.00000  0.00000  64.39   24.00    0.00    0.00
      2   10.25   10.25
      3    0.00   33.40
      4    0.00    0.00

      2  0.97950  0.00000  10.00   24.00    0.00    0.00
      1  -10.04   -10.04
      3    0.00   -7.44
      6    0.00  -40.16

```

3	0.98330	0.00000	50.00	24.00	0.00	0.00
1	0.00	-32.84				
2	0.00	7.47				
5	0.00	-2.95				
4	1.00000	0.00000	200.00	24.00	186.36	24.69
1	0.00	0.00				
5	0.00	30.40				
6	0.00	0.00				
5	0.98480	0.00000	10.00	24.00	0.00	0.00
3	0.00	2.95				
4	0.00	-29.94				
6	0.00	-29.94				
6	1.00000	0.00000	0.00	0.00	148.03	76.96
2	0.00	41.00				
4	0.00	0.00				
5	0.00	30.40				

Mw gen = 334.394
Mvar gen = 101.646
Mw load = 334.394
Mvar load = 120.000
Total I2R Mw losses = 0.210
Total I2X Mvar losses = 2.566
Generation Cost = 370.716924

=====
End of Output
=====

5.5 DC Optimal Power Flow - Flexible Generation and Load

As an example of optimal generation and demand calculations, calculations of [1] on pages 157-158 will be done by hand, using IPSYS and compared with the results in the above paper. The four bus network under consideration is shown in figure 6.1. Power flow shows that flow $P_{G1 \rightarrow L1}$ exceeds the branch maximum flow $P_{G1 \rightarrow L1}^{max}$ given as 3.7pu. Using this fact as a binding constraint and setting up the Lagrange equation for constrained optimization, the following set of equations results:

$$\begin{bmatrix} 2 & 0 & 0 & 0 & 0 & 0 & 0 & -1 & 0 & 0 & 0 & 0 \\ 0 & 4 & 0 & 0 & 0 & 0 & 0 & 0 & -1 & 0 & 0 & 0 \\ 0 & 0 & 20 & 0 & 0 & 0 & 0 & 0 & 0 & -1 & 0 & 0 \\ 0 & 0 & 0 & 24 & 0 & 0 & 0 & 0 & 0 & 0 & -1 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & -1 & 3 & 1 & 1 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & -1 & -1 & -3 & 1 & -1 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & -1 & 1 & -2 & 0 \\ -1 & 0 & 0 & 0 & -1 & -1 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & -1 & 0 & 0 & 3 & -1 & -1 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & -1 & 0 & 1 & -3 & 1 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & -1 & 1 & 1 & -2 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & -1 & 0 & 0 & 0 & 0 & 0 & 0 \end{bmatrix} z = \begin{bmatrix} -1 \\ -0.5 \\ 94.1667 \\ 158.1667 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 3.7 \end{bmatrix}$$

with the following solution:

$$z = [5.45 \quad 4.07 \quad 3.70 \quad 5.82 \quad -1.75 \quad -3.70 \quad -5.63 \quad 11.91 \quad 16.79 \quad -20.04 \quad -18.42 \quad 13.02]'$$

DCOPFFlexGD() function performs the DC optimization with respect to both generation and demand accounting for the flow constraint from bus number 1 to bus number 3:

```
ipsys> SSNet("all","allen.raw","allen.sup","allen.dmd");
ipsys> SSNetDCOPFFlexGD("all");
ipsys> SSNetNRPF("all");
```

DCOPFFlexGD() output is as the following:

=====

Solution Output

Input data file:

0 100.00 / Tue Oct 25 16:18:59 2005
 GIPSYS

From Bus	Volt. Mag.	Volt. Angle	Mw Load	Mvar Load	Mw Gen.	Mvar Gen.
To Bus	Mw Flow	Mvar Flow				
1	1.00000	0.00000	0.00	0.00	5.46	0.15
2	1.76	0.02				
3	3.70	0.13				
2	1.00000	-1.00607	0.00	0.00	4.07	0.25
1	-1.76	0.02				
4	3.88	0.15				
3	1.95	0.08				
3	0.99939	-2.12135	3.71	0.00	0.00	0.00
1	-3.70	0.01				
2	-1.95	-0.04				
4	1.94	0.04				
4	0.99922	-3.23376	5.82	0.00	0.00	0.00
2	-3.88	-0.00				
3	-1.94	0.00				

Mw gen = 9.529
 Mvar gen = 0.394
 Mw load = 9.529
 Mvar load = 0.000

Total I2R Mw losses = 0.000
 Total I2X Mvar losses = 0.394
 Generation Cost = 71.936386

=====
 End of Output
 =====

IPSYS calculations agree closely with the hand calculations above and the results reported in [1]:

	hand calculation	paper reported	IPSYS
$G_1(MW)$	5.4552	5.4553	5.45517
$G_2(MW)$	4.0734	4.0734	4.07342
$L_1(MW)$	3.7059	3.7059	3.70587
$L_2(MW)$	5.8227	5.8227	5.82273
$G_1(\$)$	11.9104	11.9106	11.91
$G_2(\$)$	16.7937	16.7936	16.79
$L_1(\$)$	20.0492	20.0487	20.05
$L_2(\$)$	18.4214	18.4219	18.42
$F_{12}(MW)$	3.70000	3.70000	3.70
$F_{12}(\$)$	13.0222		13.02

Table 5.1: Optimal welfare calculations

Although the numbers are almost exactly the same, [1] discusses the market setup as a multilateral transaction while the above is the poolco formulation. Nevertheless, the both formulations find the same optimal point.

Chapter 6

Matlab Examples

In this chapter, a few examples are used to demonstrate the main Matlab interface features. For the demonstration purposes, a four bus network [6.1](#), with associated real power cost functions, and real power demand functions is used.

6.1 Matlab Input Output

Matlab and ipsys use the same input file formats. There are currently three different input files that can be used by Matlab to define a power systems network. The only mandatory input file is the network definition file in PTI23 format. The other two files provide the real power generation cost and the load demand. The internal functions do limited checking of compatibility of these three files and user should pay attention that the real power limits in PTI23 file match the real power limits in defined by the cost functions. Also, PTI23 allows only a single load per bus. To allow for a possibility of multiple loads per bus, the demand file should use the default '1' as the load ID until a multi load options is implemented. Even in the currently used format, there can be multiple generators on a single bus and they should be named as described by PTI23 format in [Appendix B](#).

`pl_pti23Net` is the Matlab function used to read both network description and cost functions. It takes up to five arguments of which only the first one is required and returns the net structure. The first argument is the name of the PTI23 input file, the second argument is the P_g cost functions file, the

third argument is the Q_g costs file, the fourth is P_l costs and the fifth is the Q_l demand curves file. Of this five parameters, only the first one is required and Q_g and Q_l are to be used in the future. If an argument must be entered but unused, use an empty matrix []. For example, the following will read in the data for the system in the Figure 6.1:

```
>> b4 = pl_pti23Net('allen.raw','allen.sup',[],'allen.dmd')
```

```
b4 =
```

```
Title1: '0    100.00          / Tue Oct 25 16:18:59 2005'
Title2: 'GIPSYS'
Title3: ''
      IC: 0
      SBASE: 100
      bus: [1x4 struct]
      gen: [1x2 struct]
branch: [1x5 struct]
      swing: 1
pvIndx: 2
pqIndx: [2x1 double]
```

Once the system data is read in, any of the algorithms listed in table 3.2 can be applied to the system. As explained before, Matlab passes data by value, so the arguments remain unaffected and the results can be captured through the return value only. For example the following runs Newton-Raphson power flow on the above network and prints out the voltages:

```
>> nt = pl_NRPF(b4);
>> [nt.bus.I;nt.bus.VM;nt.bus.VA]
```

```
ans =
```

```
1.0000    2.0000    3.0000    4.0000
1.0000    1.0000    0.9993    0.9993
      0   -1.4332   -2.5803   -3.4406
```

Network structure data can be at any point used to extract and or change data using usual Matlab methods. Matlab provides a large number of functions to extract whatever information is needed and present it in whatever

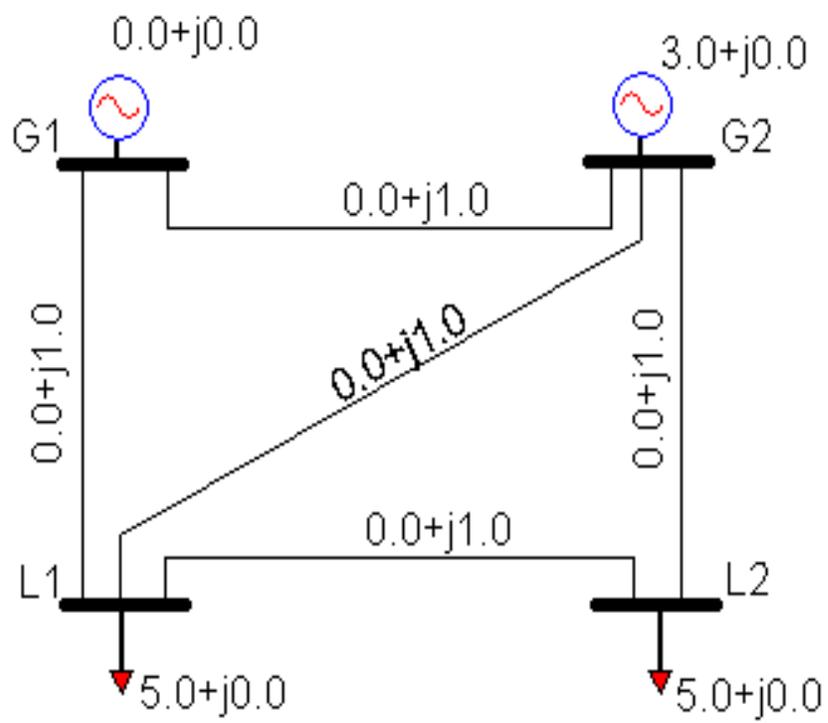


Figure 6.1: Four Bus System

format is desired with great flexibility. If it is desired to get the same line flows output as with ipsys interface, the following function would return a Matlab string with the flows:

```
>> flows = pl_NetFlows(nt);
>> flows
```

flows =

```
=====
                        Solution Output
=====
```

Input data file: unknown

0 100.00 / Tue Oct 25 16:18:59 2005
GIPSYS

From Bus	Volt. Mag.	Volt. Angle	Mw Load	Mvar Load	Mw Gen.	Mvar Gen.
To Bus	Mw Flow	Mvar Flow				
1	1.00000	0.00000	0.00	0.00	7.00	0.20
2	2.50	0.03				
3	4.50	0.17				
2	1.00000	-1.43318	0.00	0.00	3.00	0.25
1	-2.50	0.03				
4	3.50	0.13				
3	2.00	0.09				
3	0.99932	-2.58029	5.00	0.00	0.00	0.00
1	-4.50	0.03				
2	-2.00	-0.05				

```

4      1.50      0.01

4  0.99930  -3.44065      5.00      0.00      0.00      0.00
2    -3.50      -0.01
3    -1.50      0.01

```

```

Mw gen          = 10.000
Mvar gen        = 0.451
Mw load         = 10.000
Mvar load       = 0.000
Total I2R Mw losses = 0.000
Total I2X Mvar losses = 0.451
Generation Cost = 0.000

```

```

=====
                          End of Output
=====

```

and at this point the string can be stored in a file or just analyzed in Matlab.

If a net structure is modified in some way or if it is just a result of a calculation, it can be stored in a PTI23 string and/or saved in a file for further processing:

```
>> raw = pl_PrintRawStr(nt);
```

and the same can be done for the cost functions:

```
>> pgcost = pl_PrintPgCost(nt);
>> plcost = pl_PrintPLCostStr(nt);
```

6.2 Matlab Functions

Table 3.2 lists all the Matlab interface functions available to a user. In this section, a few functions will be used to demonstrate how they can be used.

The most common algorithm that can be used is the Newton-Raphson power flow and continuing with the system shown in Figure 6.1 we will change the generation of the non-slack bus and rerun the power flow:

```
>> b4.gen(2).PG = 2;
>> nt = pl_NRPF(b4);
>> [nt.bus.I;nt.bus.VM;nt.bus.VA]
```

```
ans =
```

1.0000	2.0000	3.0000	4.0000
1.0000	1.0000	0.9993	0.9993
0	-1.7916	-2.7955	-3.7275

```
>>
```

Note that due the change in generation distribution, voltage magnitudes remained the same but voltage angles changed as it should be expected.

The next example uses the same network to find DC optimal power considering both the generators and loads to be flexible:

```
>> b4 = pl_pti23Net('allen.raw','allen.sup',[],'allen.dmd');
>> nt = pl_DCOPFFlexGD(b4);
>> [nt.gen.I;nt.gen.PG;nt.gen.QG]
```

```
ans =
```

	1	2
	5.4552	4.0734
	0.14527	0.24908

```
>> [nt.bus.I;nt.bus.PL;nt.bus.QL]
```

```
ans =
```

	1	2	3	4
	0	0	3.7059	5.8227
	0	0	0	0

Chapter 7

Notes, Bugs, TODO list

IPSYS and implementation of all the underlying algorithms are results of recent development, not rigorously tested and work in progress. Further development can be done in the area of fixing bugs and providing new functionality. User feedback is crucial for both of these areas. This program is being actively developed.

Detecting, reporting, and dealing with errors is one of the most difficult aspects of interpreter and compiler design. Detecting errors can cause the interpreter to just abort the entire program, try to process as much of the input as possible and continue working and/or report the error back to the user. Helpful error reporting includes a fair amount of guessing of what is wrong with the input. IPSYS is a simple interface to a number of complex algorithms and is more focused on algorithm implementation and less on error handling. As the result, error reporting and sometimes recovery is quite limited. Following is the list of known bugs that are being worked on:

1. Running loops from the command line will slow GUI display update if the network window is moved or overlapped during loop execution. This seems to be operating system (Windows) related.
2. If a name is not associated with a function or data, the interpreter reports that there is no matrix with such a name. This is a consequence of using the same parenthesis type for indexing matrices and calling functions.
3. A function must be defined before called. This will be changed by

introducing function declaration since two functions cannot call each other unless they are the same function, that is unless it is a recursive call.

4. A defined function cannot be redefined within the same session.
5. Multi line commands in GUI must be ended with ENTER or SHIFT+RETURN except the last one which is ended with the usual RETURN key.

The error reporting needs to be improved. This is just a time consuming task. There are surely many more bugs. Any bug reports will be greatly appreciated and addressed. There are also a few unfinished things:

1. SSNetPrint function not completed.
2. Transformer editing and use is incomplete in GUI.
3. Introduce function declaration; the lack of it affects both GUI and CLI interface.
4. History saving menu is not functional yet.

Bibliography

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Appendix A

Installation

GIPSYS and MIPSYS probably require Windows 2000 or Windows XP while IPSYS could run on a less powerful computer and operating system. Installation of IPSYS and accompanying interfaces is almost automatic in Windows environment. An auto-installation executable is provided which copies all necessary files to a user chosen directory. All the necessary environment variables needed to run IPSYS and GIPSYS are entered into Windows registry. However, if MIPSYS is to be used, user must add in Matlab path to package's pl_*.m and cpp_*.dll files. This is done using addpath() Matlab command. To remember the new path between different Matlab sessions, run savepath() command after the last addpath(). At this point, all three interfaces should be functional.

Appendix B

Description of the PTI Load Flow Data Format

This is the description of an earlier version of PTI input format and it can be found at the [Power Systems Test Case Archive](#).

=====

Note that PTI reserves the right to change the format at any time.
For use with the IEEE 300 bus test case in PTI format.

Case Identification Data

=====

First record: IC,SBASE

IC - 0 for base case, 1 for change data to be added

SBASE - System MVA base

Records 2 and 3 - two lines of heading, up to 60 characters per line

Bus Data

=====

Bus data records, terminated by a record with a bus number of zero.

I, IDE, PL, QL, GL, BL, IA, VM, VA, 'NAME', BASKL, ZONE

I - Bus number (1 to 29997)

IDE - Bus type
 1 - Load bus (no generation)
 2 - Generator or plant bus
 3 - Swing bus
 4 - Isolated bus

PL - Load MW
QL - Load MVAR
GL - Shunt conductance, MW at 1.0 per unit voltage
BL - Shunt susceptance, MVAR at 1.0 per unit voltage. (- = reactor)
IA - Area number, 1-100
VM - Voltage magnitude, per unit
VA - Voltage angle, degrees
NAME - Bus name, 8 characters, must be enclosed in quotes
BASKV - Base voltage, KV
ZONE - Loss zone, 1-999

Generator Data

=====

Generator data records, terminated by a generator with an index of zero.

I, ID, PG, QG, QT, QB, VS, IREG, MBASE, ZR, ZX, RT, XT, GTAP, STAT, RMPCT, PT, PB

I - Bus number
ID - Machine identifier (0-9, A-Z)
PG - MW output
QG - MVAR output
QT - Max MVAR
QB - Min MVAR
VS - Voltage setpoint
IREG - Remote controlled bus index (must be type 1), zero to control own voltage, and must be zero for gen at swing bus
MBASE - Total MVA base of this machine (or machines), defaults to system MVA base.
ZR, ZX - Machine impedance, pu on MBASE
RT, XT - Step up transformer impedance, p.u. on MBASE
GTAP - Step up transformer off nominal turns ratio
STAT - Machine status, 1 in service, 0 out of service

RMPCT - Percent of total VARS required to hold voltage at bus IREG
to come from bus I - for remote buses controlled by several generators
PT - Max MW
PB - Min MW

Branch Data
=====

Branch records, ending with a record with from bus of zero

I,J,CKT,R,X,B,RATEA,RATEB,RATEC,RATIO,ANGLE,GI,BI,GJ,BJ,ST

I - From bus number
J - To bus number
CKT - Circuit identifier (two character) not clear if integer or alpha
R - Resistance, per unit
X - Reactance, per unit
B - Total line charging, per unit
RATEA - MVA rating A
RATEB, RATEC - Higher MVA ratings
RATIO - Transformer off nominal turns ratio
ANGLE - Transformer phase shift angle
GI,BI - Line shunt complex admittance for shunt at from end (I) bus, pu.
GJ,BJ - Line shunt complex admittance for shunt at to end (J) bus, pu.
ST - Initial branch status, 1 - in service, 0 - out of service

Transformer Adjustment Data
=====

Ends with record with from bus of zero

I,J,CKT,ICONT,RMA,RMI,VMA,VMI,STEP,TABLE

I - From bus number
J - To bus number
CKT - Circuit number
ICONT - Number of bus to control. If different from I or J, sign of ICONT
determines control. Positive sign, close to impedance (untapped) bus

of transformer. Negative sign, opposite.
RMA - Upper limit of turns ratio or phase shift
RMI - Lower limit of turns ratio or phase shift
VMA - Upper limit of controlled volts, MW or MVAR
VMI - Lower limit of controlled volts, MW or MVAR
STEP - Turns ratio step increment
TABLE - Zero, or number of a transformer impedance correction table 1-5

Area Interchange Data

=====

Ends with I of zero

I,ISW,PDES,PTOL,'ARNAM'

I - Area number (1-100)

ISW - Area interchange slack bus number

PDES - Desired net interchange, MW + = out.

PTOL - Area interchange tolerance, MW

ARNAM - Area name, 8 characters, enclosed in single quotes.

DC Line Data

=====

Ends with I of zero

Each DC line has three consecutive records

I,MDC,RDC,SETVL,VSCHD,VCMOD,RCOMP,DELTI,METER

IPR,NBR,ALFMAX,ALFMN,RCR,XCR,EBASR,TRR,TAPR,TPMXR,TPMNR,TSTPR

IPI,NBI,GAMMX,GAMMN,RCI,XCI,EBASI,TRI,TAPI,TPMXI,TPMNI,TSTPI

I - DC Line number

MDC - Control mode 0 - blocked 1 - power 2 - current

RDC - Resistance, ohms

SETVL - Current or power demand

VSCHD - Scheduled compounded DC voltage, KV

VCMOD - Mode switch DC voltage, KV, switch to current control mode below this

RCOMP - Compounding resistance, ohms
 DELTI - Current margin, per unit of desired current
 METER - Metered end code, R - rectifier I - Inverter
 IPR - Rectifier converter bus number
 NBR - Number of bridges in series rectifier
 ALFMAX - Maximum rectifier firing angle, degrees
 ALFMN - Minimum rectifier firing angle, degrees
 RCR - Rectifier commutating transformer resistance, per bridge, ohms
 XCR - Rectifier commutating transformer reactance, per bridge, ohms
 EBASR - Rectifier primary base AC volts, KV
 TRR - Rectifier transformer ratio
 TAPR - Rectifier tap setting
 TPMXR - Maximum rectifier tap setting
 TPMNR - Minimum rectifier tap setting
 TSTPR - Rectifier tap step

Third record contains inverter quantities corresponding to rectifier quantities above.

Switch Shunt Data
 =====

Ends with I = 0.

I,MODSW,VSWHI, VSWLO,SWREM,BINIT,N1,B1,N2,B2...N8,B8

I - Bus number
 MODSW - Mode 0 - fixed 1 - discrete 2 - continuous
 VSWHI - Desired voltage upper limit, per unit
 VSWLO - Desired voltage lower limit, per unit
 SWREM - Number of remote bus to control. 0 to control own bus.
 VDES - Desired voltage setpoint, per unit
 BINIT - Initial switched shunt admittance, MVAR at 1.0 per unit volts
 N1 - Number of steps for block 1, first 0 is end of blocks
 B1 - Admittance increment of block 1 in MVAR at 1.0 per unit volts.
 N2, B2, etc, as N1, B1

Appendix C

Power Flow Review

Power flow is a steady-state analytical tool of a power system. The power flow within a system is completely known if real or active power (P_i), reactive power (Q_i), voltage magnitude (V_i), and voltage phase angle (θ_i) are known at each bus i . Only two variables are known at each bus and the goal is to solve for the other two variables. The three most common bus types are load bus (P, Q known), voltage controlled bus ($P, |E|$ known), and generator bus ($P, |E|$ known, or P, Q if Q exceeds generator limits). A power system is connected with lines of known complex impedance between the buses and the ground. The system can be described with a set of equations similar to any electrical circuit. However, since the known variables are complex power quantities, the power system equations are nonlinear.

The following equations are the derivation of Newton-Raphson solution [7] used in this work. The Newton-Raphson solution is based on the first order, multivariable Taylor series expansion which requires one time calculation of the system's impedance matrix and an iterative calculation of the Jacobian. If the power system's nonlinear equations are represented by:

$$F(V) = const \quad (\text{C.1})$$

we choose a starting value for the independent variable V^0 . The starting value will cause an error, ε in function F :

$$F(V^0) + \varepsilon = const \quad (\text{C.2})$$

The error can be decreased using Taylor series expansion,

$$F(V^0) + \frac{dF(V^0)}{dV} \Delta V + \varepsilon = const \quad (\text{C.3})$$

solving for independent variable correction ΔV by setting error ε to zero and reiterating with the new value of the independent variable until the error is acceptable:

$$\Delta V = \left(\frac{dF(V^0)}{dV} \right)^{-1} [\text{const} - F(V^0)] \quad (\text{C.4})$$

In power systems case, the independent variable is the set of complex value bus voltages, the derivative in the Taylor series expansion is the Jacobian of the power injection equations at each bus, and the error is the set of P_i and Q_i mismatches. A power system's currents depend on the bus voltages in a linear manner:

$$\begin{bmatrix} I_1 \\ I_2 \\ \cdot \\ \cdot \\ I_n \end{bmatrix} = \begin{bmatrix} Y_{11} & Y_{12} & Y_{13} & Y_{14} & Y_{15} \\ Y_{21} & Y_{22} & Y_{23} & Y_{24} & Y_{25} \\ \cdot & \cdot & \cdot & \cdot & \cdot \\ \cdot & \cdot & \cdot & \cdot & \cdot \\ Y_{n1} & Y_{n2} & Y_{n3} & Y_{n4} & Y_{n5} \end{bmatrix} \begin{bmatrix} E_1 \\ E_2 \\ \cdot \\ \cdot \\ E_n \end{bmatrix} \quad (\text{C.5})$$

where:

$$Y_{ij} = -y_{ij} \quad \text{and} \quad Y_{ii} = \sum_j y_{ij} + y_{ig}$$

over all i, j connected buses and i, g ground connections. At each bus, the injected complex power is given by:

$$P_i + jQ_i = E_i I_i^* \quad (\text{C.6})$$

where:

$$I_i = \sum_{k=1}^N Y_{ik} E_k^*$$

then

$$P_i + jQ_i = E_i \left(\sum_{k=1}^N Y_{ik} E_k \right)^*$$

and

$$P_i + jQ_i = |E_i|^2 Y_{ii}^* + \sum_{\substack{k=1 \\ k \neq i}}^N Y_{ik}^* E_i E_k^*$$

The last equation can be expanded into:

$$\begin{aligned}
P_i + jQ_i &= \sum_{k=1}^N |E_i||E_k| (G_{ik} - jB_{ik}) e^{j(\theta_i - \theta_k)} \\
&= \sum_{k=1}^N |E_i||E_k| [G_{ik} \cos(\theta_i - \theta_k) + B_{ik} \sin(\theta_i - \theta_k)] \\
&\quad + j \sum_{k=1}^N |E_i||E_k| [G_{ik} \sin(\theta_i - \theta_k) - B_{ik} \cos(\theta_i - \theta_k)]
\end{aligned} \tag{C.7}$$

where

$$\begin{aligned}
\theta_i, \theta_k &= \text{the phase angles at buses } i \text{ and } k \\
|E_i|, |E_k| &= \text{the bus voltage magnitudes} \\
G_{ij} + jB_{ik} &= Y_{ik} \text{ is the } ik \text{ term in the } Y \text{ matrix}
\end{aligned}$$

The system of equations C.7 is a nonlinear system which is solved using standard first order Taylor series approximation. The Jacobian of the Equations in C.7 is given by the following matrix equation:

$$\begin{bmatrix} \Delta P_1 \\ \Delta Q_1 \\ \Delta P_2 \\ \Delta Q_2 \\ \vdots \end{bmatrix} = \begin{bmatrix} \frac{\partial P_1}{\partial \theta_1} & \frac{\partial P_1}{\partial |E_1|} & \frac{\partial P_1}{\partial \theta_2} & \frac{\partial P_1}{\partial |E_2|} & \cdots \\ \frac{\partial Q_1}{\partial \theta_1} & \frac{\partial Q_1}{\partial |E_1|} & \frac{\partial Q_1}{\partial \theta_2} & \frac{\partial Q_1}{\partial |E_2|} & \cdots \\ \frac{\partial P_2}{\partial \theta_1} & \frac{\partial P_2}{\partial |E_1|} & \frac{\partial P_2}{\partial \theta_2} & \frac{\partial P_2}{\partial |E_2|} & \cdots \\ \frac{\partial Q_2}{\partial \theta_1} & \frac{\partial Q_2}{\partial |E_1|} & \frac{\partial Q_2}{\partial \theta_2} & \frac{\partial Q_2}{\partial |E_2|} & \cdots \\ \vdots & \vdots & \vdots & \vdots & \ddots \end{bmatrix} \begin{bmatrix} \Delta \theta_1 \\ \Delta |E_1| \\ \Delta \theta_2 \\ \Delta |E_2| \\ \vdots \end{bmatrix} \tag{C.8}$$

To further simplify the derivatives, instead of $\Delta |E_i|$, we use $\frac{\Delta |E_i|}{|E_i|}$ which results in:

$$\begin{aligned}
\frac{\partial P_i}{\partial \theta_k} &= |E_i||E_k| [G_{ik} \sin(\theta_i - \theta_k) - B_{ik} \cos(\theta_i - \theta_k)] \\
\frac{\partial P_i}{\left(\frac{\partial |E_k|}{|E_k|}\right)} &= |E_i||E_k| [G_{ik} \cos(\theta_i - \theta_k) + B_{ik} \sin(\theta_i - \theta_k)] \\
\frac{\partial Q_i}{\partial \theta_k} &= -|E_i||E_k| [G_{ik} \cos(\theta_i - \theta_k) + B_{ik} \sin(\theta_i - \theta_k)] \\
\frac{\partial Q_i}{\left(\frac{\partial |E_k|}{|E_k|}\right)} &= |E_i||E_k| [G_{ik} \sin(\theta_i - \theta_k) - B_{ik} \cos(\theta_i - \theta_k)]
\end{aligned} \tag{C.9}$$

For $i = k$:

$$\begin{aligned}
\frac{\partial P_i}{\partial \theta_i} &= -Q_i - B_{ii}E_i^2 \\
\frac{\partial P_i}{\left(\frac{\partial |E_i|}{|E_i|}\right)} &= P_i + G_{ii}E_i^2 \\
\frac{\partial Q_i}{\partial \theta_i} &= P_i - G_{ii}E_i^2 \\
\frac{\partial Q_i}{\left(\frac{\partial |E_i|}{|E_i|}\right)} &= Q_i - B_{ii}E_i^2
\end{aligned}$$

And in the matrix form:

$$\begin{bmatrix} \Delta P_1 \\ \Delta Q_1 \\ \Delta P_2 \\ \Delta Q_2 \\ \vdots \end{bmatrix} = [J] \begin{bmatrix} \Delta \theta_1 \\ \frac{\Delta |E_1|}{|E_1|} \\ \Delta \theta_2 \\ \frac{\Delta |E_2|}{|E_2|} \\ \vdots \end{bmatrix} \quad (\text{C.10})$$

Equation C.10 is in the format used by the Newton–Raphson iterative solver. The whole process starts by assigning an initial solution for complex voltages which is usually of a magnitude of 1.0 per unit and 0 phase. The next step is to calculate ΔP_i and ΔQ_i as well as the Jacobian. Using these values, $\Delta \theta_i$ and $\frac{\Delta |E_i|}{|E_i|}$ are calculated and a new solution for voltages is found. This is repeated until change in P and Q is sufficiently small.

Appendix D

Optimal Power Flow Review

The Optimal Power Flow (**OPF**) problem has been a topic of intense research for the last forty years. OPF is a static power flow problem which tries to determine the optimal control variables in a power network under constraint conditions. The OPF can be mathematically formulated in general terms as in [2]:

$$\underset{z}{\text{Min}} f(Z), \quad Z \in \mathfrak{R}^{m+n}, \quad f : \mathfrak{R}^{m+n} \rightarrow \mathfrak{R}^1 \quad (\text{D.1})$$

subject to:

$$G(Z) = 0, \quad G : \mathfrak{R}^{m+n} \rightarrow \mathfrak{R}^a \quad (\text{D.2})$$

$$H(Z) \leq 0, \quad H : \mathfrak{R}^{m+n} \rightarrow \mathfrak{R}^b \quad (\text{D.3})$$

where $f(\mathbf{Z})$ is the objective function to be minimized, $G(\mathbf{Z})$ are the nonlinear power flow equations and $H(\mathbf{Z})$ are the nonlinear inequality constraints. Vector $\mathbf{Z} = [\mathbf{U} \mathbf{X}]^T$ is the vector of both state and control variables. State variables vector \mathbf{X} includes bus voltages, reference bus angle, non-controlled generator MVA and MVAR outputs and loads, fixed bus voltages, etc. Similarly, \mathbf{U} is the vector of control variables such as real and reactive power generation, phase-shifter angles, net interchange, load shedding, DC transmission line flows, control voltage settings, LTC settings, etc. Equality and inequality constraints include limits on all control variables, power flow equations, generation/load balance, power flow limits, bus voltage limits, reserve limits, MVAR limits, etc. The optimization objective could include power cost optimization, loss minimization, minimum control-shift, minimum number of controls rescheduled, etc. With the introduction of the free market,

a different set of constraints and different objectives are being introduced depending on the deregulation model.

OPF solutions are based on both linear and nonlinear numerical methods. Linear programming methods are based on different variants of Linear Programming (LP) while the nonlinear methods include Sequential Quadratic Programming, Augmented Lagrangian Methods, Generalized Reduced Gradient, Projected Augmented Lagrangian, Successive Linear Programming, Interior Point Methods, among others. The number of the different solutions and variants is a clear indication of the complexity of the problem. All of the OPF algorithms in use in some way simplify the original problem.

Appendix E

DC Optimal Power Flow Review

DC Optimal Power Flow is based on the decoupled power flow without the $Q - V$ equations [7]. The decoupled power flow neglects the P_i and any E_k interactions as well as Q_i and any Θ_k interactions. Also neglecting $Q - V$ equations results in a DC power flow that is a linear system of power flow equations with all voltages set to 1.0. This system of equations can be solved for voltage angles. The following discussion of DC OPF takes advantage of this linearity to formulate the OPF with respect to generation and load levels. Optimization with respect to either only the generation or only the load can be easily derived from the following equations.

The objective function is give in equation E.1:

$$\text{Min}_{P_{g_i}, P_{l_j}} \sum_i^{N_g} C_i(P_{g_i}) - \sum_j^{N_l} U_j(P_{l_j}) \quad (\text{E.1})$$

such that simple constraints are:

$$P_i^{min} \leq P_i \leq P_i^{max} \quad i = 0 \dots N_g \quad (\text{E.2})$$

$$\frac{\pi}{2} \leq \theta_i \leq \frac{\pi}{2} \quad i = 1 \dots N_b \quad (\text{E.3})$$

$$\theta_0 = \text{const} \quad (\text{E.4})$$

and linear combination constraints are:

$$B \times \Theta = \Delta P \quad (\text{E.5})$$

$$|DF \times \Delta P| \leq F^{max} \quad (\text{E.6})$$

Where P_i is the generation of the i^{th} bus, θ_i is the voltage angle of the i^{th} bus, θ_0 is the voltage angle of the slack bus. Matrix B is the imaginary part of the admittance matrix, and DF is the distribution matrix. Equations [E.2](#), [E.3](#), and [E.4](#) are simple variable constraints. Real power generation is limited by minimum and maximum values, all voltage angles except the slack bus angle are limited by $\pm \frac{\pi}{2}$. Slack bus angle is fixed to the original value read from the input data. Linear constraint equation [E.5](#) is the power balance equation. Equation [E.6](#) is the real power transmission constraint. ΔP is the vector of net generations of all the buses, that is $\Delta P_i = P_{g_i} - P_{l_i}$.

DCOPF functions take into account the power generation limits for all of the buses including the slack bus. The cost function is minimized with respect to all of the generators and/or loads including the slack bus. This is different from the power flow calculations where the slack bus is used to cover for the losses regardless of its limits and cost.