Optimal Allocation of Dynamic Var Sources Using the Voronoi Diagram Method Integrating Linear Programming

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Abstract—Dynamic reactive power (var) sources can effectively mitigate fault-induced delayed voltage recovery (FIDVR) issues. This paper optimizes the sizes of dynamic var sources at given locations against FIDVR issues under severe contingencies. First, the geometric characteristics about the non-convex solution space of this problem are studied. Accordingly, a Voronoi diagram approach integrating linear programming (LP) is proposed, which dispenses a number of sample points of potential solutions in the searching space to construct a Voronoi diagram blending the local cost functions over the entire space by Barycentric interpolation in Voronoi regions. New sample points are then recursively added, including the optimal point using LP, the most depopulated area point ensuring global fidelity, and the connecting point, until the stopping criterion is met. The new approach is demonstrated in detail on the WSCC 9-bus system. A case study on the NPCC 140-bus system also validates that the proposed approach can effectively estimate the boundary and the geometry of the feasible solution region in the searching space and find the optimal solution.

Index Terms—Barycentric interpolation, dynamic var support, fault-induced delayed voltage recovery, FIDVR, linear programming, nonlinear optimization, Voronoi Diagram.

I. INTRODUCTION

In recent years, fault-induced delayed voltage recovery (FIDVR) issues have drawn growing attentions, especially in the areas with a lot of air conditioning loads. In order to economically guarantee voltage security and prevent FIDVR issues, it is important to optimally allocate and manage dynamic var sources such as static var compensators (SVCs) and STATCOMs.

The optimal allocation of dynamic var sources has been studied in [1]–[13] and needs to address two problems, i.e. the optimal placement and optimal sizing of var sources, which are usually solved separately. The optimal placement problem is traditionally solved by calculating a voltage sensitivity index for each candidate location so as to identify where an injection of dynamic var can improve post-fault voltage recovery to the largest extent for the most severe one or multiple contingencies [3]–[5]. A recent work applies the empirical controllability covariance to place dynamic var sources which can reduce the dependency on the selection of contingencies [6].

In existing studies, the optimal sizing problem of the dynamic var sources is usually formulated as a mixed integer programming problem and addressed by interfacing a heuristic optimization algorithm with power system simulation. In [7], the dynamic var allocation problem is formulated as a mixed integer nonlinear programming problem and solved by interfacing the branch-and-bound and multi-start scatter algorithms, which are available in MATLAB with power system time-domain simulation software. A similar problem is solved in [8] by interfacing a MATLAB-based toolbox KNITRO with power system simulation. In [9], the sizing of dynamic var sources is optimized by a multi-objective evolutionary algorithm called MOEA/D. The approach presented in [10] employs the mean-variance mapping optimization in combination with an integrated mix-integer search strategy and two intervention schemes for a number of most severe “N-1” contingencies. In [11] the optimal locations and amounts of static and dynamic var sources are solved as a sequence of mixed integer programming problems. The particle swarm optimization method is applied in [12] for the installation of dynamic var sources including wind farms. In [13] a heuristic linear programming method is proposed for a small number of dynamic var sources.

Our previous work in [14] has tentatively shown that Voronoi diagram, as an effective technique for generating contour map [15], can approximate the geometry of the solution space of the problem very well. This paper aims to tackle the optimal sizing of dynamic var sources from a new perspective: first, a study on the geometric characteristics about the solution space indicates the non-convexity of the feasible solution region and relative flatness near the optimal solution; accordingly, the Voronoi diagram method integrating linear programming (LP) is proposed to effectively find the optimal solution.
The rest of this paper is organized as follows. Section II discusses the formulation of the problem. Section III analyzes the general geometric properties of the feasible solution region in the solution space. Section IV introduces the Voronoi diagram based blending of local function expression. Section V proposes the new approach using the Voronoi diagram method integrating LP. Then in Section VI, the proposed approach is illustrated in detail on WSCC 9-bus system and then validated on the NPCC 140-bus system. Finally, conclusions are drawn in Section VII.

II. FORMULATION OF THE PROBLEM

The optimal allocation problems of dynamic var sources can be formulated based on industry practices. To address FIDVR issues, power companies follow certain reliability standards to determine the locations and sizes of dynamic var sources for reducing voltage deviations under a contingency [16]. Consider an N-bus power system to place dynamic var sources against potential FIDVR issues under K selected contingencies. The percentage voltage deviation of a bus j at time t under the k-th contingency can be defined as:

$$r_j^k(t) = \frac{V_j^t - V_j^{init}}{V_j^{init}} \times 100\% \quad j = 1, \ldots, N, \quad k = 1, \ldots, K$$ (1)

where $V_j^{init}$ is the pre-fault voltage magnitude. The fault clearing time is denoted by $t_{cl}$ and the post-fault transient period is defined to be $t_d$ after $t_{cl}$. Without losing generality, this paper considers the following constraints $C_1$ to $C_3$ on the post-fault transient voltage performance:

- $C_1$: $r_j^k(t) \leq R_1$ for $t_{cl} \leq t \leq t_d$.
- $C_2$: The duration for $r_j^k(t)$ exceeding $R_2 \leq D$ for $t_{cl} \leq t \leq t_d$.
- $C_3$: $r_j^k(t) \leq R_3$ for $t > t_d$.

Typical parameters based on the WECC/NERC standards [17] are considered in this paper: $R_1 = 25\%$ for load buses and $30\%$ for generator buses; $R_2 = 20\%$ and $D = 1/3$ second; $t_d = 3$ seconds and $R_3 = 5\%$. Fig. 1 illustrates the criteria for a load bus.

Within a given post-contingency period, check constraints $C_1$ to $C_3$ for $T$ time points at intervals of $\Delta t$ (e.g. 4.167 ms). Define a severity index $S_j^k(\tau)$ for bus $j$ under contingency $k$ at the $\tau$-th time point of the period, which equals $r_j^k(\tau \times \Delta t)$ if any constraint is violated, or 0, otherwise. Then, for contingency $k$, the average severity index $S^k$ for the overall system and all time points of the period is calculated as

$$S^k = \frac{1}{T \cdot N} \sum_{j=1}^{N} \sum_{\tau=1}^{T} S_j^k(\tau).$$ (2)

Assume that the buses to install dynamic var sources have been determined by power system planners using an optimal placement approach as well as engineering judgement giving considerations to factors on system operations. The index set of those selected buses is denoted by $I_0$. The optimal sizing problem can be formulated as:

$$\text{Minimize } J_1 = e^T Q$$ (3)

Subject to

$$x = f(x, V, Q)$$ (4)
$$0 = g(x, V, Q)$$ (5)
$$Q_{i}^L \leq Q_i \leq Q_{i}^U$$ (6)
$$C_1, C_2, \text{ and } C_3$$ (7)

where $Q^T = [Q_1, \ldots, Q_N]^T$ is a column vector about the sizes of dynamic var sources installed at $N$ buses, whose upper and lower limits are respectively in vectors $Q^U$ and $Q^L$, and there is $Q = Q^L \leq Q \leq Q^U = 0$ if $i \notin I_0$, and $c = [c_1, \ldots, c_N]^T$ is the column vector of costs per Mvar (e.g. the installation and maintenance costs) associated with the dynamic var sources. The objective is to find the optimal vector $Q$ so as to minimize the objective function $J_1$ under all constraints. In practice, with the post-fault voltage trajectories obtained from time-domain simulation, the constraints $C_1$ to $C_3$ can be checked at each simulation step $\Delta t$.

In general, the set of feasible solutions of the optimization problem in (3)-(7) is non-convex. Also, the optimization is coupled with resolution of power system differential-algebraic equations (DAEs) in (4)-(5) for post-fault system trajectories, which dramatically increases the computational complexity. Taking exhaustive search as an example, post-fault voltage responses need to be first solved for all contingencies with each possible $Q$, based on which the voltage criteria $C_1$ to $C_3$ need to be checked. Only when all responses satisfy the criteria, such a vector $Q$ indicates a feasible solution. After all possible feasible solutions are found, the optimal $Q$ can then be obtained as the final solution.

III. GEOMETRY OF THE SOLUTION SPACE

To integrate $C_1$, $C_2$, and $C_3$ into the cost function, the objective function $J_1$ is modified as

$$J_2 = e^T Q + c_p \sum_{k=1}^{N} b_k$$ (8)

where binary variable $b_k$ equals 1 if the $k$-th contingency makes any constraint violated or equals 0, otherwise, and $c_p > c_i$ is the penalty of voltage violation. Next, the geometry of the solution space about the objective function (8) is studied in order to develop an effective algorithm for this optimization problem.

As an example, the WSCC 3-generator 9-bus system shown in Fig. 2 is studied. The most severe “N-1” contingency is identified as the three-phase fault at bus 7 cleared by opening
line 5-7 after 5 cycles. Here, set $c_i = $1,000/Mvar, $c_p =$300,000 and $Q_{L} = 0$ Mvar. The solution spaces for installing one SVC at bus 6 and three SVCs at all of three load buses are obtained by exhaustive search in the range of $[0, 85]$ (Mvar) for each $Q_i$, from which some useful insight can be gained on geometric characteristics of the solution space.

![Fig. 2. The most severe N-1 contingency of WSCC 9-bus system and three candidate buses for dynamic var supports.](image)

![Fig. 3. One SVC size at bus 6 and its corresponding objective function.](image)

![Fig. 4. The contour map of objective function and its infeasible solution space.](image)

To better understand the geometry of the region of feasible solutions, let $Q_5$ respectively take a value from $\{0, 15, 30, 45, 60, 75\}$ each time and the objective function $J_2$ is evaluated for all combinations of $Q_6$ and $Q_8$. The contour maps about the cost function are shown in Fig. 5. For different values of $Q_5$, the following are observed:

- When $Q_6$ and $Q_8$ increase starting from an infeasible solution, $J_2$ first increases almost linearly and then sharply drops to a small value when the penalty is no more applied, or in other words, when the solution becomes feasible.
- The feasible solution region is relatively flat, in which $J_2$ basically increases in a linear manner.
- The optimal solution (darkest blue) appears close to the boundary of the feasible solutions.
- The boundary of the feasible solutions is not smooth.

These observations coincide with the characteristics of Fig. 3 for installing one SVC.

![Fig. 5. Contour map of objective function when the SVC of bus 5 is fixed.](image)

Furthermore, the impacts of load and generation variations are investigated. Specifically, we change the system load together with the total generation by $-10\%$, $-5\%$, $+5\%$, and $+10\%$. For these four new loading conditions, the contour maps about the objective function are shown in Fig. 6. Each blue area indicates the region of feasible solutions, which

![Fig. 6. The contour maps of the objective function, where the region (blue) of feasible solutions are shown under four different loading conditions.](image)
shrinks with the increase of the load. The global optimum also moves as indicated by the white arrow. Despite the change of load, the aforementioned four observations are still valid with these contour maps. Another important observation is that the optimum for a heavy-load condition (e.g. the +10% load increase case) is still in the feasible region for a light-load condition.

When the objective function \( J_2 \) is used, because of the high penalties added to voltage violations in (8), the above geometric characteristics may be generalized for the optimal sizing problem of dynamic var sources. Thus, it is reasonable to make use of these geometric characteristics of the solution space and design an effective algorithm to solve the problem. An idea is to first approximately depict the boundary and to make use of these geometric characteristics of the solution space. Thus, it is reasonable geometric characteristics may be generalized for the optimal sizing problem of dynamic var sources. Thus, it is reasonable to make use of these geometric characteristics of the solution space and design an effective algorithm to solve the problem.

In the next two sections, the Voronoi diagram and the Barycentric interpolation will be introduced as an efficient technique for geometric and function approximation, and a new approach based on the Voronoi diagram method integrating LP will be proposed to effectively solve the optimal sizing problem of dynamic var sources.

IV. VORONOI DIAGRAM BASED BLENDING OF LOCAL FUNCTION APPROXIMATION

This section introduces the fundamentals of Voronoi diagram and Barycentric interpolation. In literature, Voronoi diagram based blending methods of local response surfaces have been proposed to accomplish global fidelity in function approximation for engineering designing optimization [18].

![Fig. 7. Generating Voronoi diagram and local function estimation.](image)

A Voronoi diagram based Barycentric interpolation can estimate the boundary and geometry of the feasible solution region in any dimension. Voronoi diagram partitions a plane into regions based on the distance to the sample points and can provide geometric information of sample points, such as the most depopulated area in the plane. Barycentric interpolation can estimate the local function expression around sample points in each small Voronoi region.

The following example illustrates the essence of Voronoi diagram and Barycentric interpolation in a two dimensional plane \( x-y \). The searching range is \([1, 10]\) for both \( x \) and \( y \), and the function of \( x \) and \( y \) is \( z = x^2/25 + y^2/100 - x + y \). To estimate the function values over the entire plane, the values at a sample point set \( P=\{p_1, p_2, ..., p_7\} \) including 4 searching boundary points and 3 distinct random points are first calculated and colored by their values as shown in Fig. 7(a). Perpendicular bisectors are drawn for each pair of the distinct points in \( P \). These result in a set of polyhedra (polygons for this 2-D case) as illustrated by orange dash lines in Fig. 7(b). This is called a Voronoi diagram denoted as \( \text{Vor}(P) \). The cell of \( \text{Vor}(P) \) that corresponds to a site \( p_i \) is called a Voronoi region of \( p_i \), denoted by \( \text{Vor}(p_i) \). All of the intersection points such as \( e_1, e_2, ..., e_6 \) are called Voronoi points. Taking \( p_3 \) as an example, its Voronoi region, \( \text{Vor}(p_3) \), is composed by Voronoi points \( e_1 e_2 e_3 e_4 e_5 e_6 \). Denote the Euclidean distance between any two points \( p \) and \( e \) by \( \text{dis}(p,e) = \sqrt{(p_x - e_x)^2 + (p_y - e_y)^2} \). The judge of the territory of each Voronoi region, any point \( a \) lies in \( \text{Vor}(p_i) \) if and only if \( \text{dis}(a,p_j) < \text{dis}(a,p_i) \) for any \( p_j \in \text{P} \) with \( j \neq i \).

As illustrated in Fig. 7(b), since \( p_1 \) has a smallest function value, so \( \text{Vor}(p_1) \) is most likely to contain the minimum value. To estimate the function values inside this region, Barycentric interpolation is applied to estimate local function values in triangles about any three adjacent \( p \) points. Taking triangle \( p_3 p_6 p_7 \) for example, each point located inside this triangle can be written as a unique convex combination of the three vertices. To estimate the function value of an inside point \( e_6 \) as shown in Fig. 7(c), a unique sequence of three positive numbers, \( a_1, a_2, \) and \( a_3 \), can be found such that \( a_1 + a_2 + a_3 = 1 \) and \( e_6 = a_1 p_3 + a_2 p_6 + a_3 p_7 \). Here \( a_1, a_2, \) and \( a_3 \) are the Barycentric coordinates of the point \( e_6 \) with respect to the triangle and there are \( a_1 = A_1/(A_1 + A_2 + A_3) \), \( a_2 = A_2/(A_1 + A_2 + A_3) \) and \( a_3 = A_3/(A_1 + A_2 + A_3) \), where \( A_1, A_2, A_3 \) are the sub triangle areas as shown in Fig. 7(c). Each point inside \( p_3 p_6 p_7 \) is uniquely defined by any two of the Barycentric coordinates. Finally, \( e_6 \) is colored with its corresponding value as an estimate of the function value there.

With the 7 points in the plane, the entire space can be estimated by Barycentric interpolation as shown in Fig. 7(d) which is very close to the accurate values as shown in Fig. 7(e). With more sample points, the estimation for the entire space will be more accurate. Based on this idea, in the next section, a new approach is proposed to effectively optimize the dynamic var sources using Voronoi diagram.

V. PROPOSED APPROACH

As discussed in Section IV, the Voronoi diagram and Barycentric interpolation are useful techniques to establish function approximation by means of sample points added to the solution space. However, toward the global optimization, without any heuristic information, the Voronoi diagram based blending of local function expression may require many iterations of adding new sample points. Our previous work in
[13] shows that a heuristic LP based method can correctly identify an effective searching direction from an existing point in the solution space, but may jump out of the feasible solution region or converge to the local optimal when the nonlinearity of the optimization problem is significant with four or more dynamic var sources needed to be optimized.

To take the advantage of the Voronoi diagram method on exploring the geometric information on the solution space and the simplicity and time performance of LP in optimization, this section introduces a new approach based on the Voronoi diagram method integrating LP. In each iteration of the approach, Voronoi diagram and Barycentric interpolation are used to identify the most promising region, which integrate LP for determining the search direction to add new sample points without jumping out of that region.

A. Proposed Algorithm

Specifically, this paper proposes the following approach for solving the optimal sizing problem:

**Step 1** In the $|I_Q|$-dimensional solution space about $Q_i$ ($i \in I_Q$), i.e. the sizes of placed dynamic var sources, randomly select a set of sample points, denoted by $M$, and evaluate cost function $J_2$ about $Q_i$ ($i \in I_Q$) at each point.

**Step 2** Establish the Voronoi diagram using all $M$ sample points and estimate the approximate value of $J_2$ in a neighborhood of each point by Barycentric interpolation.

**Step 3** Find the point with the minimal $J_2$ as a tentative solution.

**Step 4** Add three new sample points (as explained in subsections V.B-C), and go back to Step 2.

The algorithm can be terminated either after a pre-defined large number of iterations from Step 2 to Step 4, or when the decrease in $J_2$ is less than a pre-defined tolerance $\epsilon$.

Fig. 8 illustrates the implementation of the entire approach by integrating the proposed algorithm with power system time-domain simulation. The Voronoi diagram and LP are implemented in MATLAB and are interfaced with power system dynamic simulation software PSS/E via Python. PSS/E solves the DAEs in (4)–(5) to simulate the post-fault voltage responses for any given sizing strategy $Q$, i.e. a sample point in the solution space. The results are used to evaluate $J_2$ for the strategy and fed back to the Voronoi diagram and LP for function approximation and searching direction identification.

The $|I_Q|$-dimensional space requires at least $|I_Q|+1$ points to establish a Voronoi diagram. To make the diagram authentically present geometrical characteristics of the space, more points should be utilized [19]. In this paper, $2(|I_Q|+1)$ initial sample points are randomly selected in the solution space together with its $2|I_Q|$ geometric vertices (i.e. the limits in all dimensions) to build the first Voronoi diagram.

To improve the fidelity of the global approximation, three new sample points are added every time as Step 4 is executed: the first point is based on LP to enhance the current tentative optimum within the identified candidate optimum region, the second is to improve the global approximation fidelity at the most depopulated region, and the third is to connect the above two avoiding distorting the Voronoi diagram.

![Flow chart for implementing the proposed approach.](image)

Fig. 8. Flow chart for implementing the proposed approach.

In the following, how to add three new sample points in Step 4 is introduced in detail.

B. No. 1 New Point by LP for Tentative Optimum Fidelity

![Addition of a new sample point for the optimum.](image)

Fig. 9. Addition of a new sample point for the optimum.

As shown in Fig. 9, if the tentative optimal solution is obtained as $p_0$, the Voronoi region, the polyhedra determined by vertices $e_2$ to $e_6$ is considered as the most effective area. A new candidate sample point shown as $Q^0(i \in I_Q)$ is chosen at the estimated minimum value of the objective function in this region by using Barycentric interpolation.

Since the interpolation value will be changed by adding other points, a new sample point $Q^k(i \in I_Q)$ is refined by an iterative LP algorithm like [13] utilizing the maximum voltage recovery sensitivity defined by

$$VSI_q^k = \max_{j=1,\cdots,T} \left( V_{j,\text{new},t}^k - V_{j,\text{old},t}^k \right), q \in K, k = 1,\cdots,K $$

where $k$ is the index of the contingency, $q_i$ is the size of a small dynamic var source (simulated by, e.g., SVC) added at bus $i$, and $V_{j,\text{new},t}^k$ and $V_{j,\text{old},t}^k$ are the voltage magnitudes...
respectively with and without that small var source at time $t$. The LP algorithm determines $Q_i$ from $Q_i^0$ by these two steps:

1) Time-domain simulation is performed with SVCs of sizes $Q_i^0 (i \in I_0)$ added to the candidate buses. Then, add a small amount $Q_i (i \in I_0)$, e.g. $Q_i^0 / 80$, is added to each candidate bus and the simulation under the contingency is performed again. Calculate $FSI_k^0 (i \in I_0)$ for the voltage responses with and without $Q_i (i \in I_0)$.

2) The direction to update $Q_i^0$ to $Q_i=Q_i^0+\Delta Q_i$ is determined by testing $FSI_k^0$ under contingency $k$. Then, the amount of update $\Delta Q_i$ is determined by solving a LP problem which utilizes the voltage responses obtained from 1).

The detailed algorithm in 2) is given below. Define

$$\Delta V_j^{i,k} = \min(v_j^{i,k} - v_j^{i',k}, t = 1, \cdots, T), j = 1, \cdots, N, k = 1, \cdots, K$$

(10)

$$\Delta V_j^{i,k} = \min(v_j^{i,k} - v_j^{i',k}, t = 1, \cdots, T), j = 1, \cdots, N, k = 1, \cdots, K$$

(11)

where $V_j^{i,k}$ is the voltage of bus $j$ at time $t$ under contingency $k$, and $V_j^{i',k}$ are closest voltages under the contingency $k$, respectively the lower and upper limits of bus $j$ voltage. The magnitudes of $\Delta V_j^{i,k}$ and $\Delta V_j^{i,k}$ are actually the closest distances from the voltage trajectory to the two limits under contingency $k$. $\Delta V_j^{i,k}$ is positive if the trajectory is above (below) the limit, or negative, otherwise. Then the following LP problem is solved to determine $\Delta Q_i (i \in I_0)$.

Minimize $f = \sum_{i=1}^{N} c_i Q_i$  

subject to $Q_i = Q_i^0 + \Delta Q_i, \forall i \in I_0$  

(13)

$-\alpha_k \sum_{i=1}^{N} (VSI_{ij})^T \Delta Q_i \leq \Delta V_j^{i,k}, \forall i \in I_0, j = 1, \cdots, N, k = 1, \cdots, K$  

(14)

$\beta_k \sum_{i=1}^{N} (VSI_{ij})^T \Delta Q_i \leq \Delta V_j^{i,k}, \forall i \in I_0, j = 1, \cdots, N, k = 1, \cdots, K$  

(15)

$$Q_i (i \in I_0) \in \text{Vor}(Q_i^0 (i \in I_0))$$  

(16)

where $\alpha_k$ and $\beta_k$ are acceleration factors with a default value of 1. The above LP problem can approximately find the minimum var requirement to improve the post-fault voltage performance by pushing the post-fault voltage trajectories close to the lower voltage limit as much as possible. $\Delta Q_i (i \in I_0)$ are solved to update $Q_i^0 (i \in I_0)$ for the next iteration. The constraints (14)-(15) are required because the voltage response is expected to stay within the two limits and approach the lower limit to save the total cost. The constraint (16) is also considered in this LP algorithm because the voltage size has to stay within the most effective searching space which is the Voronoi region of tentative optimum.

C. No. 2 and No. 3 New Points Respectively for Global Fidelity and Connection of the First Two

For the global fidelity purpose, a region where existing sample points are depopulated must be effective. Under the terminology of the Voronoi diagram, each Voronoi point is the farthest point from its surrounding sample points. A second sample point is chosen based on the largest $dis(p, e)$ and $e_i$ is the candidate new second point. Taking Fig. 9 as an example, since $e_4$ is the farthest point to any surrounding $p$ points, it will be the second new sample point if needed.

After the first and second sample points are added, the densities of samples around the tentative optima and around the most depopulated one become quite different. In order to connect the parts of both areas, a third sample point is chosen at the middle point of the straight line connecting the first and second sample points.

As a remark on the proposed approach, the use of the Voronoi diagram together with Barycentric interpolation enables effective cost function approximation for the entire solution space: on one hand, the Voronoi diagram identifies a relatively flat local region for the LP to efficiently optimize the solution; on the other hand, the Voronoi diagram adds new sample points to the most depopulated region to address the global approximation fidelity.

VI. CASE STUDIES

The proposed approach is first illustrated on the WSCC 9-bus system in detail and then tested on the NPCC 14-bus system. The simulation time for each contingency is 5 seconds and integration time step is 1/120s. In the case studies, we assume that all $c_p=\$1,000/Mvar, \ c_p=\$300,000/contingency for the WSCC 9-bus system and $c_p=\$3,000,000/contingency for the NPCC system. All buses in one system have the identical penalty for any voltage violation.

A. SVC and Load Modeling

Dynamic models of the dynamic var sources and loads are important for credibly simulating the phenomena of FIDVR and the performance of dynamic var supporting. In case studies, each SVC adopts the PSS/E CSVGN5 SVC model and each load is represented by the PSS/E ELODDBL load model [20]. In the following, the SVC and load models will be briefly introduced. For more details on the parameter settings and the functions of the models, please see [20].

| TABLE I PARAMETERS FOR THE SVC MODEL [20] |
|---------------|-----------|------|
| Parameter    | Range     | Value |
| $T_{S1}$, Filter Lag Time Constant/s  | $<0.4$ | 0 |
| $V_{E\text{MAX}}$, Voltage Error Max./pu  | $<0.3$ | 0.15 |
| $T_{S3}$, 1st Stage Lead Time Constant/s | $<2$ | 0.1 |
| $T_{S3}$, 1st Stage Lead Time Constant/s | $0, 5$ | 4.5 |
| $T_{S4}$, 2nd Stage Lead Time Constant/s | $<2$ | 0 |
| $T_{S5}$, 2nd Stage Lead Time Constant/s | $<5$ | 0 |
| $K_{SVS}$, Gain | $50, 1000$ | 50 |
| $K_{S2D}$, Time Constant/s | $0, 1000$ | 0 |
| $B_{\text{MAX}}$, Max. Susceptance of SVC/pu | $(0, 10)$ | 1 |
| $B_{\text{MIN}}$, Threshold Upper Limit/pu | $< B_{\text{MAX}}$ | 0.9 |
| $B_{\text{MIN}}$, Threshold Lower Limit/pu | $> -2 B_{\text{MAX}}$ | -0.9 |
| $B_{\text{MIN}}$, Min. Susceptance of SVC/pu | $< B_{\text{MIN}}$ | -1 |
| $T_{SV}$, Thyristor Delay/s | $(2 \pm 0.2)$ | 0.05 |
| $D_{V}$, Deviation Voltage/pu | $(0, 0.5)$ | 0.15 |

The PSS/E SVC model CSVGN5 is represented as a generator in the power flow model with features including...
remote bus voltage control and a fast override capability. Main parameters used in case studies are listed in the first column of Table I. Suggested ranges of their values are provided in the second column and the values adopted in case studies are given in the third column. The control blocks and voltage control characteristics of the SVC are shown in Fig. 10 and Fig. 11. The fast override function in Fig. 10 is activated when the voltage error exceeds a threshold value $DV$ during a fault near the SVC to make the SVC act as a capacitor or reactor. Otherwise, the SVC behaves following the slope $K_{SVS}$ shown in Fig. 11. The MBASE in Fig. 10 is the Mvar output of the SVC and takes the optimized size for this SVC.

As a composite load model, the CLODBL contains large induction motors (LMs), small induction motors (SMs), discharge lighting, distribution transformers with saturation effects, and other static load components as shown in Fig. 12. All load components are assumed to be connected at 0.98 pu voltage. Table II lists the parameters used in case studies.

![Fig. 10. Control blocks of the CSVGN5 SVC model [20].](image)

![Fig. 11. Voltage-reactive power characteristic of CSVGN5 SVC [20].](image)

![Fig. 12. CLODBL load model.](image)

<table>
<thead>
<tr>
<th>Parameter</th>
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![Fig. 13. Contour map of approximated function and Voronoi diagram constrains for linear programming during cumulative global optimization.](image)
B. WSCC 9-Bus System

To illustrate the proposed Voronoi diagram based approach, optimization of the sizes of 2 SVCs at bus 6 and bus 8 is considered. The tolerance in the stopping criterion of iterations is $\varepsilon = 1000$. The global optimum is found after 3 iterations. Fig. 13 shows the progress of a contour map on the objective function updated with the addition of new samples and how the tentative optimal solution approaches to the actual global optimum. All tentative optimal solutions are checked by the dark solid curves in Fig. 13(a-d) which indicate the boundary of actual feasible solution. Fig. 13(e) illustrates the Voronoi boundary of the tentative optimum in each searching iteration.

Fig. 13(a) gives the initial solution with $f = 75,000$ at $(Q_6 = 68 \text{ Mvar}, Q_8 = 7 \text{ Mvar})$ under the initial approximation with 10 sample points. In Fig. 13(b), the solution is updated to $f = 59,000$ at $(Q_6 = 58 \text{ Mvar}, Q_8 = 1 \text{ Mvar})$ with 13 sample points after the first iteration. In Fig. 13(c), the tentative solution is moved to $f = 57,000$ at $(Q_6 = 56 \text{ Mvar}, Q_8 = 1 \text{ Mvar})$. In Fig. 13(d), the shapes of the cost function in polygons are further refined specifically for the areas around the true optimum, and the global optimal solution as indicated by the arrow has $f = 57,000$ at $(Q_6 = 56 \text{ Mvar}, Q_8 = 1 \text{ Mvar})$. The solution obtained from the proposed approach is verified to be the same as the global optimum found by exhaustive search.

Fig. 14 illustrates bus voltage profiles in time domain without and with the optimal dynamic var supporting. In Fig. 14(a), FIDVR is seen on the voltage trajectories of 5 out of 9 buses without any var support. During the transient period, one load bus violates $C_1$, i.e. the 75% of initial voltage lower limit, and four buses violate $C_2$, i.e. the voltage duration between 75% and 80% of the initial voltage longer than 20 cycles. Also, at the post transient period, two buses violate $C_3$, i.e. the 5% deviation limit. The severity index $S$ of the system under this contingency is 0.0079 pu. Fig. 14(b) shows all of voltage trajectories meet the voltage criteria with the optimally sized SVCs, indicating a severity index of zero.

C. NPCC System

The proposed approach is also tested on the NPCC 48-generator 140-bus system as shown in Fig. 15, which represents a simplified equivalent of the northeast region of the Easter Interconnection power grid. Consider 7 SVCs to be installed at seven predetermined buses 3, 6, 7, 12, 16, 34, and 56, which are optimized by the empirical controllability covariance based fault specified method in [6], to mitigate the FIDVR issues under the most severe “N-1” contingency. Assume that the size of each SVC ranges from 0 to 400 Mvar. The tolerance in the stopping criterion of iterations is $\varepsilon = 5000$. Fig. 15 illustrates bus voltage profiles in time domain without and with the optimal dynamic var supporting. In Fig. 15(a), FIDVR is seen on the voltage trajectories of 5 out of 9 buses without any var support. During the transient period, one load bus violates $C_1$, i.e. the 75% of initial voltage lower limit, and four buses violate $C_2$, i.e. the voltage duration between 75% and 80% of the initial voltage longer than 20 cycles. Also, at the post transient period, two buses violate $C_3$, i.e. the 5% deviation limit. The severity index $S$ of the system under this contingency is 0.0079 pu. Fig. 15(b) shows all of voltage trajectories meet the voltage criteria with the optimally sized SVCs, indicating a severity index of zero.

![Fig. 15. NPCC system and the most severe N-1 contingency and seven candidate buses for dynamic var sources (important buses are highlighted in the following discussion).](image-url)

![Fig. 16. Searching path of the optimization of dynamic var on the NPCC system under the most severe N-1 contingency.](image-url)
The most severe “N-1” contingency is identified to be the outage of line 6–7 by a three-phase-to-ground fault on bus 6 with 5-cycle clearing time. Starting an initial estimate based on $2 \times (7+1)=16$ initial sample points and $2^7=128$ geometric vertices, the approach adds three new points for each iteration. Fig.16 shows the trajectory of iterations converging to an optimum in the spider chart. The initial estimate of optimum $f=1,240,000$ is at $(400, 400, 10, 10, 10, 400, 10)$ in the space about $Q_3, Q_6, Q_7, Q_{12}, Q_{16}, Q_{34}$, and $Q_{56}$. After the first iteration, the tentative optimum is found to be $f=1,120,000$ with $Q_3=400$ Mvar, $Q_6=Q_{34}=360$ Mvar, and others to be 0 Mvar. Finally, after 12 iterations, the search stops at an optimum having $f=1,055,000$ with $Q_3=Q_6=400$ Mvar, $Q_{34}=255$ Mvar, and others 0 Mvar. An exhaustive search is performed in the seven-dimensional solution space and that obtained solution after 12 iterations is verified to be the true global optimum.

**Fig. 17.** Post-fault voltage responses of NPCC most severe N-1 system.

Fig. 17 illustrates bus voltage profiles in time domain simulation without and with the optimal SVC support. In Fig. 17(a) shows the delayed voltage recovery phenomenon without any var support in which 5 buses violate $C_1$ at the beginning of the 3-second transient period and some buses violate $C_3$ in the post transient period, the severity index $S^f$ for the contingency without any var support is 0.0034 pu and the network loss is 1.3356% of the total system load. Fig. 17(b) shows the all of voltage trajectories meet the voltage criteria with the obtained optimal sizes of SVCs, the severity index becomes zero with optimized var support and the network loss slightly reduces to 1.3267% of the total system load.

**TABLE III**

<table>
<thead>
<tr>
<th>LM/%</th>
<th>SM/%</th>
<th>Optimized Var Sizes/Mvar</th>
</tr>
</thead>
<tbody>
<tr>
<td>25</td>
<td>25</td>
<td>[400, 400, 0, 0, 0, 255, 0]</td>
</tr>
<tr>
<td>22.5</td>
<td>22.5</td>
<td>[395, 400, 0, 0, 0, 5, 0]</td>
</tr>
<tr>
<td>20</td>
<td>20</td>
<td>[230, 400, 0, 0, 0, 0, 0]</td>
</tr>
<tr>
<td>17.5</td>
<td>17.5</td>
<td>[50, 400, 0, 0, 0, 0, 0]</td>
</tr>
</tbody>
</table>

**Fig. 18.** Optimal sizes of dynamic var sources under different load condition.
five independent tests are performed in order to find the average performance of the approach. Each test starts from $2(|IQ|+1)$ random initial sample points followed by $2^{|IQ|}$ geometric vertices and then adds 3 new sample points per iteration. For each test, a large number of iterations are performed to observe the convergence performance of the approach. All tests model each load bus with 25% LMs load and 25% SMs load. The best locations of SVCs are determined by the method in [6]. The environment to test time performance of the approach is a desktop computer with 3.6 GHz I7-4790 CPU and 16 GB RAM.

For 5 SVCs, they are placed at buses 3, 6, 12, 19, and 30. Each test starts from $2 \times (5+1)=12$ initial sample points and $2^5=32$ geometric vertices. From the Fig. 19, after only 8 iterations, all tests converge to the total cost of $1,175,000$ with an optimum at (400, 0, 0, 0, 375) about $Q_3$, $Q_6$, $Q_{12}$, $Q_{19}$, and $Q_{30}$, respectively.

For 6 SVCs, they are placed at buses 3, 6, 7, 12, 34, and 56. Each test starts from $2 \times (6+1)=14$ initial sample points and $2^6=64$ geometric vertices. From Fig. 20, after 12 iterations, all tests converge to the total cost of $1,055,000$ at (400, 0, 255, 0) about $Q_3$, $Q_6$, $Q_7$, $Q_{12}$, $Q_{34}$, and $Q_{56}$.

For the tests on 7 SVCs, starting with $2 \times (7+1)=16$ initial sample points and $2^7=128$ geometric vertices, the approach takes 15 iterations to have all tests converge to the optimum, as shown in Fig. 21.

The above tests show that the proposed approach quickly converges to the optimum after iterations of a moderate number, which is not sensitive to the selection of initial sample points.

For the tests above on optimizing 5, 6, and 7 SVCs, Table IV gives the time performances of the proposed approach. The initial stage on $2(|IQ|+1)+2^{|IQ|}$ points takes respectively 439 s, 778 s and 1436 s, which each include the times for the time-domain simulation in PSS/E and the cost function calculation on initial sample points and creation of the initial Voronoi diagram in MATLAB. The time cost per point is about 10s. The iteration stage takes 728 s, 1320 s, and 1980 s, respectively for 8, 12, and 15 iterations, i.e. the worst one among five tests. The time costs on one iteration are 91 s, 110 s, and 132 s, respectively, each including the times for evaluating 3 new points, LP, and updating the Voronoi diagram.

| No. of SVCs | Initial stage time cost on $2(|IQ|+1)+2^{|IQ|}$ points (s) | Iteration stage time cost (s) | Total time (s) |
|-------------|---------------------------------------------------|---------------------------|---------------|
| 5           | 439                                               | 91 x 8 = 728             | 1167          |
| 6           | 778                                               | 110 x 12 = 1320          | 2098          |
| 7           | 1436                                              | 132 x 15 = 1980          | 3416          |

Fig. 22. Time costs for optimizing 5, 6 and 7 SVCs

Fig. 22 depicts the bar chart and the trends on the total time costs, where the light and dark regions of each bar respectively represent the time costs on the initial stage and on the iteration stage. The total time cost will grow exponentially with the increase of the number of dynamic var sources. This approach can be applied offline to solve the optimal sizing problem in the planning stage. In practice, the total number of dynamic var sources, e.g. SVCs and STATCOMs, needed by an electric
utility company is not large (typically, <10), and if necessary, high-performance computers may be applied to solve the problem in a faster manner.

VII. CONCLUSION

This paper proposes a new approach for solving optimal sizes of dynamic var sources against the FIDVR issues. The geometric characteristics about the non-convex solution space of this problem has been studied. Accordingly, a Voronoi diagram based approach integrating LP was proposed and illustrated on the WSCC 9-bus system by case studies. The approach was also validated on the NPCC 140-bus system to quickly give the optimal sizes of seven SVCs against the most severe “N-1” contingency.

REFERENCES


BIographies

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