



INVERTER DEAD-TIME ELIMINATION FOR REDUCING HARMONIC DISTORTION AND IMPROVING POWER QUALITY

R.Narmatha

II.M.E-Power Electronics & Drives, Muthayammal Engineering College, Rasipuram Namakkal, India

T.Govindaraj

Head of Electrical and Electronics Engineering, Muthayammal Engineering College, Rasipuram, Namakkal, India

ABSTRACT

Numerous studies have been presented to eliminate dead-time effect. This paper will present a dead-time elimination scheme for a sinusoidal pulse width modulation (SPWM) controlled inverter. In comparison to using expensive current sensor, this method precisely determine the load current polarity by detecting the terminal voltage of the antiparallel diode of power devices. The presented scheme includes the freewheeling current polarity detection circuit and the PWM control generator without dead-time. This method significantly reduces the output voltage loss, harmonic distortion and improves quality of power. Simulation results are given to demonstrate the effectiveness of the dead-time elimination scheme.

Keywords: Dead time elimination, Sinusoidal pulse width modulation (SPWM).

INTRODUCTION

The state of the art in motor control provides an adjustable voltage and frequency to the terminals of the motor through a pulse width modulated (PWM) voltage source inverter drive. As the power devices change switching states, a dead time exists. Dead-time is used for sinusoidal pulse width-modulation (SPWM)-controlled inverter control to avoid “short through” of high-side and low-side power devices. The dead-time mainly depends upon characteristics of power devices and gate drive circuit. The effects of dead time include output voltage loss and current distortion. These effects become relevant as voltage is low and switching frequency is high. Moreover, addition of dead time to a PWM-controlled inverter also affects the common-mode voltage.

Several methods have been presented to deal with the dead-time issue. These methods include dead-time compensation, dead-time elimination and dead-time minimization. To overcome the dead-time effects, the authors (Yong Wang, Qiang Gao, and Xu Cai, 2011) propose many dead-time

compensation solutions. They are all developed based upon the knowledge of the current direction. In order to determine the direction of current, an accurate current sensor is required. However, the result is highly affected by the harmonics around the zero-crossing points, particularly when the current is small. For the dead-time minimization method, dead time is still required when the current is around zero-crossing points in which current polarity detection is difficult and not accurate.

Table-1. Comparison of Different Methods

Method	Dead time compensation	Dead time elimination	Dead time minimization	Proposed method
Current sensor	o	x	o	x
Isolated power	x	o	x	x
Dead time	o	x	o	x

In (David and Russel, 2008; Yong and Yen, 2009), current polarity is determined by detecting the terminal voltages of the antiparallel diode of a power device. Therefore, the dead-time elimination method is developed based upon the detection method. However, two power sources are required for each inverter leg or half-bridge of converter. For a three-phase inverter, four power sources for such detection circuits are required. Moreover, the conduction states of power antiparallel diode are detected only at the instants of rising edge of chop on, as shown in. It may result in detection error due to switching noise and current ripple in practice and therefore cause commutation error.

More details of the comparisons are summarized in Table I. There are three categories: dead-time compensation; dead-time elimination; and dead-time minimization. This paper will present a dead-time elimination scheme for PWM-controlled inverter. The presented dead-time elimination scheme does not require separate power supplies for freewheeling-current detection of high- and low-side power devices. Therefore, only one power source is required for freewheeling-current polarity detection of three-phase inverter/converter.

The presented scheme includes the freewheeling-current polarity detection circuit and the PWM control generator without dead time. Current polarity is detected regularly with a sampling

frequency which is higher than the switching frequency to reduce the detection error. Simulation results are shown to demonstrate the effectiveness.

Fig-1. Dead time effect

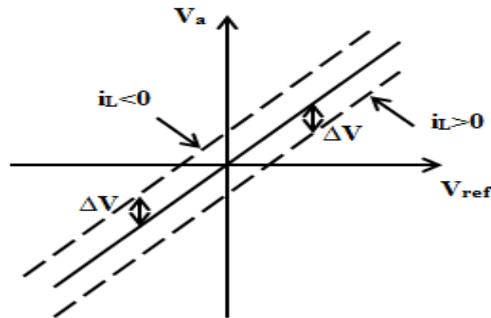
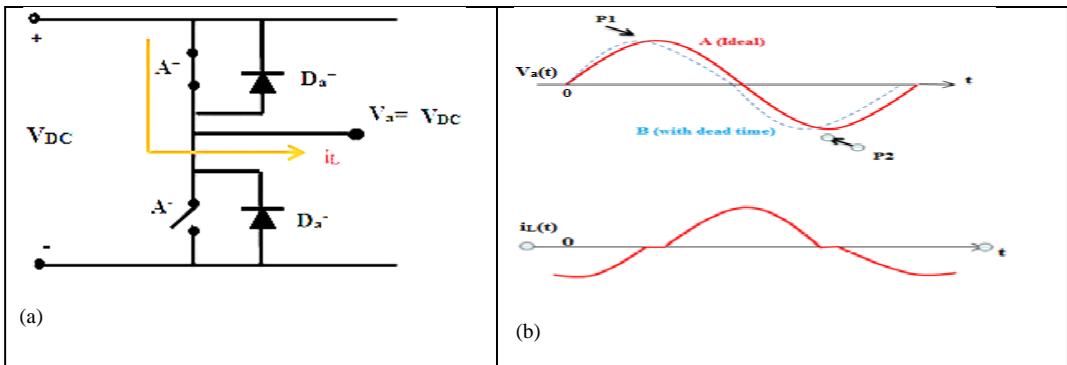


Fig-2. Voltage distortion caused by dead time. (a) Inverter/converter leg. (b) Voltage distortion caused by dead time



EFFECT OF DEAD TIME

When ac induction motors are operated using open-loop adjustable frequency drives, system instabilities may occur for certain frequency ranges and loading conditions. The cause of these instabilities can be inherent low-frequency motor instabilities, instability due to the interaction between the motor and the PWM inverter, or the choice of PWM strategy.

When the ac induction motor is fed by the voltage source inverter, the applied stator voltage waveforms contain harmonics generated by the PWM algorithm. The system stability will be affected by these harmonics, especially at low frequencies and no load conditions, causing additional machine losses and reduced efficiency. The magnitude of these losses will depend on the magnitude of the harmonic content in the applied voltage and are compounded by induced harmonics. Excessive harmonics will increase motor heating and torque pulsations. Even the

smallest of harmonics as a percent of the fundamental, when coupled with the motor, can result in unstable operation. The choice of the PWM strategy is then important to minimize the voltage and current harmonics. Defects in the PWM strategy will result in voltage deviations at the motor terminals and will be intensified by the addition of the inverter dead time.

The effects of the dead time on the output voltage are shown in Fig. 1. It can be examined from one phase of the PWM inverter. The basic configuration shown in Fig. 2 consists of upper and lower power devices A^+ and A^- , and reverse recovery diodes D_{a^+} and D_{a^-} , connected between the positive and negative rails of the power supply. Commutation of the power devices comes from the PWM generator. Output terminal V_a is connected to motor phase V_a and the current i_L is positive with respect to the motor. Examining the power device switching sequence as A^+ is turning OFF and A^- turning ON, or A^- is turning OFF and A^+ turning ON, there exists a time when both power devices cease to conduct. During the dead time output V_a appears to be floating, but the current i_L must conduct through reverse recovery diodes D_{a^+} and D_{a^-} . Depending on the current polarity, the reference voltage may be delayed by the dead time.

Consider the four possible commutation sequences. In the first condition, the current i_L is positive. A^+ transitions from ON to OFF and A^- from OFF to ON. During the dead zone, D_{a^-} conducts and D_{a^+} blocks the flow of current to the positive rail. This condition results in the correct voltage applied to the motor terminals.

In the second condition, the current i_L is positive. A^+ transitions from OFF to ON and A^- from ON to OFF. During the dead zone, D_{a^-} continues conduction and D_{a^+} blocks the flow of current to the positive rail. Current conducts in D2 until the dead time elapses, then A^+ turns ON. This condition results in a loss of voltage at the motor terminals.

In the third condition, the current i_u is negative. A^+ transitions from OFF to ON and A^- from ON to OFF. During the dead zone, D_{a^+} conducts and D_{a^-} blocks the current flow to the negative rail. This condition results in the correct voltage applied to the motor terminals.

For the fourth condition, the current i_L is negative. A^+ transitions from ON to OFF and A^- from OFF to ON. During the dead zone, D_{a^+} continues conduction and D_{a^-} blocks the flow of current to the negative rail. Current conducts in D1 until the dead time elapses, then A^- turns ON. This condition results in a gain of voltage at the motor terminals.

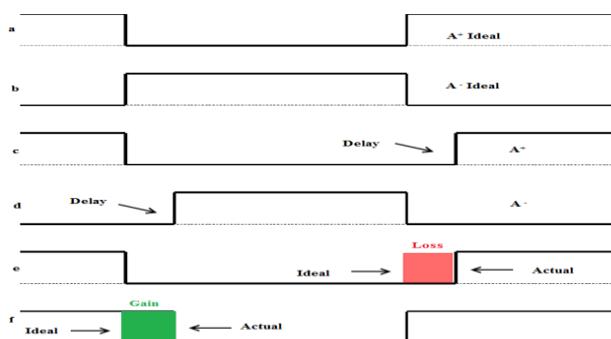
Fig-3. Pulse deviations (Afarulrazi and Zarafi, 2010)

Fig. 3 shows the effect of dead-Time. Trace 3a and 3b are the ideal pulse times; if applied, the resulting fundamental voltage would be of the correct magnitude and phase. In trace 3c, A^+ transitions from ON to OFF, but there must be a delay time before A^- in trace 3d can turn from OFF to ON. Likewise as A^- in trace 3d transitions from ON to OFF, A^+ in trace 3c must delay before it can turn on.

Consider i_u positive in trace 3e, as A^+ transitions from ON to OFF, there is no reduction or gain to the pulse time as compared to the ideal pulse time. As A^+ transitions from OFF to ON, the pulse time decreases from the ideal resulting in a deviation to the pulse time and an incorrect fundamental voltage to the load.

When i_u is negative as in trace 3f, A^+ is held on longer than the ideal, resulting in an increase in pulse time, and an incorrect fundamental voltage applied to the load. As A^+ transition from OFF to ON, there is no reduction or gain to the pulse as compared to the ideal pulse.

Therefore, the real output voltage is greater (smaller) than its command as current is negative (positive). Fig. 2 shows the phase voltage and current of the inverter output. As shown in Fig. 2, the output voltage $v_o(t)$ is with distortion as compared to that without dead time (see waveforms A and B). However, waveforms A and B cross each other at points P1 and P2. The output current $i_o(t)$ is also distorted at these two zero-crossing points, as shown in Fig. 2.

PROPOSED DEAD-TIME ELIMINATION SCHEME

A. PWM Generator Without Dead Time

Fig. 3(a) shows the circuit of an inverter leg or half-bridge of converter. As shown in Fig. 3(a), an antiparallel diode is connected with a power device. As the power device is off while the current conduction continues, the antiparallel diode of its opposite power device provides the current path. Therefore, there is no need to turn on the opposite power device during this turn-off period. Once no switching occurs to its opposite power device, dead time is no more needed.

For example, when power device “A+” is turned off and the current direction retains, “D_a⁻” will provide the current path when power device “A+” is turned off. Similar facts occur to power device “A-” and diode “D_a⁺”. Therefore, power device “A+” and diode “D_a⁻” are defined as a “P” cell for positive current control (current flowing into the load side), as shown in Fig. 3(b). In addition, power device “A-” and diode “D_a⁺” are defined as “N” cell [as shown in Fig. 3(b)], which conducts negative current.

Fig. 4 shows the PWM control without dead time. As shown in Fig. 4(a), once current is positive, P-cell control is retained. Meanwhile, there is no PWM control signal for N-cell control.

Therefore, dead time is no longer required while guaranteeing no short through between positive and negative dc links. Similarly, when current is negative, a PWM control signal is applied to N cell only. Since there is no switching in the power device of P cell, dead time is no longer needed, and no short through will occur.

Fig-4. PWM control based upon P cell and N cell. (a) P-cell control, $i_L > 0$. (b) N-cell control, $i_L < 0$.

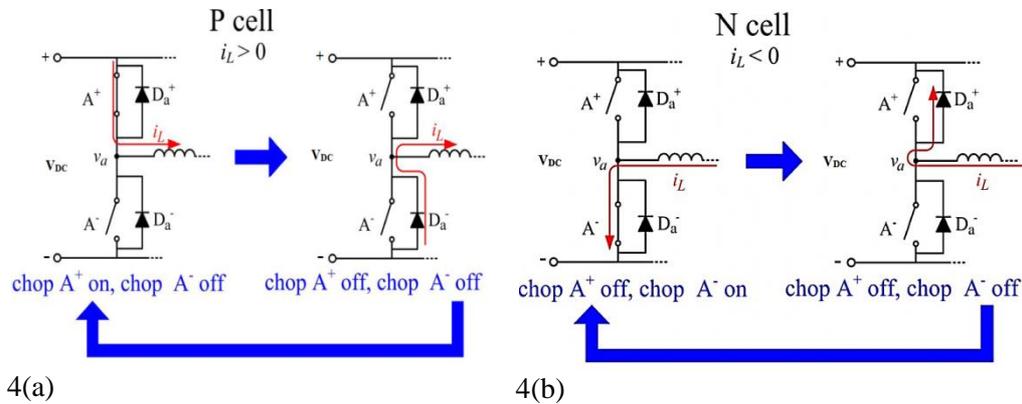


Fig. 5 shows the relationship between the chop signals and the control signals of converter without dead time. The control signals can therefore be summarized as follows:

$$\text{Chop A}^+ = \text{chop} \cdot \text{sign}(i_L) \quad (1)$$

$$\text{Chop A}^- = \text{chop} \cdot \text{sign}(i_L) \quad (2)$$

As shown in (1) and (2), the required calculation is simple, and only slight modifications to the PWM signal are required. Furthermore, the modifications can be realized by a digital controller. For inverter control, the chop signal is changed to a PWM control signal. The PWM generator can be realized using (1) and (2).

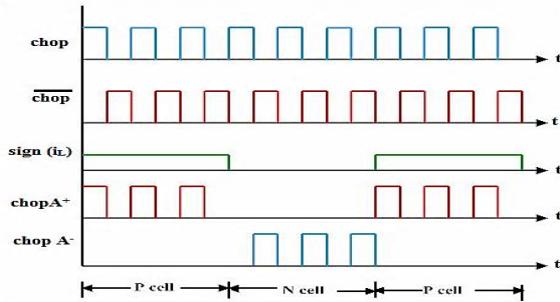


Fig-5. Signals for PWM generator.

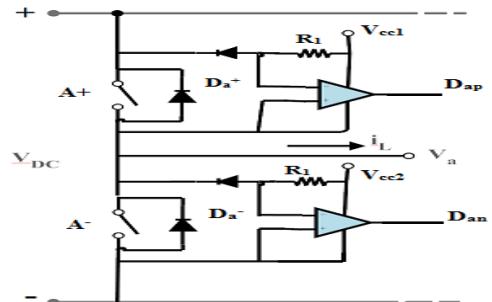


Fig-6. Previous detection circuit (Artur)

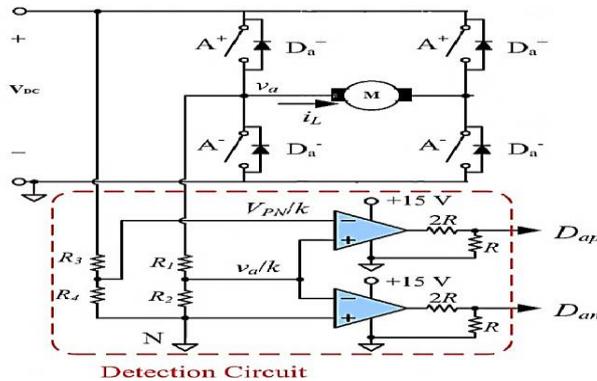


Fig-7. Proposed detection circuit.

B. Freewheeling-Current Polarity Detection Circuit Without Isolated Power

Fig. 6 shows the polarity detection of freewheeling current. The detection circuit requires two separate power sources, namely, “Vcc1” and “Vcc2,” as shown in Fig. 6. The required number of separate power sources is increased up to four for a three-phase inverter. These separate power sources increase the difficulty for modularization of the detection circuit.

Fig. 7 shows the presented freewheeling-current polarity detection circuit. As shown in Fig. 7, only one power source is required for the detection circuit for both single- and multiphase inverter/converter. This special feature provides the potential of modularization of the detection circuit. In Fig. 7, when $iL > 0$, the terminal voltage becomes negative during the switch-off period, as shown in Fig. 8(a). Similarly, during the switch-off period, the terminal voltage is positive and greater than the dc-link voltage when $iL < 0$, as shown in Fig. 8(b). Therefore, the terminal voltage can be used to reflect the polarity of freewheeling current. Once the polarity of current is determined, the control signals of converter/inverter can be generated by (1) and (2).

C. Freewheeling-Current Polarity Detection for Current With Multiple Zero-Crossing Points

Under some conditions, e.g., small inductor of load, the output current polarity changes very quickly in the zero-crossing area. There may be a few zero-crossing points, as shown in Fig. 9.

To deal with such ambiguous situation, the concept of average current is used as an assistance index for the judgment of current polarity. Note that no real average value of load current is

calculated. Once the period between “chop off” and zero crossing point is slightly greater than $0.5(1 - D)t_s$, the average current becomes negative, and the current polarity is changed. The polarity change rule is therefore modified as follows. If

$$t_k > \frac{1}{2}(1 - D)t_s \quad (3)$$

then $i_{L,avg} > 0$, and there is no change of current polarity. If

$$t_k \leq \frac{1}{2}(1 - D)t_s \quad (4)$$

then $i_{L,avg} \leq 0$, and the current polarity is changed, where t_k = time interval between “chop off” and zero-crossing point ($k = 1, 2, 3, \dots$).

The presented circuit for the dead-time elimination circuit and the method are indeed effective. In the presented paper, dead time is not required, and the power device (e.g., high-side power device) is turned on only when the antiparallel diode of its counterpart (low-side power device) is conducting current. Therefore, the possibility for ZVS seems dim.

Fig-8. Terminal voltage and PWM control signals without dead time. (a) $i_L > 0$ (b) $i_L < 0$

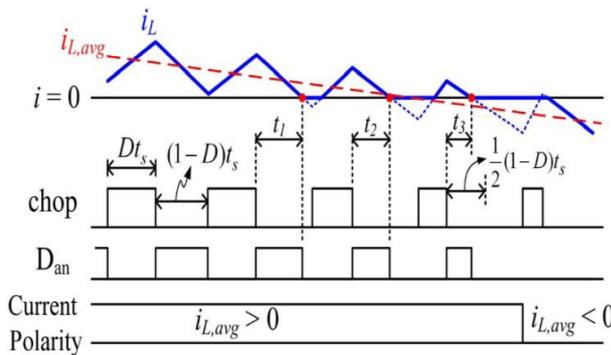
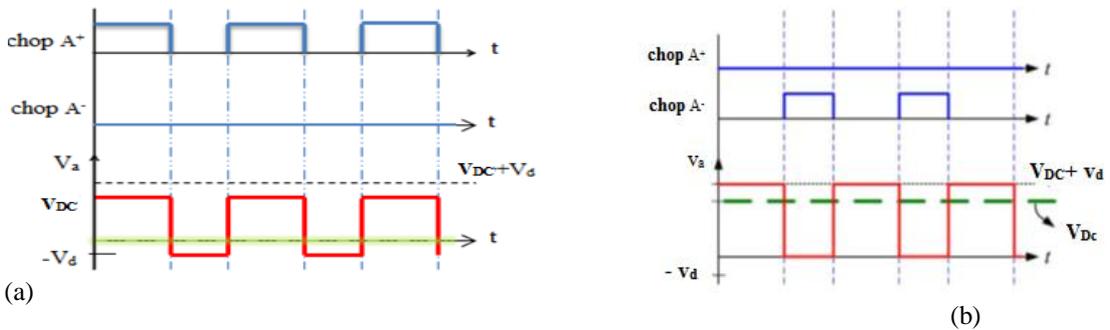


Fig-9. Load current with several crossing points around zero-current area

SIMULATION RESULTS

Fig. 10 shows the flowchart of the PWM generator without dead time. The “P”-cell control signal is switched on and off when current is negative. The polarity of freewheeling current is detected regularly with a sampling frequency which is higher than the switching frequency to reduce the detection error. In this section, the simulation performed by MATLAB software is carried out to verify the proposed method. The schematic of the SPWM voltage source converter power stage used for the simulation is shown in fig.11. The induction motor is chosen for the load of the inverter. The simulations with both the conventional SPWM strategy with dead time and the proposed method are carried out for comparison. Fig. 4 shows the simulation waveform of I_L using the conventional PWM strategy with dead time. From the simulation results it can be seen that the output current is distorted. Fig. 12(b) shows the simulation waveforms using the proposed Method. From Fig. 12(b) it can be seen that the switch commands to the upper and lower device of phase A, A^+ and A^- are complementary and without dead time.

As shown in Fig. 11, the proposed method can detect the polarity, and the PWM control signals do not require any dead time. Since the dead time for the presented method is eliminated, the current distortion associated with dead time can be removed.

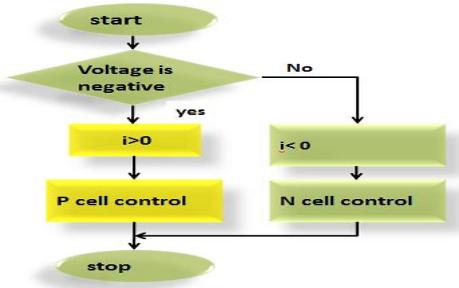


Fig-10. Flowchart of the implementation

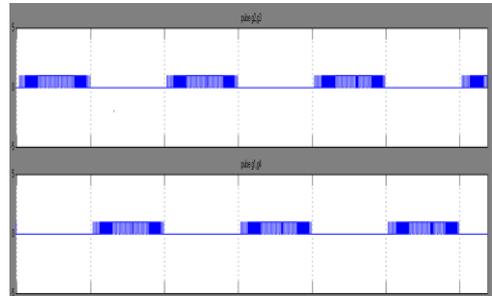
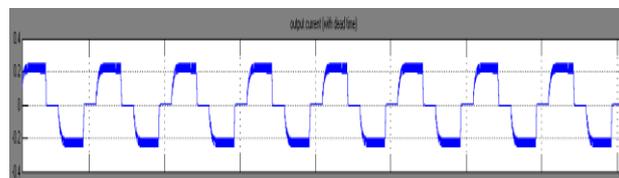
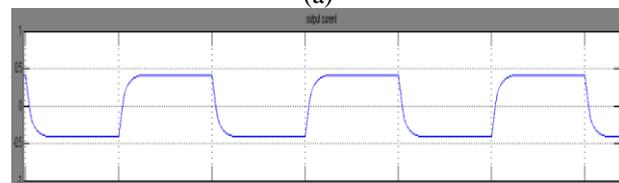


Fig-11. Gate pulses without dead-time



(a)



(b)

Fig-12. Current waveforms. (a) With dead-time. (b) Without dead-time

THD ANALYSIS

SPWM is an effective technique used for variable frequency drive applications. It utilizes dc bus voltage more effectively

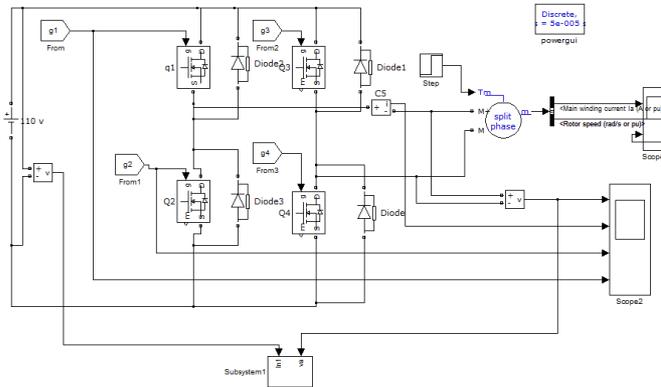


Fig-13. Simulation Diagram

and generates less THD in the Voltage Source Inverter. SPWM utilize a switching frequency to spread the harmonics continuously to a wide band area so that the peak harmonics can be reduced greatly. Simulation has been carried out by varying the modulation index between 0 and 1. Finally performance of SPWM has been compared with and without dead time. The harmonic spectrum of SPWM inverter with and without dead time is shown in fig. 14.

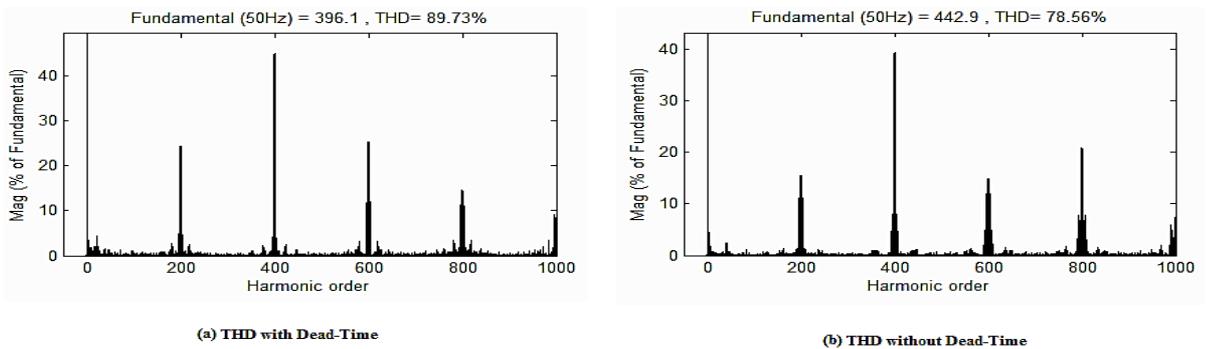


Fig-14. Harmonic spectrum of SPWM inverter

CONCLUSION

In this paper, a method was proposed to eliminate dead time in the SPWM controlled inverters. Compared to the conventional method with dead-time, this method significantly reduces the output distortion and THD and improves the performance of the load. The contributions of this paper include the following.

- 1) Propose a current polarity detection circuit which requires one power source only for inverter.

- 2) Present the PWM control method without dead time based upon the proposed current polarity detection circuit
- 3) Flexible implementation makes it an attractive option for VSI applications.

This method can be used in the voltage source PWM converter to improve the performance, increase the reliability, and reduce the cost.

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