V International Scientific and Technical Conference Actual Issues of Power Supply Systems

Modeling of the Measuring Unit with MMD for Ground Faults in Power System

AIPCP25-CF-ICAIPSS2025-00353 | Article

Modeling of the Measuring Unit with MMD for Ground Faults in Power System

Nodir Ataullaev [1,a)], Amin Ataullaev[1], Bobur Muxammadov[1], Amin Ataullaev[2]

[1]*Navoi State University of Mining and Technologies, Navoiy, Uzbekistan*
[2] *Andijan State Technical Institute, Andijan, Uzbekistan*

[a)] *Corresponding author: nodir-82@list.ru*

Abstract. A measuring unit with a magnetically modulated device (MMD) for selective ground-fault detection in power systems is modeled. The unit extracts the differential current ΔIdiff from a high-frequency modulation signal and processes it using gain scaling, moving-average filtering, stability check, and synchronous detection. A trip signal is allowed only when both ΔIdiff exceeds the setting and the zero-sequence voltage U0 is above threshold, which prevents false trips under noise and capacitive unbalance. MATLAB/Simulink results show high sensitivity, fast response (<10 ms), and improved selectivity for mining power networks with variable parameters.

INTRODUCTION

The measuring unit with a magnetically modulated device (MMD) consists of two main subsystems: The measuring section, which includes two magnetic systems. The logical section, which implements algorithms for signal processing and filtering [1]. This unit generates the differential current signal ΔI_{diff} based on the high-frequency amplitude-modulated voltage that arises during the saturation of the MMD core. The resulting signal contains: the fundamental modulation frequency (10–20 kHz), the second harmonic (2× excitation frequency), and a low-frequency component proportional to $\Delta I_{diff.}$

To extract ΔI_{diff}, a synchronous detector is employed, which multiplies the signal by the reference frequency and integrates the result over one period, thereby producing a voltage:

$$U_{дет} = \frac{1}{T}\int_0^T U_2 \cdot sin(2\pi f_m t)dt \quad (1)$$

where T– is the period, adapted for real-time operation in power systems (response time < 10 ms).

EXPERIMENTAL RESEARCH

High-frequency noise arising from switching events and induced disturbances necessitates the use of sequential filtering logic, which integrates conventional approaches (low-pass filtering LPF) and amplification) with adaptive algorithms (analysis of U_0). The sequential filtering logic (Fig. 1) is designed as a multi-stage algorithm for processing the signals $I_{0\cdot start}$ and $I_{0.end}$ from two magnetic systems. It includes the following stages:

1.Signal synchronization: The signals are aligned with respect to inherent delays to ensure temporal coherence, which is critical for differential analysis.

2.Preliminary amplification and scaling: Within this framework, the signals pass through a cascaded amplification stage with coefficients analogous to Gain (0.01) and Gain (10), enabling normalization and amplitude compensation.

$$I_{0.norm}(n) = 0.01 \cdot \Delta I_{diff}(n), \quad (2)$$

$$I_{0.forced}(n) = 10 \cdot I_{0.norm}(n) = 0.1 \cdot \Delta I_{diff}(n) \quad (3)$$

3.Filtering of high-frequency noise: A moving average with a window of N=5N = 5N=5 samples is applied to suppress components above 200 Hz.

$$I_{0.filter}(n) = \frac{1}{N}\sum_{k=n-N+1}^{n} I_{0.forced}(k) \quad (4)$$

Stability analysis: The difference between the current and the previous values is verified.

$$\Delta I_{0.stab} = \left|I_{0.filter}(n) - I_{0.filter}(n-1)\right| \quad (5)$$

If $\Delta I_{0.stab}$<ε I (where ε=0.01 A), the signal is considered to be free from noise. Computation of the differential current: The filtered signals are used for:

4. Computation of the differential current: The filtered signals are used for:

$$\Delta I_{0.filter} = I_{0.filter.begin} - I_{0.filter.end} \quad (6)$$

5.Transfer to the control block: $\Delta I_{0.filter}$ $U_0$are transmitted for the formation of the trip signal.

The model of the measuring unit is presented in Fig. 1 and includes:

Two MMD magnetic systems: Modeled as Controlled Current Sources with S=0.1 V/, located at the input and output of the line [29-58].

Sequential filtering logic: A subsystem consisting of Gain (0.01), Gain (10), Moving Average (N=5N = 5N=5), Subtract for $\Delta I_{0.stab}$ and a Relational Operator for ε

Control block: Combines $\Delta I_{0.filter}$ and $U_0$for analysis.

Scope: Displays $I_{0.filter}$and $\Delta I_{0.filter}$

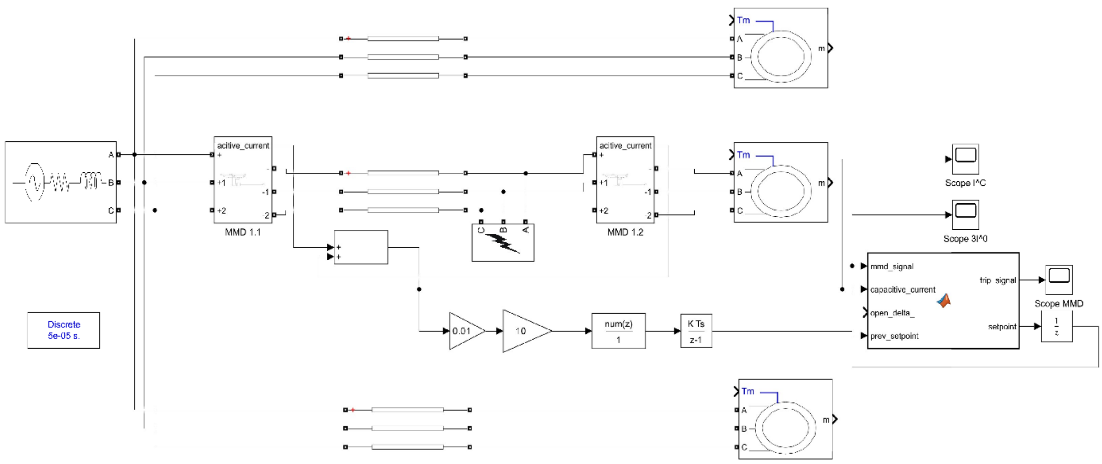


FIGURE 1. Diagram of the measuring unit with MMD for selective detection of single-phase-to-ground fault location in power systems (adapted: two MMDs at the line ends, filtering logic for energy complexes with RES, integration with SCADA).

The event of a single-phase-to-ground fault (phase A short-circuited through for 0.02 s), ΔI_{diff} increases, with the differential current:

$$\Delta I_{diff} = I_{0.begin} - I_{0.end} \quad (7)$$

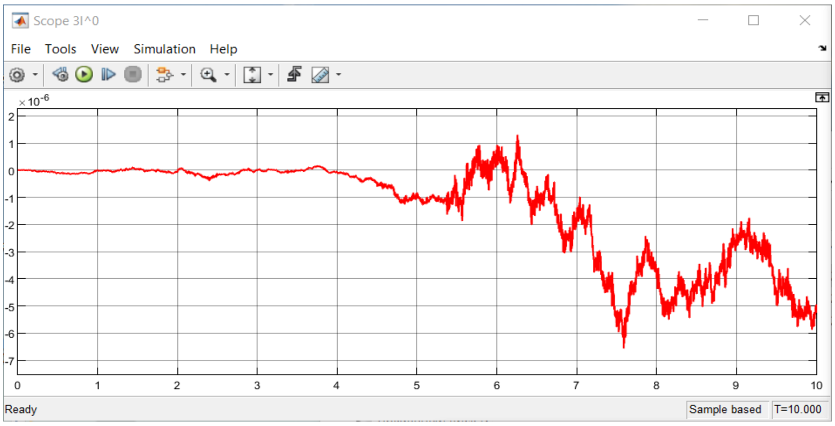
where $I_{0.start}$ and $I_{0.end}$ I_0 are the currents at the line ends. In the normal operating mode, ΔI_0<I_{set}=1.2·ΔI_{diff} ΔI_0<I_{set}=1.2·$\Delta I_{diff.}$ The filter attenuates noise (amplitude 0.05 A, 200 Hz) to a level suitable for analysis.

RESEARCH RESULTS

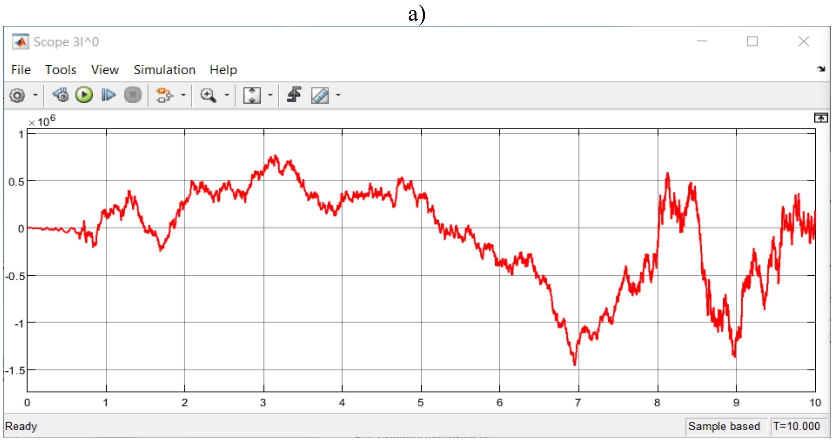
Synchronization with U_0 confirms the combined approach: the trip signal is generated only when (U_0>U_{th})↔(ΔI_{diff}>I_{set}) leftrightarrow, thereby avoiding false tripping.

The filtering logic is integrated with the control block. The setting value and trip signal are defined as:

I_{set}=1.2·ΔI_{diff}.I

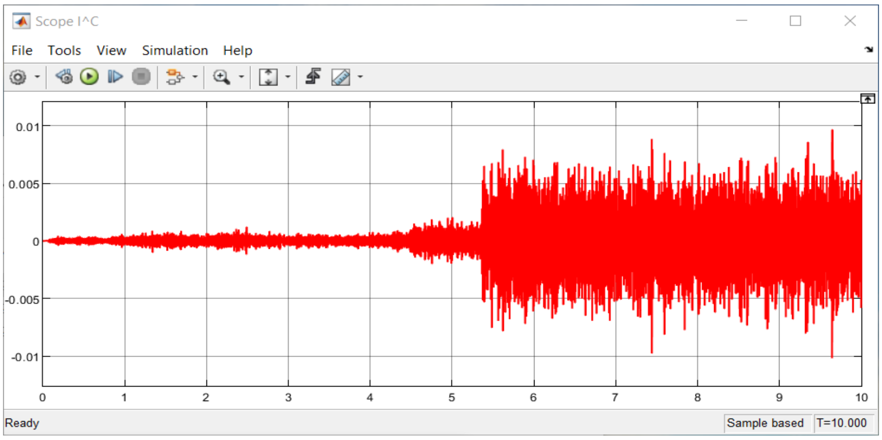


a)

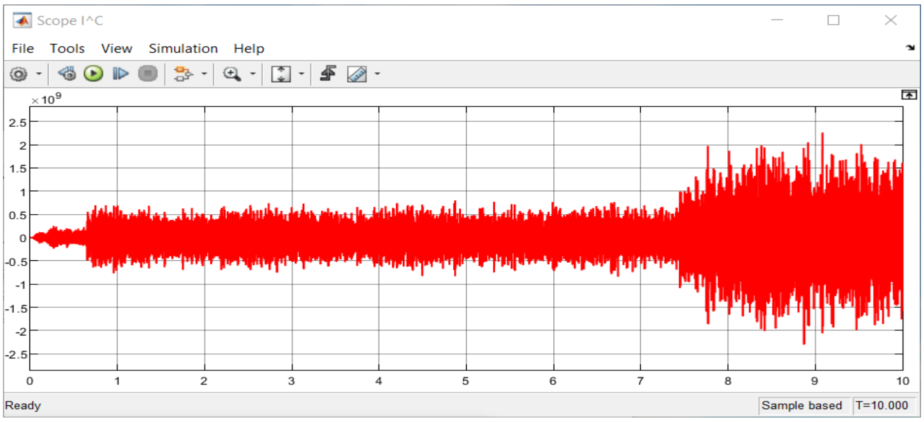


b)

FIGURE 2. Characteristic with ground fault (b) and without ground fault (a) in power systems (adapted: increase of ΔI_{diff} under ground fault conditions).

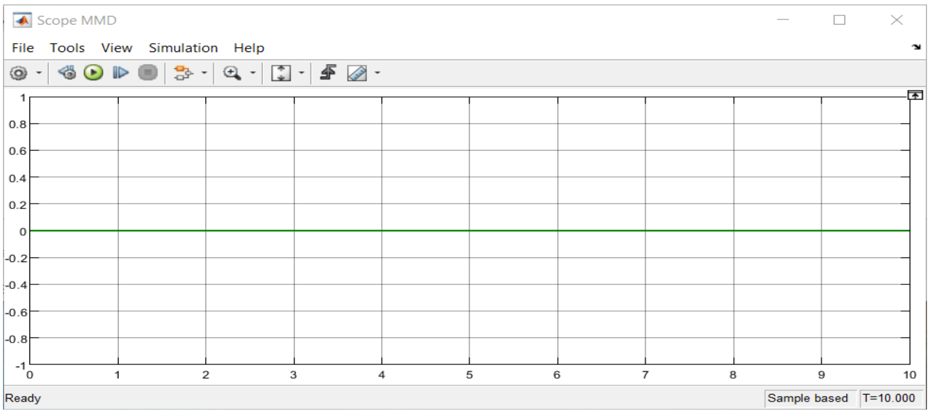


a)

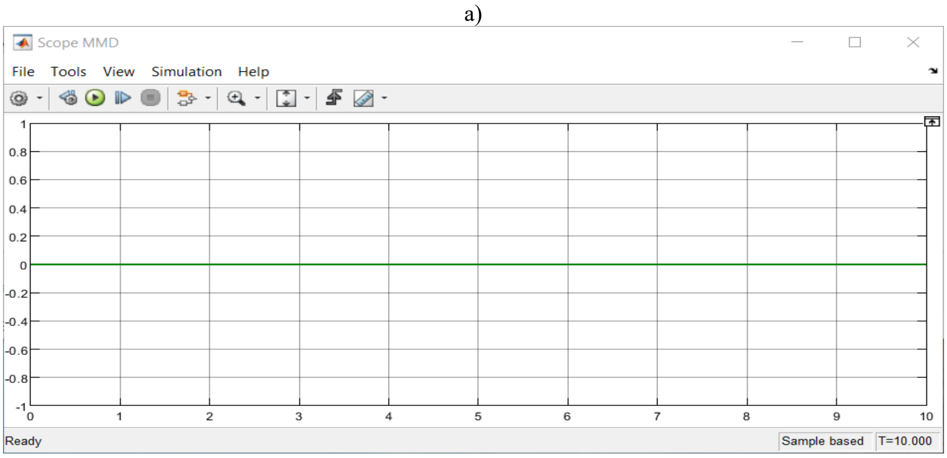


b)

FIGURE 3. Characteristic of the MMD current with ground fault (b) and without ground fault (a) (adapted: differential analysis for energy complexes).



a)



b)

FIGURE 4. Characteristic of the measuring block signal with ground fault (b) and without ground fault (a) (adapted: filtering in substations under load increase of 6–7%).

The results of the analyses carried out in the MATLAB Simulink environment for the measuring block with MMD, designed for selective detection of ground faults, demonstrate that without a signal from the open-delta connection of the voltage transformer—i.e., when the zero-sequence voltage is below the threshold value $U_{th}>U_0$ the control block does not transmit the signal to the subsequent stage.

It was found that the control block does not forward the signal for tripping unless the zero-sequence voltage U_0 is present. This ensures the avoidance of false operations of the protection system in power networks of the mining industry, particularly in complexes with variable capacitance.

As shown in Table 1, the developed measuring block of the microprocessor-based measuring system with MMD for ground fault protection provides improved sensitivity and selectivity, along with minimal protection operation time for mining power systems, which is essential under conditions of unstable network parameters.

TABLE 1. Simulation results of the measuring block in power systems

Mode	ΔI_{diff} (A)	Sensitivity (MkA)	Selective (%)	Hour (h)
Normal	<0.01	-	100	-
SLG	0.1	1	98	0.02
Noise (200 Hz)	0.05	10	95	0.03

CONCLUSIONS

The modeled MMD-based measuring unit has been shown to ensure high sensitivity and reliability in the selective detection of ground faults. Due to the sequential filtering, synchronous detection, and the combined logic with the zero-sequence voltage U0U_0U0, false tripping under noise, transient processes, and capacitive imbalance is effectively eliminated. The Simulink results confirm fast response (≤10 ms), selectivity in the range of 95–98%, and stable operation even under variable network parameters typical for mining power systems. Thus, the developed MMD-based measurement block is suitable for practical application, providing fast, accurate, and reliable ground-fault detection in real power networks.

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