

Two-Area Load Frequency Control Using Hybrid PSO-Fuzzy Logic Controller in a Renewable Integrated Nigerian Grid

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Article Info

Article history:

Received May 2, 2026

Revised July 14, 2026

Accepted July 21, 2026

Keywords:

Load Frequency Control
Particle Swarm Optimization
Fuzzy Logic Controller
Renewable Energy Integration
Interconnected Power Systems

ABSTRACT

Frequency stability in interconnected power systems is increasingly challenged by the growing penetration of renewable energy sources, which introduce variability and uncertainty into generation. This issue is particularly evident in the Nigerian grid, where disturbances significantly affect system dynamic performance. This study presents a hybrid Particle Swarm Optimization–Fuzzy Logic Controller (PSO–FLC) to improve load frequency control (LFC). The approach combines the adaptability of fuzzy logic with the optimization capability of PSO to achieve better dynamic response. A two-area power system model with non-reheat turbine and governor dynamics was developed in MATLAB/Simulink, integrating solar generation in one area and wind generation in the other. A 0.2 p.u. load disturbance was applied to assess system performance. The controller uses Area Control Error (ACE) as input, while PSO is employed to tune the scaling factors by minimizing the Integral of Time-weighted Absolute Error (ITAE). Performance was compared with no control, conventional PI control, and standalone fuzzy logic control. Results show that the PSO–FLC significantly improves system response. Peak undershoot is reduced from 11.25×10^{-4} p.u to 8.10×10^{-4} p.u, and settling time decreases from over 10 s to about 3.9 s. The proposed method eliminates steady-state error, enhances damping, and reduces oscillations in both areas, while also minimizing tie-line power fluctuations. These findings demonstrate that PSO–FLC is an effective and robust solution for frequency regulation in renewable-integrated systems, with strong potential for improving the stability of the Nigerian power grid.

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1. INTRODUCTION

Maintaining frequency stability in electric power systems requires a continuous balance between generation and load demand so that system frequency remains within acceptable limits [1]. When this balance is disturbed, frequency deviations occur, which can reduce system efficiency and, in severe cases, lead to instability [1][2]. In interconnected multi-area systems, the problem becomes more pronounced because tie-line power exchanges allow disturbances in one area to propagate to others, particularly in large grids such as those found in developing power networks [3]. Load Frequency Control (LFC) serves as a key strategy for frequency regulation and maintaining scheduled tie-line power flows [1][4]. Traditional approaches, especially Proportional-Integral (PI) controllers, remain popular due to their straightforward design and implementation [1][5]. However, these controllers are mainly based on linearized system models and fixed parameters, which may limit their effectiveness under nonlinearities, uncertainties, and rapidly changing operating conditions associated with modern power systems [6][7].

The increasing integration of renewable energy sources such as solar photovoltaic (PV) and wind generation presents additional challenges for frequency control in power systems [8]–[10]. Due to their intermittent and uncertain nature, these sources introduce rapid power fluctuations, which can degrade the performance of conventional load frequency control methods. Consequently, maintaining desirable dynamic characteristics

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such as low overshoot, fast settling time, and adequate oscillation damping becomes more difficult under high renewable penetration conditions [1][11].

To address these challenges, advanced control strategies have attracted significant attention. Among them, Fuzzy Logic Controllers (FLCs) are widely used because of their ability to handle nonlinearities and system uncertainties without requiring an accurate mathematical model [15]. However, the performance of FLCs strongly depends on the proper selection of scaling factors and membership functions, which are often determined through trial-and-error procedures [16]. This limitation can affect their ability to achieve optimal performance under varying system operating conditions.

To improve controller performance, optimization techniques have been increasingly applied to systematically tune FLC parameters [17][18]. In particular, evolutionary algorithms such as Particle Swarm Optimization (PSO) have been successfully used to enhance control performance by minimizing frequency deviations and tie-line power oscillations in interconnected power systems [19][20]. Particle Swarm Optimization is attractive due to its simplicity, rapid convergence, and effective global search capability inspired by swarm intelligence principles [21]-[23]. Recent studies have demonstrated that PSO-based tuning of FLC scaling factors can improve transient performance, reduce oscillations, and enhance stability in interconnected power systems [20][24]-[26].

However, despite the progress achieved in intelligent LFC techniques, most existing PSO-FLC-based studies have focused on conventional power system models or simplified renewable integration scenarios. Limited studies have investigated hybrid PSO-FLC approaches considering renewable energy integration characteristics of developing power networks, particularly the Nigerian interconnected power system. Therefore, further investigation is required to evaluate the capability of optimized intelligent controllers under renewable generation conditions representative of the Nigerian grid. The Nigerian power grid faces significant frequency regulation challenges due to persistent imbalance between generation and load demand, limited spinning reserves, transmission constraints, and increasing interest in renewable energy integration [27]. To enhance system stability, the Nigerian Electricity Regulatory Commission emphasizes the importance of governor response from generating units, highlighting the need for more effective load frequency control strategies [27][28]. Furthermore, future interconnection with the West African Power Pool introduces additional complexity, as disturbances can propagate across interconnected systems. These operational challenges necessitate the development of adaptive and robust LFC techniques suitable for improving frequency stability under uncertain operating conditions [27][29][30].

This paper proposes a hybrid control approach that combines a Fuzzy Logic Controller (FLC) with Particle Swarm Optimization (PSO) for load frequency control of a renewable-integrated two-area interconnected power system. The proposed method is designed to mitigate frequency deviations under varying load disturbances and renewable energy penetration conditions. The study considers a two-area interconnected power system incorporating renewable energy sources, where solar photovoltaic generation is integrated into Area 1 and wind generation is integrated into Area 2. PSO is employed to optimally tune the parameters of the FLC using the Integral Time-weighted Absolute Error (ITAE) performance index, with the aim of improving dynamic response and enhancing system stability.

The main contribution of this study is the development of a hybrid Particle Swarm Optimization-Fuzzy Logic Controller (PSO-FLC) for load frequency control of a renewable-integrated two-area interconnected power system. Unlike conventional PI and standalone Fuzzy Logic Controllers, the proposed method employs Particle Swarm Optimization to optimally tune the fuzzy controller scaling factors using the ITAE criterion. Although PSO-based optimization and fuzzy logic control techniques have been widely investigated, limited studies have considered their application to renewable-integrated interconnected systems representing developing grid conditions, particularly the Nigerian power system. This study addresses this gap by incorporating solar photovoltaic generation in Area 1 and wind generation in Area 2 to evaluate frequency regulation performance under practical renewable energy integration conditions. The proposed controller is implemented in MATLAB/Simulink and compared with no-control, PI, and standalone FLC approaches using performance indicators such as frequency deviation, settling time, tie-line power oscillations, and steady-state error. Furthermore, the robustness of the proposed controller is assessed under varying renewable penetration levels to verify its effectiveness under changing operating conditions. The results demonstrate improved frequency regulation, reduced oscillations, faster settling response, and enhanced dynamic stability, highlighting the potential application of the proposed PSO-FLC strategy for future renewable-integrated Nigerian interconnected power systems.

The remainder of this paper is organized as follows. Section 2 presents the mathematical modeling and methodology adopted in this study. Section 3 discusses the simulation results and comparative performance analysis. Finally, Section 4 presents the conclusions, limitations, and recommendations for future research.

2. METHOD

2.1 Overview of the Proposed Method

This study proposes a hybrid Particle Swarm Optimization–Fuzzy Logic Controller (PSO–FLC) for load frequency control of a renewable-integrated two-area interconnected power system. The objective is to improve frequency regulation by optimally tuning the scaling factors of the fuzzy logic controller using the Particle Swarm Optimization (PSO) algorithm. The system consists of two interconnected control areas. Area 1 comprises a conventional thermal generating unit integrated with solar photovoltaic (PV) generation, while Area 2 consists of a conventional thermal generating unit integrated with wind generation. The two areas exchange power through a tie-line. Figure 1 illustrates the overall operation of the proposed control strategy. Load disturbances occurring in either control area produces frequency deviations and tie-line power deviations, from which the Area Control Error (ACE) is calculated. The ACE is applied to the fuzzy logic controller to generate the supplementary control signal. The fuzzy controller scaling factors are optimized offline using PSO based on the ITAE criterion. The optimized control signal is applied to the governor loops to regulate system frequency and maintain scheduled tie-line power exchange.

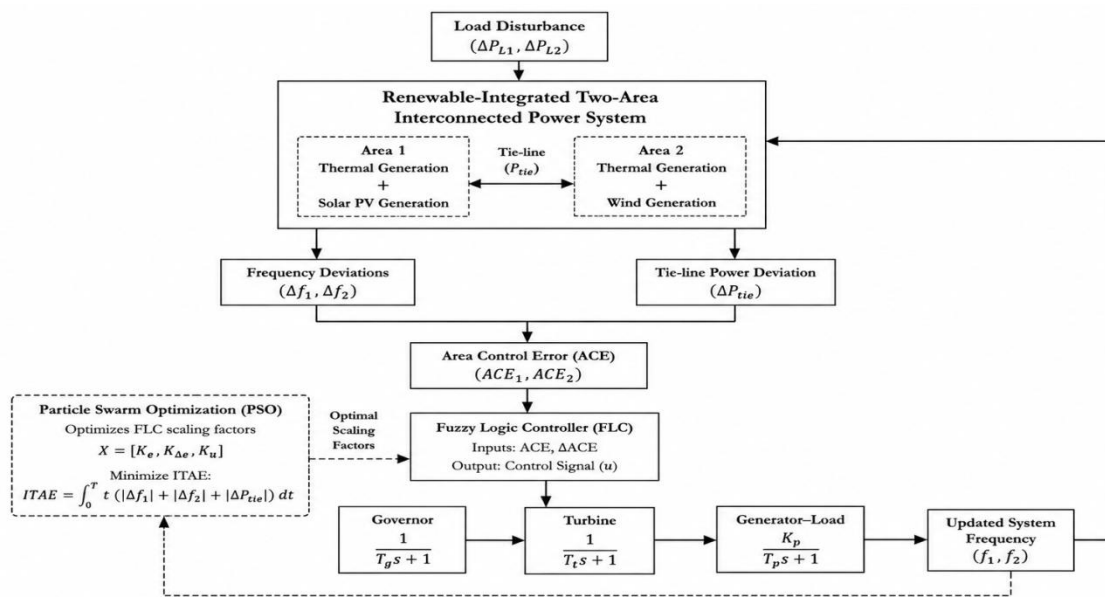


Figure 1. Block diagram of the proposed PSO–FLC-based load frequency control system.

2.2 Mathematical Description of the Proposed PSO–FLC Strategy

The mathematical models corresponding to each functional block of the proposed control framework are presented in this section.

2.2.1. Load Disturbance and Renewable Generation Block

The power imbalance within each control area is expressed as

$$\Delta P_{imb} = \Delta P_m + \Delta P_{RE} - \Delta P_L - \Delta P_{tie} \quad (1)$$

Where ΔP_m is the mechanical power deviation, ΔP_{RE} represents renewable generation fluctuation, ΔP_L represents load disturbance, and ΔP_{tie} represents tie-line power deviation.

2.2.2. Two-Area Generator-Load Dynamic Block

The generator-load model describes the relationship between power imbalance and frequency deviation. For the two-area interconnected system, the frequency deviations are expressed as:

$$\Delta f_1(s) = \frac{\Delta P_{m1}(s) + \Delta P_{RE1}(s) - \Delta P_{L1}(s) - \Delta P_{tie}(s)}{2H_1 s + D1} \quad (2)$$

$$\Delta f_2(s) = \frac{\Delta P_{m2}(s) + \Delta P_{RE2}(s) - \Delta P_{L2}(s) + \Delta P_{tie}(s)}{2H_2 s + D2} \quad (3)$$

Where H is the inertia constant and D is the damping coefficient. The equivalent generator-load transfer function is

$$G_p(s) = \frac{K_p}{T_p s + 1} \quad (4)$$

Where K_p and T_p are the power system gain and time constant, respectively.

2.2.3. Tie-Line Power Exchange Block

The tie-line power deviation between the two interconnected areas is

$$\Delta P_{tie}(s) = \frac{2\pi T_{12}}{s} (\Delta f_1(s) - \Delta f_2(s)) \quad (5)$$

Where T_{12} is the synchronizing coefficient. In the time domain,

$$\Delta P_{tie}(t) = 2\pi T_{12} \int_0^t (\Delta f_1 - \Delta f_2) dt \quad (6)$$

2.2.4. Area Control Error Block

The Area Control Error combines frequency deviation and tie-line power deviation. For Area 1,

$$ACE_1 = B_1 \Delta f_1 + \Delta P_{tie} \quad (7)$$

For Area 2,

$$ACE_2 = B_2 \Delta f_2 - \Delta P_{tie} \quad (8)$$

Where B_1, B_2 are the frequency bias constants. The ACE signals constitute the inputs to the fuzzy logic controller.

2.2.5. Fuzzy Logic Controller Block

A Mamdani-type fuzzy inference system is employed to generate the supplementary control signal. The controller inputs are

- Area Control Error (ACE),
- Change in Area Control Error (ΔACE).

Five triangular membership functions are defined for each input and output variable:

- Negative Big (NB)
- Negative Small (NS)
- Zero (ZE)
- Positive Small (PS)
- Positive Big (PB)

The fuzzy controller output is $u(t) = F(ACE, \Delta ACE)$

2.2.6. PSO Optimization Block

PSO is used to optimize the fuzzy controller scaling factors:

The Particle Swarm Optimization algorithm is employed to optimize the input and output scaling factors of the fuzzy controller. The optimization vector is $X = [K_e, K_{\Delta e}, K_u]$. Where K_e = ACE scaling factor, $K_{\Delta e}$ = change in ACE scaling factor, K_u = output scaling factor. The velocity update equation is

$$v_i^{k+1} = w v_i^k + c_1 r_1 (Pbest_i - X_i^k) + c_2 r_2 (Gbest - X_i^k) \quad (9)$$

The position update equation is

$$X_i^{k+1} = X_i^k + v_i^{k+1} \quad (10)$$

Where w = inertia weight, c_1, c_2 = acceleration coefficients, r_1, r_2 = random numbers in $[0, 1]$, $Pbest_i$ = personal best position, $Gbest$ = global best position.

2.2.7. ITAE Objective Function Block

The PSO minimizes the Integral Time-weighted Absolute Error (ITAE)

$$ITAE = \int_0^T t (|\Delta f_1| + |\Delta f_2| + |\Delta P_{tie}|) dt \quad (11)$$

The optimization objective is $\min(ITAE)$. Minimizing the ITAE improves transient performance by reducing overshoot, oscillations, and settling time.

2.2.8. Governor–Turbine Control Block

The governor transfer function is

$$G_g(s) = \frac{1}{T_g s + 1} \quad (12)$$

The turbine transfer function is

$$G_t(s) = \frac{1}{T_t s + 1} \quad (13)$$

Where T_g = governor time constant, T_t = turbine time constant. The governor output is driven by the optimized fuzzy control signal generated through PSO.

2.2.9. Frequency Restoration Block

The primary objective of the proposed PSO–FLC controller is to eliminate steady-state frequency deviations and restore scheduled tie-line power exchange following renewable generation fluctuations and load disturbances. The desired operating conditions are

$$\begin{aligned} \lim_{t \rightarrow \infty} \Delta f_1 &= 0 \\ \lim_{t \rightarrow \infty} \Delta f_2 &= 0 \\ \lim_{t \rightarrow \infty} \Delta P_{tie} &= 0 \end{aligned}$$

These conditions ensure stable system frequency, accurate power sharing between interconnected areas, and improved overall dynamic performance.

2.3 MATLAB/Simulink Implementation

The proposed PSO–FLC strategy was implemented in MATLAB/Simulink. The two-area interconnected power system consisted of governor, turbine, generator-load, renewable energy, and tie-line models represented using transfer-function blocks. A Mamdani fuzzy logic controller was developed using the Fuzzy Logic Toolbox, while the Particle Swarm Optimization algorithm was implemented in MATLAB to determine the optimal controller scaling factors based on the ITAE objective function. A step load disturbance of 0.2 p.u. was applied at $t=1$ s after the system reached steady-state to evaluate the dynamic performance of the proposed controller under renewable generation variability.

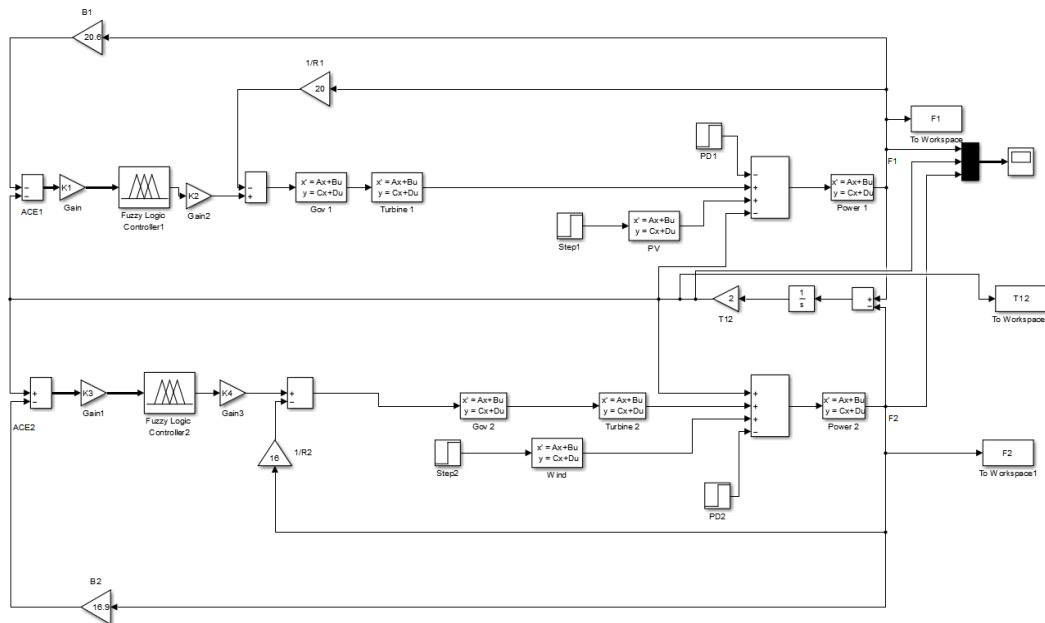


Figure 2. Simulink model of the two-area interconnected system

2.3.1. Mathematical Model

Each component is represented using first-order state-space models. Governor:

$$\dot{x}_g = -12.5x_g + 12.5u \quad (14)$$

Turbine:

$$\dot{x}_t = -3.333x_t + 3.333x_g \quad (15)$$

Power system (frequency dynamics):

$$\begin{aligned} \dot{x}_p &= -0.06x_p + 0.1x_t - \Delta P_L \\ \Delta f &= x_p \end{aligned} \quad (16)$$

Where ΔP_L represents load disturbance. Tie-Line Power Equation:

$$\Delta P_{tie} = T_{12}(\Delta f_1 - \Delta f_2) \quad (17)$$

Renewable models (solar PV in Area 1, wind in Area 2):

$$\dot{x}_r = -20x_r + 20u_r$$

The renewable generation is modeled as a first-order system to capture dominant dynamics. Although simplified, this representation is widely adopted in LFC studies for control design purposes.

Table 1. System Parameters of the Two-Area Renewable Integrated Power System

Parameter	Area 1	Area 2	Description
B	20.6	16.5	Frequency bias (p.u. MW/Hz)
R	0.05	0.0625	Speed regulation (p.u.)
D	0.015	0.02	Load damping coefficient
1/R	20	16	Droop characteristic
T_{12}	2	2	Tie-line synchronizing coefficient

The frequency bias parameter is defined as:

$$B_i = \frac{1}{R_i} + D_i \quad (18)$$

This relationship ensures proper coordination between primary droop control and secondary frequency regulation.

2.3.2. Area Control Error (ACE)

The Area Control Error is defined as:

$$ACE_1 = B_1\Delta f_1 + \Delta P_{tie} \quad (19)$$

$$ACE_2 = B_2\Delta f_2 - \Delta P_{tie} \quad (20)$$

This signal serves as the input to all controllers.

2.4. Simulation Model Parameters

The main parameters used for the simulation of the renewable-integrated two-area interconnected power system are summarized in Table 2. Area 1 consists of a thermal generating unit integrated with solar PV generation, while Area 2 consists of a thermal generating unit integrated with wind generation. The parameters represent the dynamic characteristics of the governor, turbine, generator-load, tie-line, and renewable generation models used in MATLAB/Simulink.

Table 2. Simulation Model Parameters

Parameter	Area 1	Area 2
Frequency bias factor (B)	20.6	16.5
Speed regulation (R)	0.05	0.0625
Load damping coefficient (D)	0.015	0.02
Droop gain (1/R)	20	16
Tie-line synchronizing coefficient (T_{12})	2	2
Governor time constant (T_g)	0.08 s	0.08 s
Turbine time constant (T_t)	0.30 s	0.30 s
Power system time constant (T_p)	20 s	20 s
Power system gain (Kp)	120	120
Base power	100 MVA	
Nominal frequency	50 Hz	
Load disturbance	0.2 p.u. at $t = 1$ s	
Simulation time	10 s	
Renewable sources	Solar PV	Wind

The renewable generation units are represented using first-order dynamic models to capture their dominant response characteristics. This simplified representation is commonly adopted in LFC studies because the primary objective is to evaluate frequency regulation performance rather than detailed energy conversion dynamics. Although this assumption neglects high-frequency renewable converter behaviors, it adequately represents the dominant power fluctuation characteristics relevant to secondary frequency control analysis. These parameters provide the necessary information for reproducing the simulation results.

2.5 Control Strategies

2.5.1. No Controller

The system operates without secondary control. This case establishes the baseline dynamic behavior.

2.5.2. PI Controller

A conventional PI controller is implemented:

$$u(t) = K_p e(t) + K_i \int e(t) dt \quad (21)$$

The PI controller gains are tuned using the Ziegler-Nichols method to provide a reasonable baseline for comparison. Parameters:

- $K_p = 0.5$
- $K_i = 0.4$

2.5.3. Fuzzy Logic Controller

A Mamdani-type fuzzy logic controller is implemented independently in each area. Table 3 shows the controller design parameters.

Table 3. The Controller Design Parameter

Parameter	Specification
Input	ACE $\in [-0.05, 0.05]$
Output	Control signal $\in [-1, 1]$ (before scaling)
Membership functions	Triangular, 5 levels
Defuzzification	Centroid method

Membership functions are Negative Big (NB), Negative Small (NS), Zero (Z), Positive Small (PS), Positive Big (PB). The controller provides nonlinear control action to improve transient response.

Table 4. Rule Base

ACE	Output
NB	PB
NS	PS
Z	Z
PS	NS
PB	NB

2.5.4. PSO-Fuzzy Controller

Particle Swarm Optimization (PSO) is used to tune the scaling gains of the fuzzy controller. Decision Variables

$$x = [K_1, K_2, K_3, K_4] \quad (22)$$

Where K_1, K_2 : input scaling factors for ACE1 and ACE2. K_3, K_4 : output gains of fuzzy controllers. PSO Update Equations:

$$v_i^{k+1} = w v_i^k + c_1 r_1 (pbest_i - x_i^k) + c_2 r_2 (gbest - x_i^k) \quad (23)$$

$$x_i^{k+1} = x_i^k + v_i^{k+1} \quad (24)$$

Objective Function:

$$J = \int_0^T t (|\Delta f_1| + |\Delta f_2| + |\Delta P_{tie}|) dt \quad (25)$$

Table 5. PSO Parameters

Parameter	Value
Population size	20
Maximum iterations	30
Inertia weight (w)	0.7
Cognitive coefficient (c ₁)	1.5
Social coefficient (c ₂)	1.5

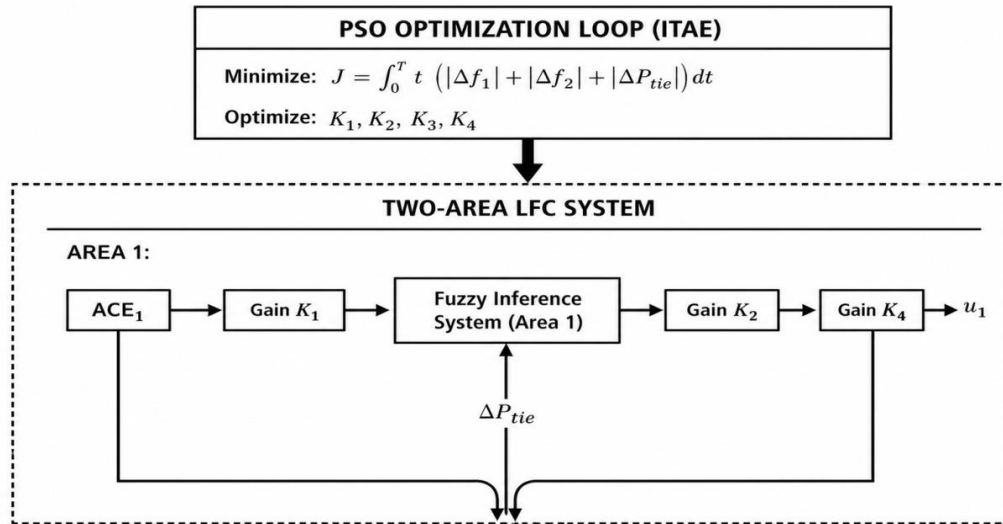


Figure 3. The complete PSO–FLC structure, illustrating how the scaling factors interface with the fuzzy logic controllers in both areas.

2.6. Simulation Setup

- Simulation time: 10 s
- Sampling time: 0.01 s
- Disturbance applied at 1 s

3. RESULTS AND DISCUSSION

The performance of the proposed hybrid Particle Swarm Optimization–Fuzzy Logic Controller (PSO–FLC) is evaluated in a renewable-integrated two-area interconnected power system under load disturbance conditions. The controllers considered for comparison include no controller, conventional Proportional-Integral (PI) controller, standalone Fuzzy Logic Controller (FLC), and the proposed PSO–FLC strategy. The evaluation is based on frequency deviation response, tie-line power oscillations, settling time, overshoot, undershoot, and steady-state error.

3.1. Case 1: No Controller

Figure 4 shows the frequency deviation and tie-line power response without secondary frequency control. The system exhibits large oscillations and fails to restore the frequency to its nominal value after the disturbance. The absence of an effective control mechanism results in poor damping capability and prolonged frequency deviation, demonstrating the importance of an appropriate load frequency control strategy in interconnected power systems.

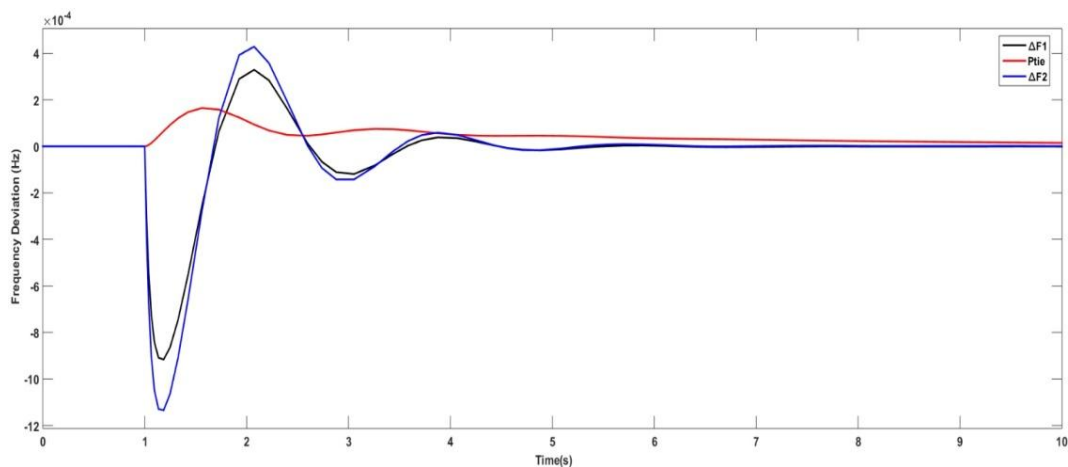


Figure 4. Frequency deviation and tie-line power without control

3.2. Case 2: PI Controller

Figure 5 presents the system response using a conventional PI controller. The PI controller reduces the steady-state frequency error due to its integral action, which compensates for accumulated deviations. However, noticeable oscillations and a relatively longer settling time are observed. This limitation is associated with the fixed controller gains, which may not provide optimal performance under nonlinear operating conditions and renewable generation uncertainties.

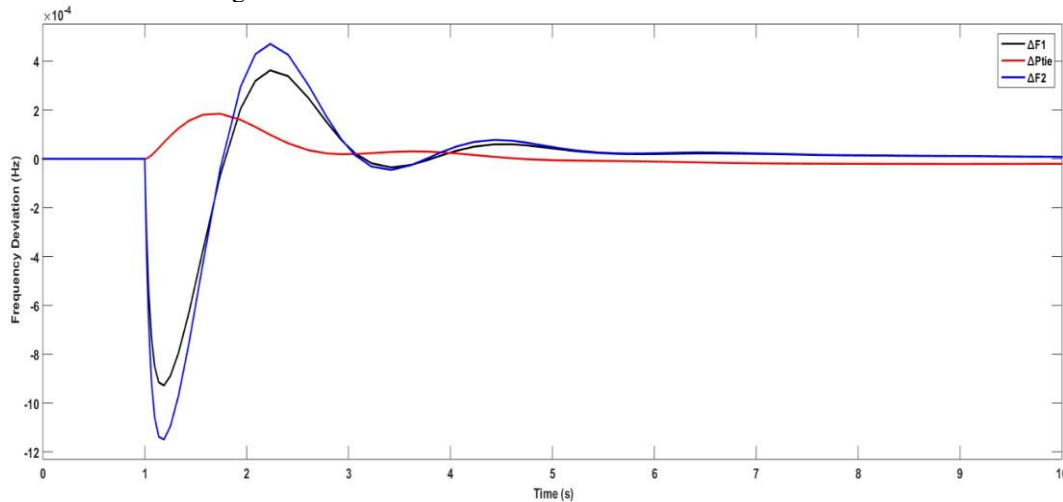


Figure 5. Frequency response using PI controller

3.3. Case 3: Fuzzy Controller

The frequency response using the standalone Fuzzy Logic Controller is shown in Figure 6. Compared with the PI controller, the FLC provides improved dynamic performance with reduced oscillations and faster settling response due to its ability to handle nonlinear system behavior without requiring an exact mathematical model. However, the response still exhibits considerable overshoot and undershoot. This is mainly due to the selection of fuzzy controller scaling factors, which significantly influences the controller output. Without optimization, the FLC parameters may not provide the most effective corrective action during transient disturbances.

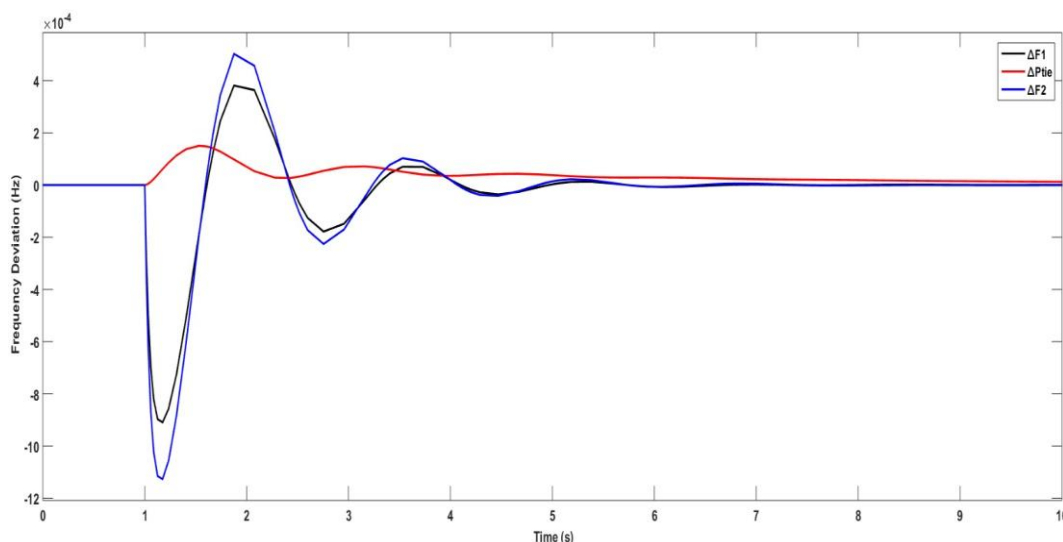


Figure 6: Frequency response using fuzzy controller

3.4 Case 4: PSO-Fuzzy Controller

Figure 7 presents the response of the proposed PSO-FLC controller. The controller demonstrates the best performance among all investigated strategies, with reduced frequency deviation, improved damping characteristics, and faster recovery of system frequency.

The improved performance is attributed to the optimization of the fuzzy controller scaling factors using Particle Swarm Optimization. By minimizing the ITAE objective function, PSO determines suitable controller parameters that provide effective control actions during disturbance conditions. This enables the controller to achieve a better balance between rapid response and oscillation suppression, resulting in reduced overshoot, lower undershoot, and shorter settling time.

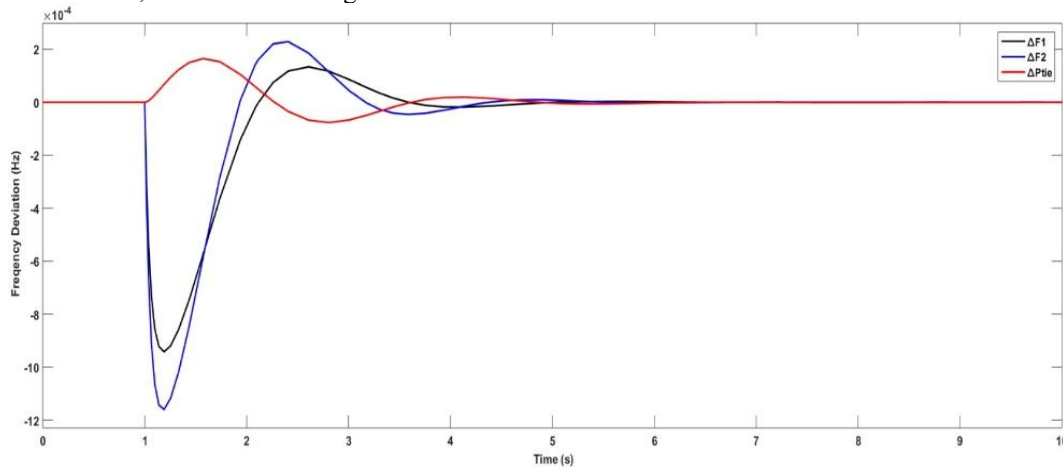


Figure 7. Frequency response using PSO-Fuzzy controller

3.5. Comparative Analysis

Table 6 presents the comparative performance of the different LFC strategies. The uncontrolled system shows the highest frequency deviation and fails to achieve stable operation, confirming the necessity of secondary frequency regulation. The PI controller improves the steady-state response but exhibits slower dynamic recovery due to its fixed gain structure. The standalone FLC provides better performance than the PI controller because of its nonlinear control capability. However, its performance is limited by the manually selected scaling factors. In contrast, the proposed PSO-FLC controller achieves the best overall performance, with the lowest peak undershoot (8.10×10^{-4}), lowest overshoot (2.80×10^{-4}), shortest settling time (3.90 s), and zero steady-state error.

Table 6. Performance Comparison of LFC Strategies

Control Strategy	Peak Undershoot ($\times 10^{-4}$)	Overshoot ($\times 10^{-4}$)	Settling Time (s)	Steady-State Error
No Control	11.25	4.20	>10	High
PI Controller	10.50	4.80	7.50	Minimal
Fuzzy (FLC)	9.80	3.80	5.20	Near Zero
Hybrid PSO-Fuzzy	8.10	2.80	3.90	Zero

The superior performance of the proposed PSO-FLC controller is due to the combination of PSO optimization capability and the adaptability of fuzzy logic control. The ITAE-based optimization process enables the controller to minimize frequency error over time while improving damping performance. Consequently, the proposed controller provides faster frequency restoration and better suppression of tie-line power oscillations compared with conventional approaches. These characteristics are particularly important in renewable-integrated systems where solar and wind generation introduce additional uncertainties and power fluctuations.

3.6. PSO Convergence Analysis

The convergence behavior of the PSO algorithm is presented in Figure 8. The convergence curve shows the reduction of the ITAE objective function as the optimization process progresses. The PSO algorithm achieves the optimal solution after 12 iterations with a minimum ITAE value of 0.03253, demonstrating effective convergence toward the optimal controller parameters.

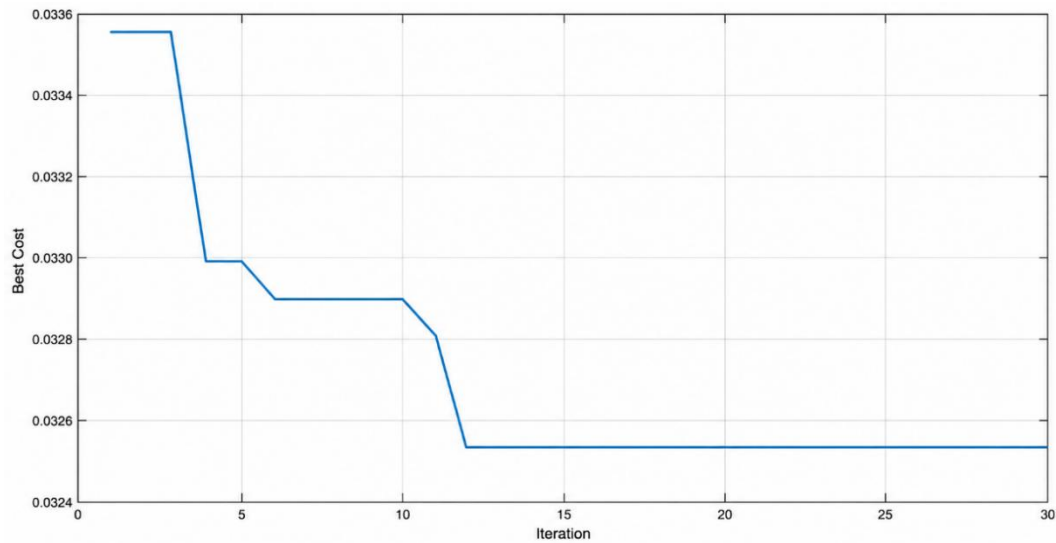


Figure 8: PSO convergence curve (ITAE vs iteration)

Table 7: Optimization Results of the PSO Algorithm

Parameter	Value
Best ITAE	0.03253
Convergence Iteration	12
Optimization Goal	Minimize ITAE

The optimal scaling parameters obtained from the PSO algorithm are presented in Table 8. These parameters determine the relationship between the area control error (ACE) signals and the fuzzy controller output. The optimized values enable improved control action and contribute to the enhanced transient response obtained with the proposed PSO–FLC strategy.

Table 8: The optimal scaling parameters obtained from the PSO algorithm are:

Parameter	Optimal Value	Description
K_1	2.45	Area 1 input scaling factor ($ACE_1 \rightarrow FLC$)
K_2	2.10	Area 2 input scaling factor ($ACE_2 \rightarrow FLC$)
K_3	0.85	Area 1 output gain ($FLC \rightarrow u_1$)
K_4	0.72	Area 2 output gain ($FLC \rightarrow u_2$)

Overall, the results validate the main contributions of this study by demonstrating the effectiveness of the proposed PSO–FLC strategy for frequency regulation in a renewable-integrated two-area interconnected power system. Compared with conventional PI and standalone FLC controllers, the proposed approach achieves superior transient performance through optimal tuning of fuzzy controller scaling factors using the ITAE criterion. Furthermore, the improved damping capability, reduced frequency deviations, minimized tie-line power oscillations, and zero steady-state error demonstrate the robustness of the proposed controller under renewable energy integration conditions. These results confirm the suitability of the PSO–FLC approach for enhancing frequency stability in future renewable-integrated Nigerian interconnected power systems.

3.7 Robustness Assessment Under Different Renewable Penetration Levels

To evaluate the robustness of the proposed Particle Swarm Optimization–Fuzzy Logic Controller (PSO–FLC), additional simulations were performed under renewable generation levels of 10%, 20%, and 30%. These operating conditions were implemented by varying the amplitudes of the Step1 and Step2 inputs connected to the solar PV and wind generation state-space models, respectively. The Step inputs were set to 0.1 p.u., 0.2 p.u., and 0.3 p.u., representing increasing renewable power injection into the two-area interconnected system. For all cases, the load disturbance remained constant at 0.2 p.u. to ensure that the controller performance was evaluated under identical disturbance conditions while only the renewable generation level was varied. The corresponding frequency responses are presented in Figures 9–11, while the comparative performance is summarized in Table 9.

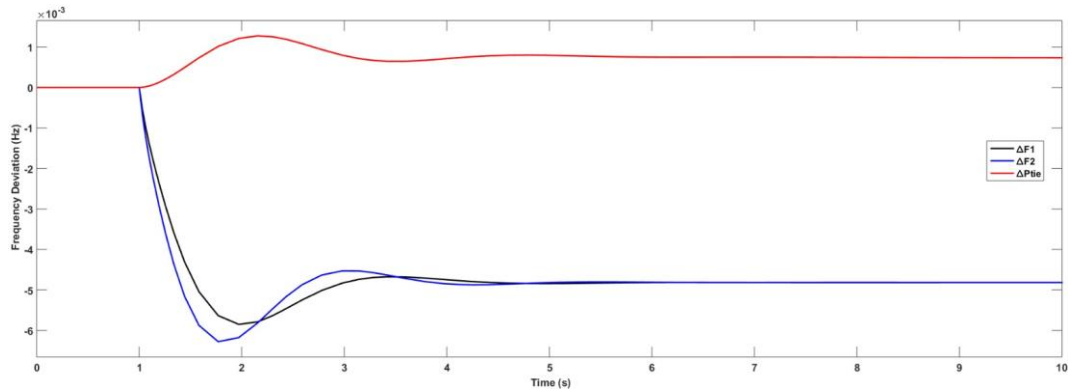


Figure 9. Frequency response of the proposed PSO-FLC under 10% renewable penetration.

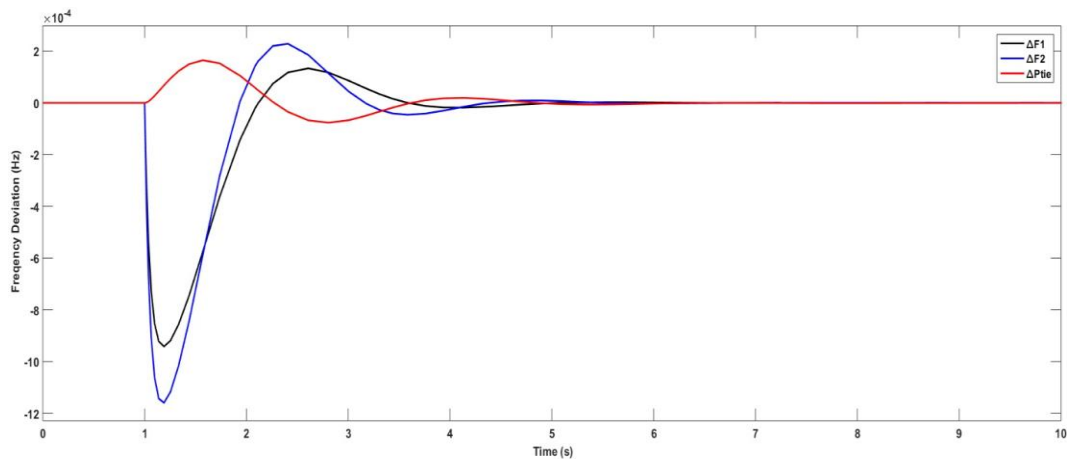


Figure 10. Frequency response of the proposed PSO-FLC under 20% renewable penetration.

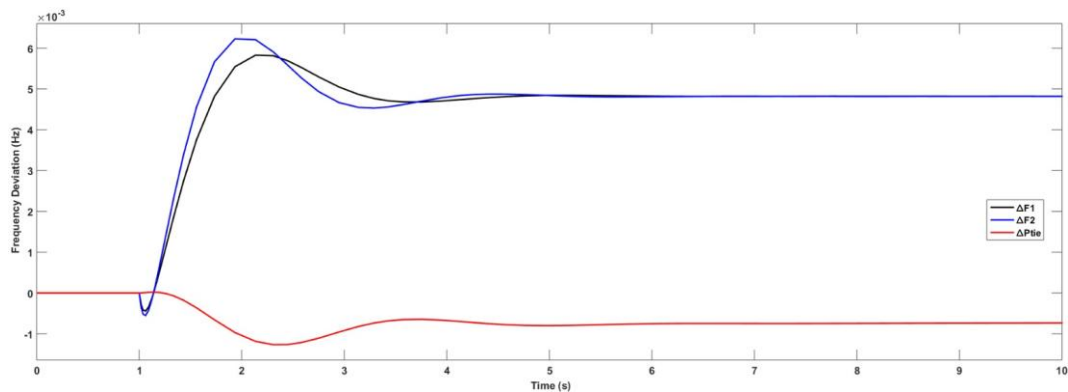


Figure 11. Frequency response of the proposed PSO-FLC under 30% renewable penetration.

Table 9. Performance of the Proposed PSO-FLC Under Different Renewable Penetration Levels

Renewable Penetration (%)	Maximum Frequency Deviation (Hz)	Settling Time (s)	Stability
10	$\pm 6.3 \times 10^{-3}$	≈ 5.5	Stable
20	$\pm 2.3 \times 10^{-4}$	$\approx 4.5-5.0$	Stable
30	$\pm 6.3 \times 10^{-3}$	≈ 5.0	Stable

The results presented in Figures 9–11 and Table 9 demonstrate that the proposed PSO-FLC maintains satisfactory frequency regulation under different renewable generation levels. Among the three operating conditions, the 20% renewable generation scenario produced the smallest maximum frequency deviation and the shortest settling time. This improved response is associated with the selected operating point, where renewable power support provides additional regulation capability without significantly reducing the effective system inertia. Consequently, the optimized PSO-FLC is able to compensate for the disturbance more efficiently, resulting in improved damping and faster frequency restoration.

At 10% renewable generation, the renewable power contribution is relatively small, providing limited support during transient conditions. Consequently, larger frequency excursions and a slightly longer settling time are observed. At 30% renewable generation, although greater renewable power is available, the higher penetration level reduces the effective system inertia of the interconnected system, leading to slightly larger transient oscillations. Nevertheless, the proposed PSO–FLC successfully maintains system stability and restores the nominal frequency within approximately 5s in all investigated cases without sustained oscillations or steady-state error.

These results demonstrate that the proposed PSO–FLC possesses strong robustness and adaptability under varying renewable generation levels, indicating its suitability for future Nigerian interconnected power systems with increasing penetration of solar photovoltaic and wind energy.

4. CONCLUSION, LIMITATIONS AND FUTURE WORK

This study presented a hybrid Particle Swarm Optimization–Fuzzy Logic Controller (PSO–FLC) for load frequency control of a renewable-integrated two-area interconnected power system. The proposed approach combines the adaptive capability of fuzzy logic control with the optimization capability of Particle Swarm Optimization (PSO) to improve frequency regulation under load disturbances and renewable generation variations. The main contribution of this study is the optimization of the fuzzy controller scaling factors using the ITAE performance criterion to achieve enhanced frequency regulation.

The performance of the proposed controller was evaluated and compared with an uncontrolled system, a conventional PI controller, and a standalone Fuzzy Logic Controller (FLC). The simulation results demonstrated that the PSO–FLC achieved superior dynamic performance by reducing frequency deviations, minimizing tie-line power oscillations, improving damping characteristics, and eliminating steady-state error. The proposed controller achieved the shortest settling time of approximately 3.9 s, with lower overshoot and undershoot than the other control strategies. In addition, the robustness assessment under 10%, 20%, and 30% renewable penetration levels confirmed that the proposed controller maintained stable frequency regulation under varying operating conditions.

Overall, the results confirm that the proposed PSO–FLC provides an effective and robust solution for enhancing frequency stability in renewable-integrated interconnected power systems. The proposed controller therefore offers strong potential for supporting the modernization and reliable operation of the Nigerian power grid as renewable energy penetration continues to increase.

This study has several limitations. The proposed controller was evaluated using a simplified renewable-integrated two-area interconnected power system with non-reheat turbine dynamics and first-order models for the solar PV and wind generation units. Although these assumptions are widely adopted in load frequency control studies, they do not fully represent the complexity of practical large-scale power systems. In addition, the controller was validated only through MATLAB/Simulink simulations without experimental or Hardware-in-the-Loop (HIL) implementation. The study also did not consider stochastic renewable generation, communication delays, measurement noise, or cyber-physical disturbances, which may influence controller performance under real operating conditions.

Based on the findings and limitations of this study, future research should extend the proposed PSO–FLC strategy to more realistic multi-area interconnected power systems incorporating reheat turbines, nonlinear dynamics, energy storage systems, and higher renewable penetration levels. The inclusion of stochastic renewable generation, forecasting uncertainties, communication delays, and cyber-physical disturbances would provide a more comprehensive evaluation of controller performance under practical operating conditions.

Future studies should also investigate the real-time implementation of the proposed controller using embedded controllers or Hardware-in-the-Loop (HIL) platforms to validate its practical feasibility. In addition, comparative investigations with other advanced optimization techniques, such as Genetic Algorithms (GA), Grey Wolf Optimizer (GWO), and deep learning-based control methods, could further improve controller performance and support the development of more resilient renewable-integrated smart power systems.

ACKNOWLEDGEMENTS

The authors gratefully acknowledge the guidance, supervision, and constructive feedback of Dr. Sabo Aliyu, whose expertise significantly contributed to the successful completion of this research. The authors also appreciate the support provided by the Nigerian Defence Academy (NDA) for creating a conducive research environment. Finally, the authors express their sincere gratitude to Almighty God for His guidance, strength, and wisdom throughout the course of this study.

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