Modeling control of low frequency plasma turbulence

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HSCoPP'04, Frèjus, France, October 21 - 23, 2004 Back Next

- p. 1/1

Contents

- Motivation
- Drift-wave turbulence in the Kiwi/Mirabelle device
- Autoresonance as a control method for nonlinear systems
- Autoresonance in a spatio-temporal system?
- **Conclusion**

Motivation

Turbulence and the induced transport are key ingredients to a number of problems in building a working device for nuclear fusion:

- scaling of transport
- transport events: blobs, ELMs ...
- transport of impurities

Thus effectively controlling or influencing turbulence is a mayor issue in fusion research.

There are clearly two ways to control a plasma:

- choose the right parameters and geometry
- do something actively

The Kiwi/Mirabelle device

Experimental buildup (Thomas Klinger this morning):



Magnetized cylinder, current driven instability of drift wave type, weak turbulence. Control/influence by a spatiotemporal signal in resonance

with naturally occuring 'linear' mode

HSCoPP'04, Frèjus, France, October 21 - 23, 2004 Back Next

- p. 4/1

The Kiwi/Mirabelle device

Experimental result:



Resonant drive with a m = 2 mode collapses turbulent spectrum.

HSCoPP'04, Frèjus, France, October 21 - 23, 2004 Back Next

- p. 5/1

Modeling the experiment

Idea:

Simplest system describing drift wave dynamics, reducing drift wave dynamics to its core Hasegawa-Wakatani equations: (1987)

$$\frac{\partial}{\partial t} \nabla_{\perp}^{2} \phi + \vec{V}_{E \times B} \cdot \nabla \nabla_{\perp}^{2} \phi = \nabla_{\parallel} J_{\parallel} + \mu_{w} \nabla_{\perp}^{4} \phi$$
$$\frac{\partial}{\partial t} n + \vec{V}_{E \times B} \cdot \nabla (N_{0} + n) = \nabla_{\parallel} J_{\parallel} + \mu_{n} \nabla_{\perp}^{2} n$$

Balance divergences in ion-polarisation with parallel current to hold up quasi-neutrality.

Modeling the experiment

$$\frac{\partial}{\partial t} \nabla_{\perp}^2 \phi + \vec{V}_{E \times B} \cdot \nabla \nabla_{\perp}^2 \phi = \tilde{\sigma} (\phi - n) - \mathbf{S} + \mu_w \nabla_{\perp}^4 \phi$$

$$\frac{\partial}{\partial t}n + \vec{V}_{E \times B} \cdot \nabla \left(N_0(r) + n\right) = \tilde{\sigma}\left(\phi - n\right) - \frac{S}{S} + \mu_n \nabla_{\perp}^2 n$$

Driver term acts onto the source of instability: Parallel current.

$$S = \nabla_{\parallel} J_{ext} = A \sin(\pi r/r_0) \sin(2\pi m_d \theta - \omega_d t)$$

Solved numerically on a disk (r, θ) . Drive/Damping layers at around r = 0 and $r = r_{max}$ keep up density gradient N_0 .

Results: Experiment



Results: Simulation



Excellent agreement between simulation and experiment. Schröder et al. PRL 2001

HSCoPP'04, Frèjus, France, October 21 - 23, 2004 Back Next

- p. 8/1

Results: Simulation



Excellent agreement between simulation and experiment. Schröder et al. PRL 2001 But: Is this the whole story? No, modeling is merely a good starting point...

HSCoPP'04, Frèjus, France, October 21 - 23, 2004 Back Next

- p. 8/1

Controlling multidimensional PDEs

Control theory of multidimensional PDEs is an active field of research and not very well developed. It is not at all well developed for non-linear problems...

- Inear control theory for low number of degrees of freedom ODE's well developed.
- nonlinear control theory for chaos (attractors)
- feedback, open loop control

Some identifications:

A possible resonance of a system helps to exert control at low control power....critical for fusion plasmas.

Autoresonance: Parametric Excitation

AUTORESONANCE (adiabatic nonlinear phase locking and synchronization) is a remarkable phenomenon of nonlinear physics when a driven nonlinear system stays in resonance with the driving oscillation or wave continuously, despite variation of system's parameters. (Fajans, Friedland)

Or: How do you drive a nonlinear oscillator or wave to high amplitude?

Simple example: Pendulum

$$\frac{d^2}{dt^2}x + \sin(x) = A\cos(f(t))$$

Linear resonant frequency: $\omega = 1$. At large oscillator amplitude resonant frequency changes: Resonance lost

Solutions:

Simple example: Pendulum

$$\frac{d^2}{dt^2}x + \sin(x) = A\cos(f(t))$$

Linear resonant frequency: $\omega = 1$. At large oscillator amplitude resonant frequency changes: Resonance lost

Solutions: a) modify frequency accordingly Inability to measure and to adjust makes this difficult for most non-trivial systems.

Simple example: Pendulum

$$\frac{d^2}{dt^2}x + \sin(x) = A\cos(f(t))$$

Linear resonant frequency: $\omega = 1$. At large oscillator amplitude resonant frequency changes: Resonance lost

Solutions:

b) sweep driver frequency slowly, assuming some monotonous frequency response
a (good) shot into the dark.

Simple example: Pendulum



Note: Sweep must be slow compared to system frequency change!

L. Friedland, J. Fajans, and E. Gilson, Subharmonic autoresonance of the diocotron mode. Phys. Plasmas, 7:1712, 2000.

HSCoPP'04, Frèjus, France, October 21 - 23, 2004 Back

ack Next

- p. 12/1

AR and plasma turbulence? No way, as turbulence

- is a complicated system, many degrees of freedom
- has a complicated frequency response
- exhibits instabilities
- **.**...

but....there are certain similarities:

- no good knowledge of system
- Inear frequencies (waves)
- **_**

Results from simulations of Hasegawa- Wakatani System.



Amplitudes of modes m = 1 to m = 5. Free system, far from onset of instability, many unstable modes, turbulent....

HSCoPP'04, Frèius, France, October 21 - 23, 2004

Back Next

- p. 14/1

Results from simulations of Hasegawa- Wakatani System.



Driving mode m = 3 with driver frequency increasing over time.

HSCoPP'04, Frèjus, France, October 21 - 23, 2004 Back Next

– p. 14/1

Results from simulations of Hasegawa- Wakatani System.



Driving mode m = 3 with driver frequency decreasing over time.

HSCoPP'04, Frèjus, France, October 21 - 23, 2004 Back Next

- p. 14/1

AR in turbulence



Amplitude of driven mode m = 3 over frequency, using increasing and decreasing driver frequency.

HSCoPP'04, Frèius, France, October 21 - 23, 2004 Back Next

– p. 15/1

AR (linearly stable system)



Amplitude of driven mode m = 3 over frequency, using increasing driver frequency, sweep stopped at certain frequency. Note: Linearly stable system.

HSCoPP'04, Frèjus, France, October 21 - 23, 2004 Back Next

- p. 16/1

Conclusion

- turblence control accomplished (aka GWB)
- modelled in simulations
- autoresonance as a simple control strategy
- some features of AR control demonstrated in 'taming turbulence'
- allows to optimize control power
- promising for future investigations

Thanks and Literature

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