Structured Electronic Design

Frequency stability of feedback amplifiers

Anton J.M. Montagne

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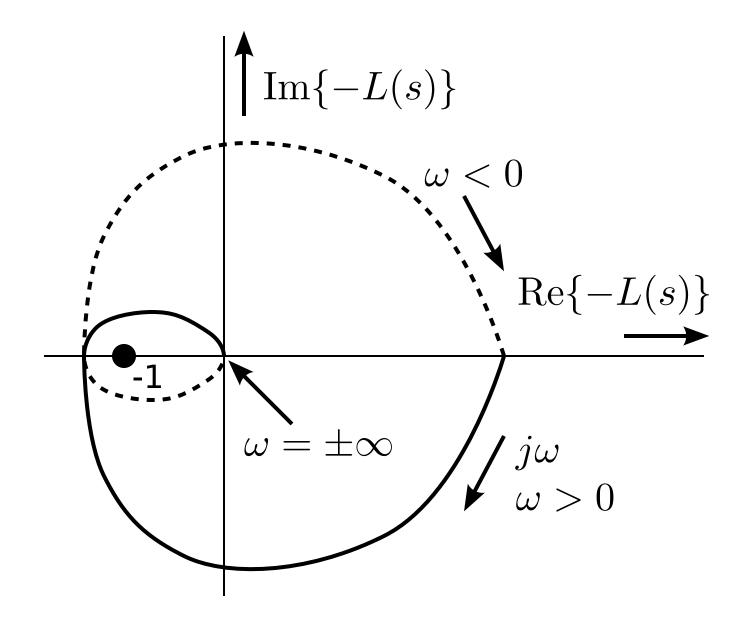
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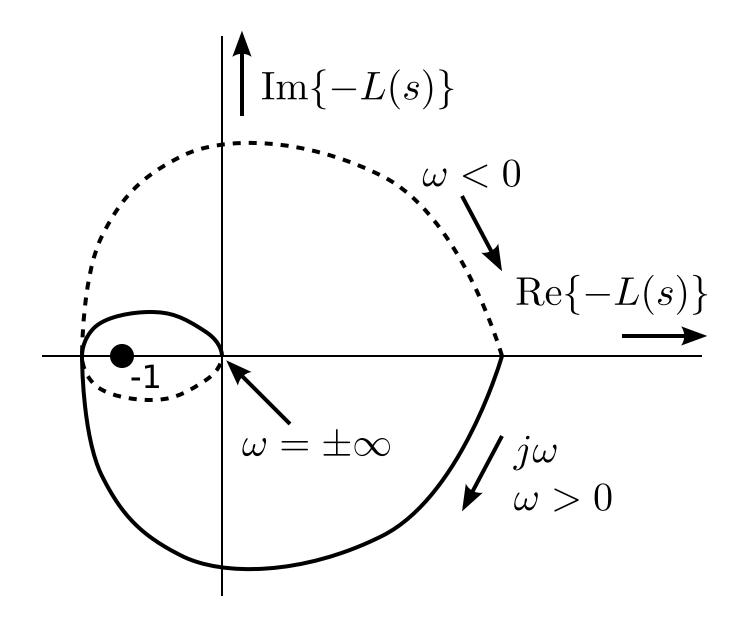
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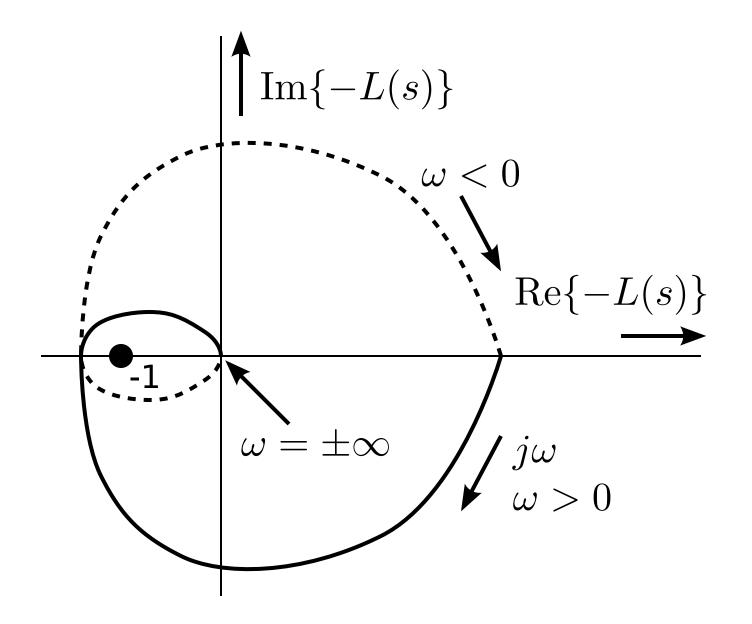
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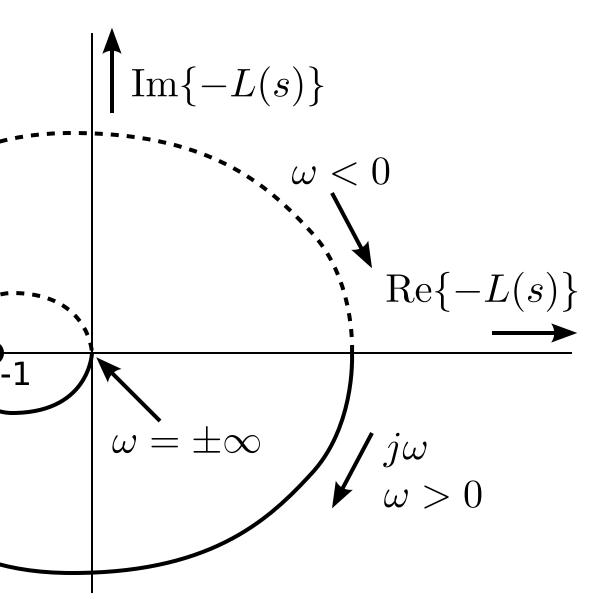


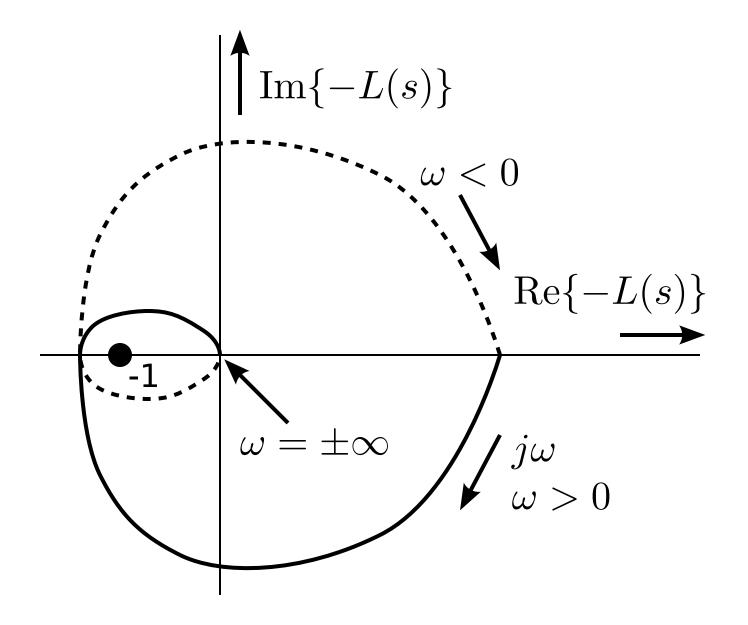


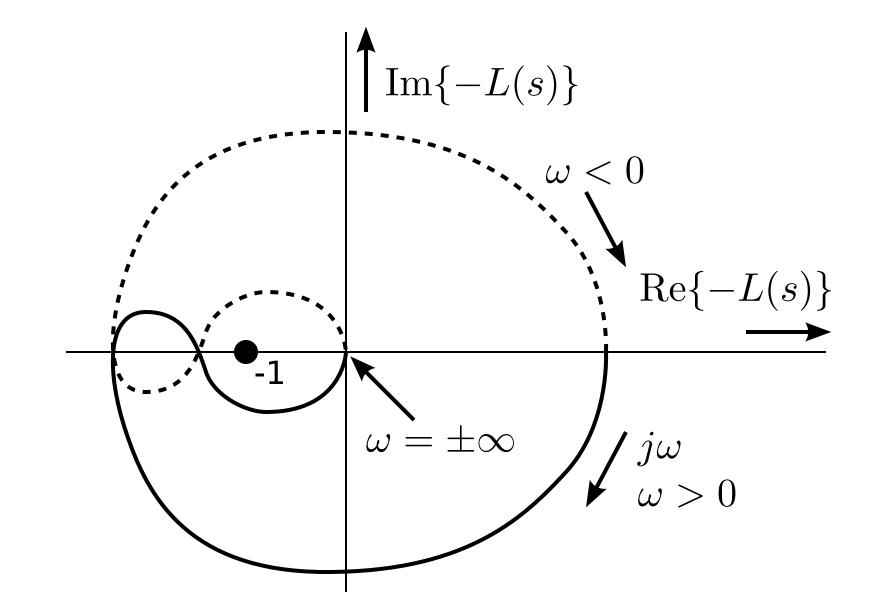
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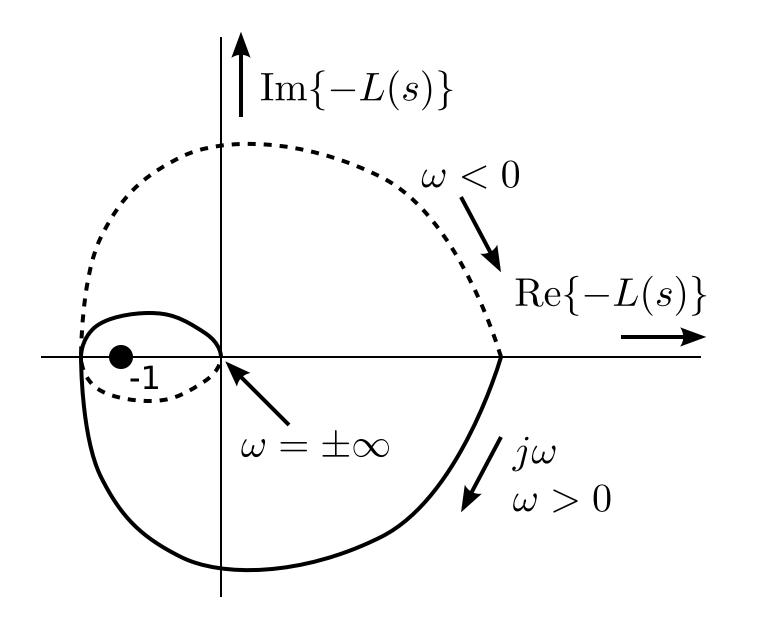


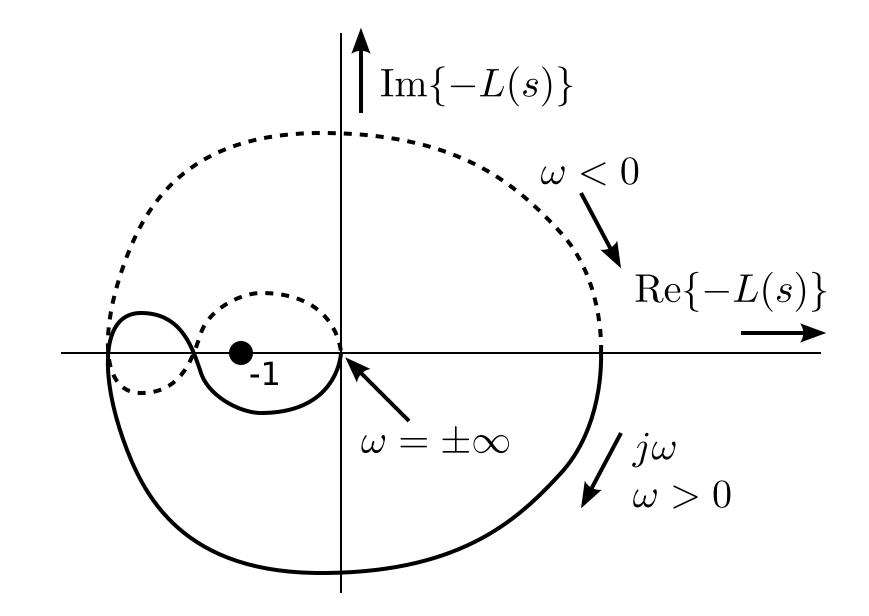




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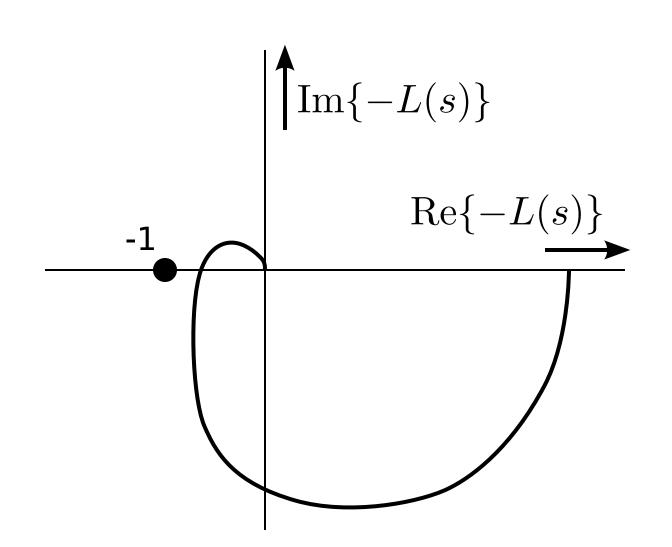


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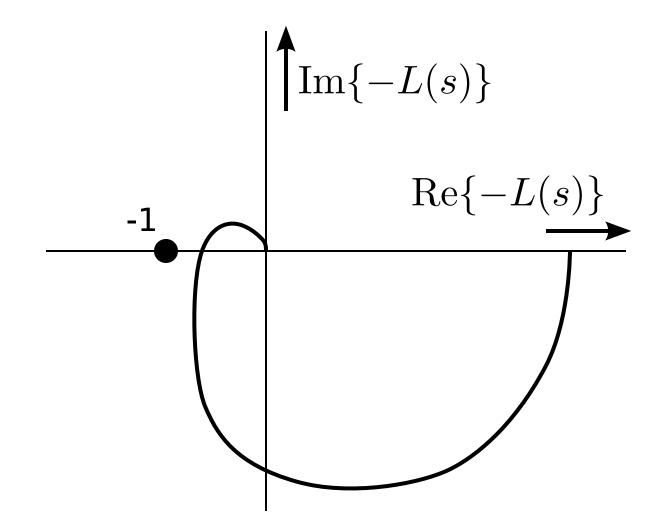
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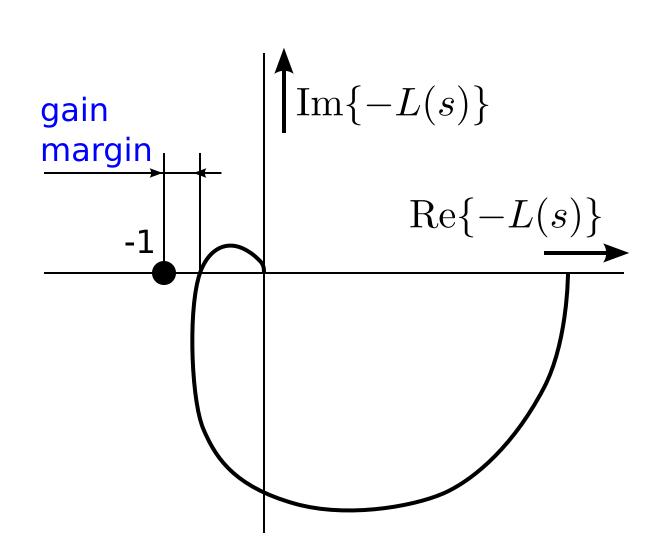
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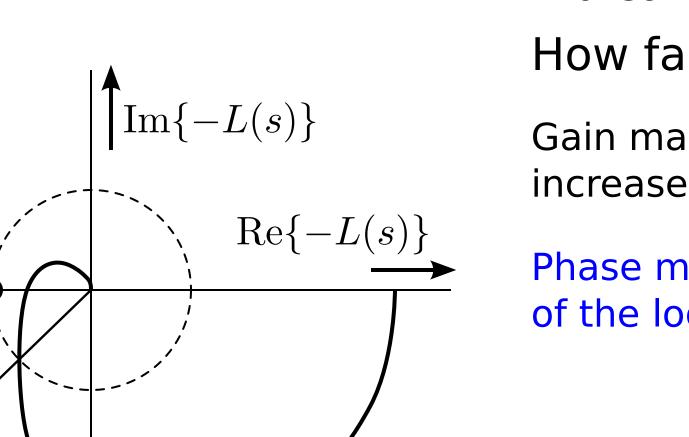


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Gain margin: how much in dB the loop gain must be increased to cause instability



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-1

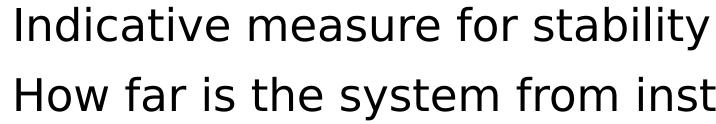
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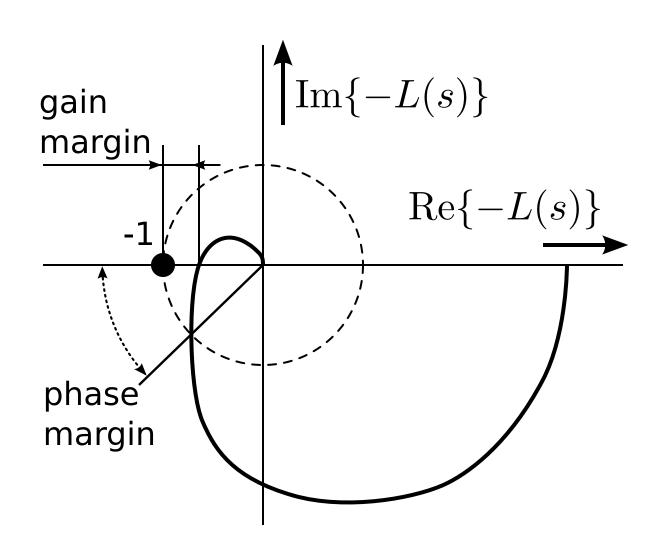
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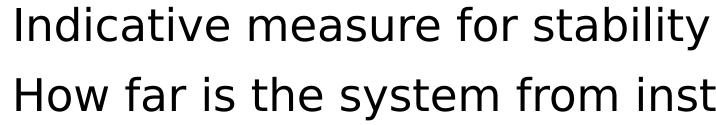


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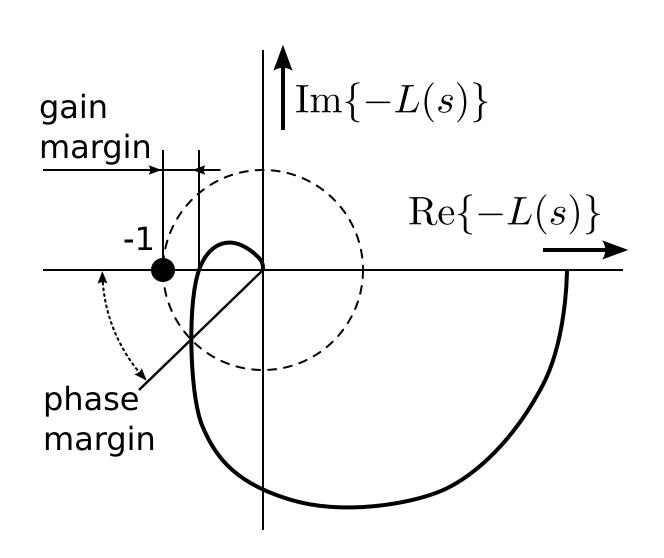


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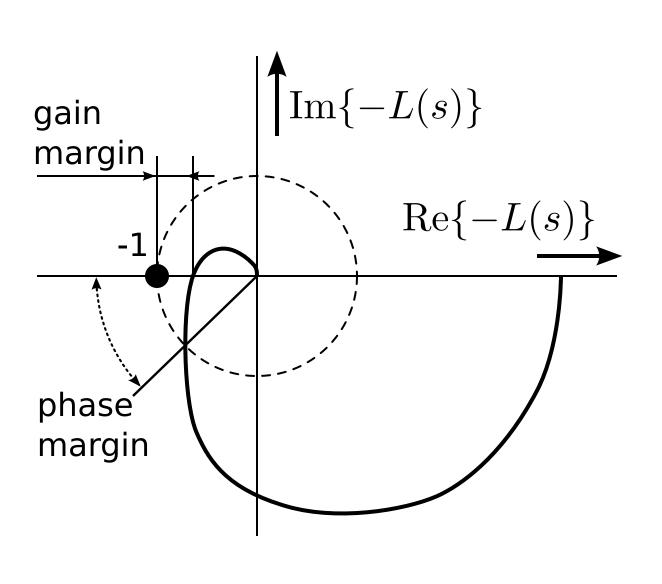


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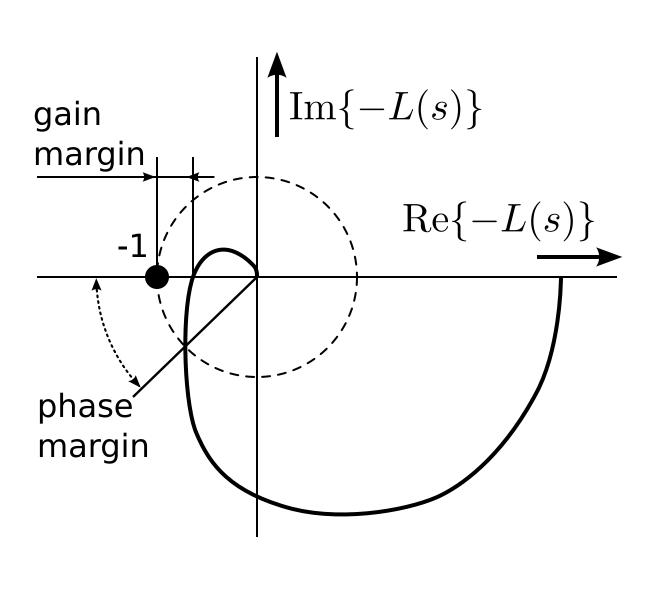
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Rules of thumb:

1. Gain margin better than 6 dB 2. Phase margin better than 30 degrees

Warnings:

- How far is the system from instability ...
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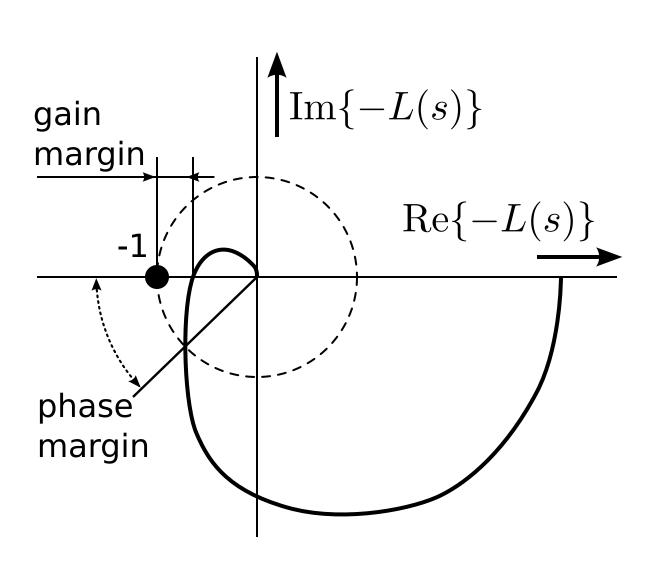
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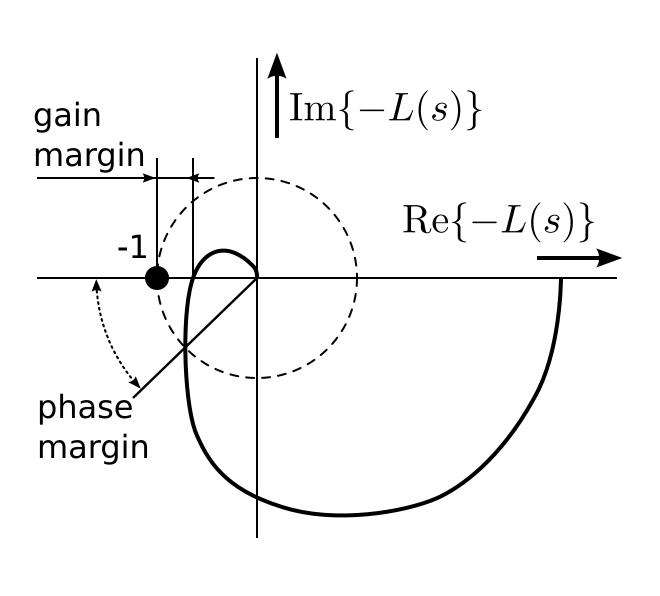
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Root locus:

Paths traced out by the poles of the servo function while varying the DC loop gain

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Paths traced out by the poles of the servo function while varying the DC loop gain

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Paths traced out by the poles of the servo function while varying the DC loop gain

Paths depend on:

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Starting point: DC loop gain equals zero

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Paths traced out by the poles of the servo function while varying the DC loop gain

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Starting point: DC loop gain equals zero End point: DC loop gain equals infinity

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Paths traced out by the poles of the servo function while varying the DC loop gain

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Paths traced out by the poles of the servo function while varying the DC loop gain

Paths depend on:

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1. Number of branches equals number of poles of the loop gain

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Paths traced out by the poles of the servo function while varying the DC loop gain

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- 1. Number of branches equals number of poles of the loop gain
- 2. Symmetrical with respect to the real axis
- 3. Branches start at poles of the loop gain

$$S(s) = \frac{-L(s)}{1-L(s)} = \frac{-L_{\rm DC}N(s)}{D(s)-L_{\rm DC}N(s)}$$

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Paths traced out by the poles of the servo function while varying the DC loop gain

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Paths traced out by the poles of the servo function while varying the DC loop gain

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- 2. Zeros of the loop gain
- 3. DC loop gain

- 1. Number of branches equals number of poles of the loop gain
- 2. Symmetrical with respect to the real axis
- 3. Branches start at poles of the loop gain
- 4. Branches end at zeros of the loop gain or at infinity

$$L(s) = L_{\rm DC} \frac{N(s)}{D(s)}$$

 $\begin{array}{ll} L_{\rm DC} = & {\sf DC} \mbox{ value of the loop gain} \\ N(s) = 0 \Longrightarrow {\sf Zeros of the loop gain} \\ D(s) = 0 \Longrightarrow {\sf Poles of the loop gain} \end{array}$

$$S(s) = \frac{-L(s)}{1-L(s)} = \frac{-L_{\rm DC}N(s)}{D(s)-L_{\rm DC}N(s)}$$

 $D(s) - L_{\rm DC}N(s) = 0 \Longrightarrow$ Poles of servo function

Root locus:

Paths traced out by the poles of the servo function while varying the DC loop gain

Paths depend on:

- 1. Poles of the loop gain
- 2. Zeros of the loop gain
- 3. DC loop gain

- 1. Number of branches equals number of poles of the loop gain
- 2. Symmetrical with respect to the real axis
- 3. Branches start at poles of the loop gain
- 4. Branches end at zeros of the loop gain or at infinity
- 5. Parts of the real axis left from odd number of poles + zeros belong to a branch

$$L(s) = L_{\rm DC} \frac{N(s)}{D(s)}$$

 $\begin{array}{ll} L_{\rm DC} = & {\sf DC} \mbox{ value of the loop gain} \\ N(s) = 0 \Longrightarrow {\sf Zeros of the loop gain} \\ D(s) = 0 \Longrightarrow {\sf Poles of the loop gain} \end{array}$

$$S(s) = \frac{-L(s)}{1-L(s)} = \frac{-L_{\rm DC}N(s)}{D(s)-L_{\rm DC}N(s)}$$

 $D(s) - L_{\rm DC}N(s) = 0 \Longrightarrow$ Poles of servo function

Root locus:

Paths traced out by the poles of the servo function while varying the DC loop gain

Paths depend on:

- 1. Poles of the loop gain
- 2. Zeros of the loop gain
- 3. DC loop gain

- 1. Number of branches equals number of poles of the loop gain
- 2. Symmetrical with respect to the real axis
- 3. Branches start at poles of the loop gain
- 4. Branches end at zeros of the loop gain or at infinity
- 5. Parts of the real axis left from odd number of poles + zeros belong to a branch
- 6. n poles and m zeros, then n m asymptotes

$$L(s) = L_{\rm DC} \frac{N(s)}{D(s)}$$

 $\begin{array}{ll} L_{\rm DC} = & {\sf DC} \mbox{ value of the loop gain} \\ N(s) = 0 \Longrightarrow {\sf Zeros of the loop gain} \\ D(s) = 0 \Longrightarrow {\sf Poles of the loop gain} \end{array}$

$$S(s) = \frac{-L(s)}{1 - L(s)} = \frac{-L_{\rm DC}N(s)}{D(s) - L_{\rm DC}N(s)}$$

 $D(s) - L_{\rm DC}N(s) = 0 \Longrightarrow$ Poles of servo function

Root locus:

Paths traced out by the poles of the servo function while varying the DC loop gain

Paths depend on:

- 1. Poles of the loop gain
- 2. Zeros of the loop gain
- 3. DC loop gain

- 1. Number of branches equals number of poles of the loop gain
- 2. Symmetrical with respect to the real axis
- 3. Branches start at poles of the loop gain
- 4. Branches end at zeros of the loop gain or at infinity
- 5. Parts of the real axis left from odd number of poles + zeros belong to a branch
- 6. n poles and m zeros, then n m asymptotes
- 7. Real axis intersection point asymptotes

$$L(s) = L_{\rm DC} \frac{N(s)}{D(s)}$$

 $\begin{array}{ll} L_{\rm DC} = & {\sf DC} \mbox{ value of the loop gain} \\ N(s) = 0 \Longrightarrow {\sf Zeros of the loop gain} \\ D(s) = 0 \Longrightarrow {\sf Poles of the loop gain} \end{array}$

$$S(s) = \frac{-L(s)}{1 - L(s)} = \frac{-L_{\rm DC}N(s)}{D(s) - L_{\rm DC}N(s)}$$

 $D(s) - L_{\rm DC}N(s) = 0 \Longrightarrow$ Poles of servo function

Root locus:

Paths traced out by the poles of the servo function while varying the DC loop gain

Paths depend on:

- 1. Poles of the loop gain
- 2. Zeros of the loop gain
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$$\sigma = \frac{\sum_{k=1}^{n} p_k - \sum_{i=1}^{m} z_i}{n - m}$$

$$L(s) = L_{\rm DC} \frac{N(s)}{D(s)}$$

 $L_{\rm DC} = -$ DC value of the loop gain $N(s) = 0 \Longrightarrow$ Zeros of the loop gain $D(s) = 0 \Longrightarrow$ Poles of the loop gain

$$S(s) = \frac{-L(s)}{1 - L(s)} = \frac{-L_{\rm DC}N(s)}{D(s) - L_{\rm DC}N(s)}$$

 $D(s) - L_{\rm DC}N(s) = 0 \Longrightarrow$ Poles of servo function

Root locus:

Paths traced out by the poles of the servo function while varying the DC loop gain

Paths depend on:

- 1. Poles of the loop gain
- 2. Zeros of the loop gain
- 3. DC loop gain

Starting point: DC loop gain equals zero End point: DC loop gain equals infinity Actual servo poles: DC loop gain $= L_{DC}$

- 1. Number of branches equals number of poles of the loop gain
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$$\sigma = \frac{\sum_{k=1}^{n} p_k - \sum_{i=1}^{m} z_i}{n - m}$$

8. Angle asymptotes equally spaced

$$L(s) = L_{\rm DC} \frac{N(s)}{D(s)}$$

 $L_{\rm DC} = -$ DC value of the loop gain $N(s) = 0 \Longrightarrow$ Zeros of the loop gain $D(s) = 0 \Longrightarrow$ Poles of the loop gain

$$S(s) = \frac{-L(s)}{1-L(s)} = \frac{-L_{\rm DC}N(s)}{D(s)-L_{\rm DC}N(s)}$$

 $D(s) - L_{\rm DC}N(s) = 0 \Longrightarrow$ Poles of servo function

Root locus:

Paths traced out by the poles of the servo function while varying the DC loop gain

Paths depend on:

- 1. Poles of the loop gain
- 2. Zeros of the loop gain
- 3. DC loop gain

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$$\sigma = \frac{\sum_{k=1}^{n} p_k - \sum_{i=1}^{m} z_i}{n - m}$$

- 8. Angle asymptotes equally spaced
- 9. Break away (and arrival) points

$$L(s) = L_{\rm DC} \frac{N(s)}{D(s)}$$

 $L_{\rm DC} = -$ DC value of the loop gain $N(s) = 0 \Longrightarrow$ Zeros of the loop gain $D(s) = 0 \Longrightarrow$ Poles of the loop gain

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$$\sigma = \frac{\sum_{k=1}^{n} p_k - \sum_{i=1}^{m} z_i}{n - m}$$

8. Angle asymptotes equally spaced

$$\frac{d}{ds}L(s) = 0$$

10. Break away angles equally spaced

$$L(s) = L_{\rm DC} \frac{N(s)}{D(s)}$$

 $L_{\rm DC} = -$ DC value of the loop gain $N(s) = 0 \Longrightarrow$ Zeros of the loop gain $D(s) = 0 \Longrightarrow$ Poles of the loop gain

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 $D(s) - L_{\rm DC}N(s) = 0 \Longrightarrow$ Poles of servo function

Root locus:

Paths traced out by the poles of the servo function while varying the DC loop gain

Paths depend on:

- 1. Poles of the loop gain
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- 6. n poles and m zeros, then n m asymptotes
- 7. Real axis intersection point asymptotes

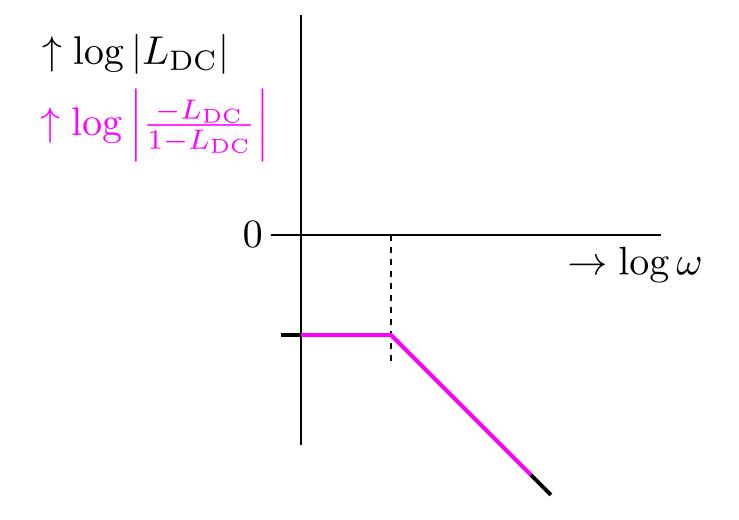
9. Break away (and arrival) points

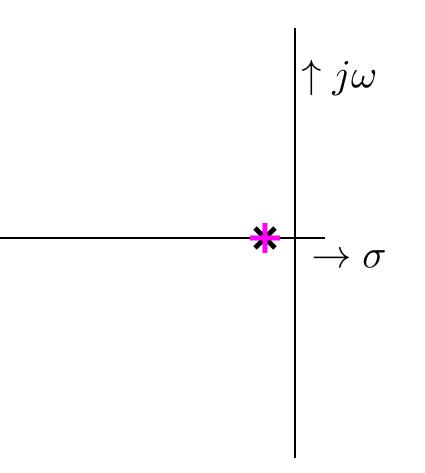
$$\sigma = \frac{\sum_{k=1}^{n} p_k - \sum_{i=1}^{m} z_i}{n - m}$$

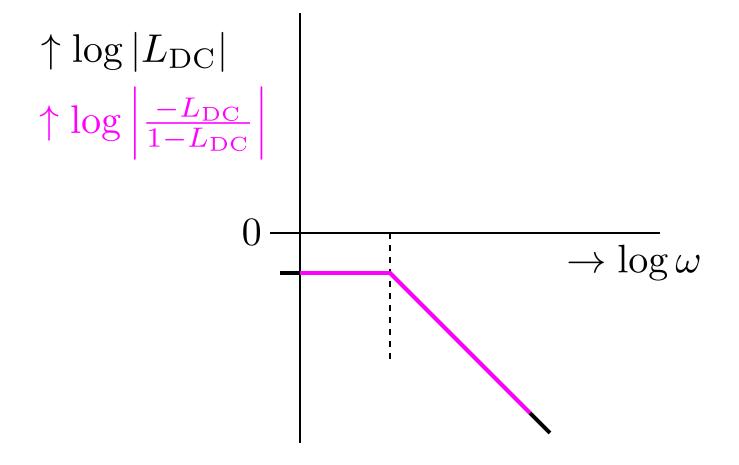
8. Angle asymptotes equally spaced

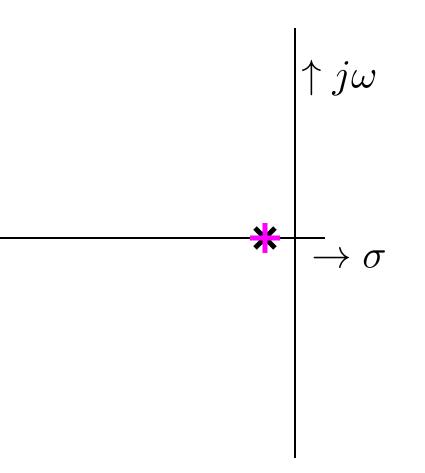
$$\frac{d}{ds}L(s) = 0$$

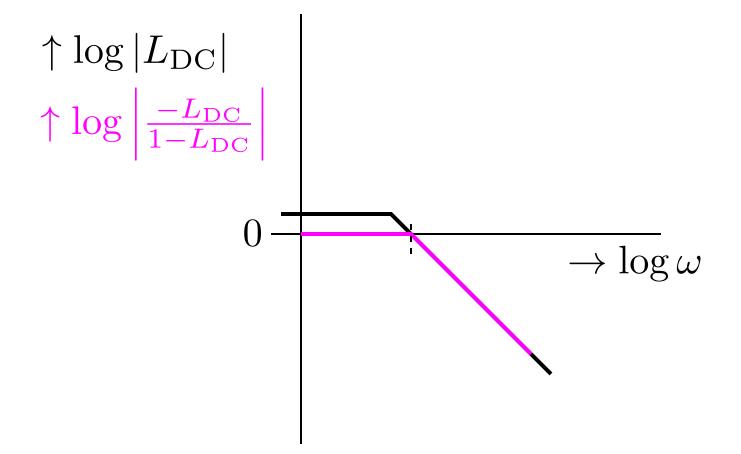
10. Break away angles equally spaced

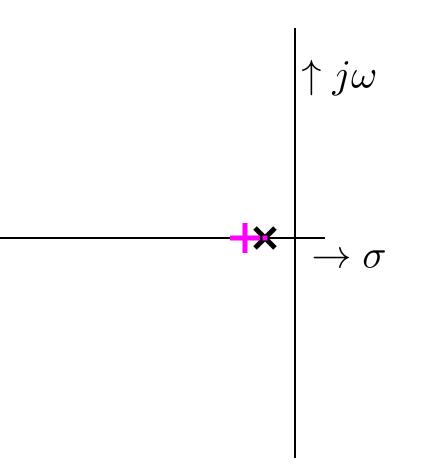


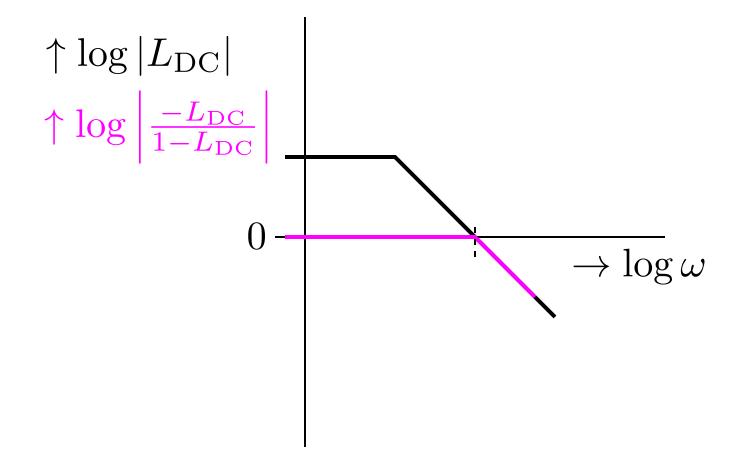


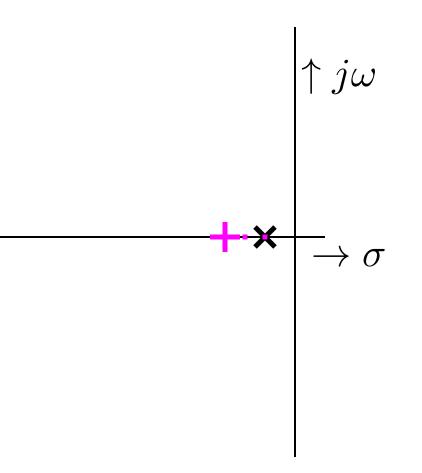


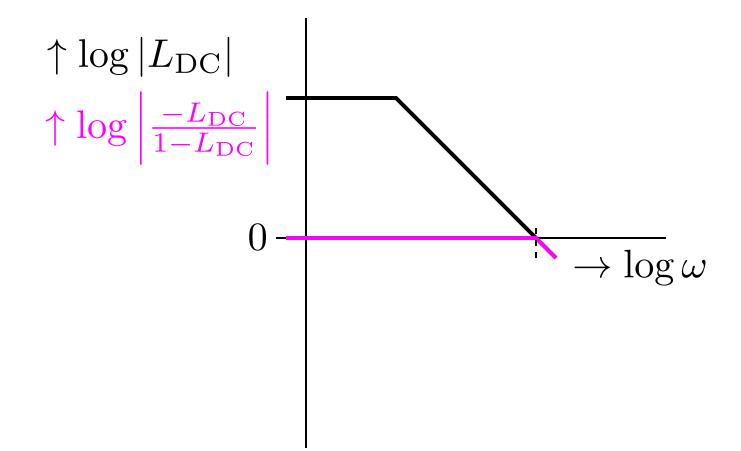


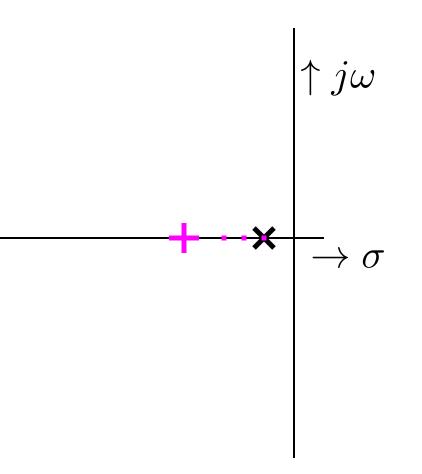


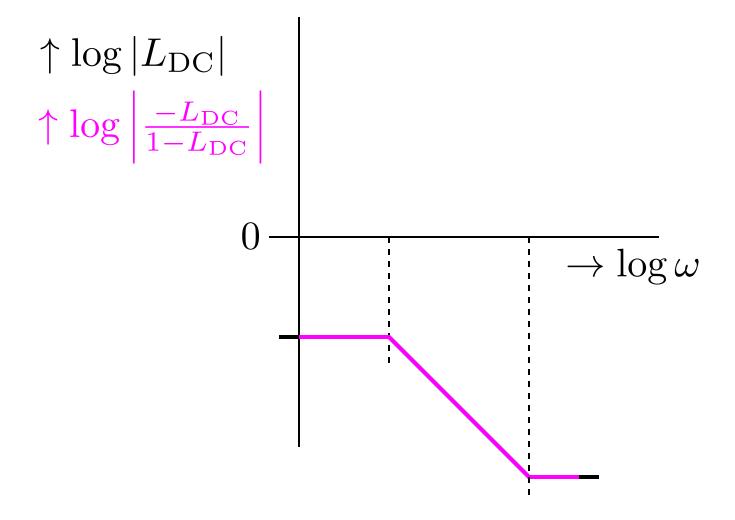


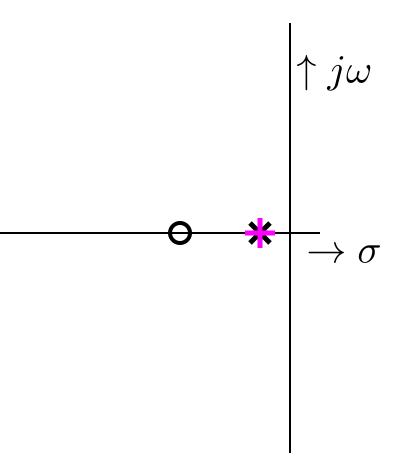


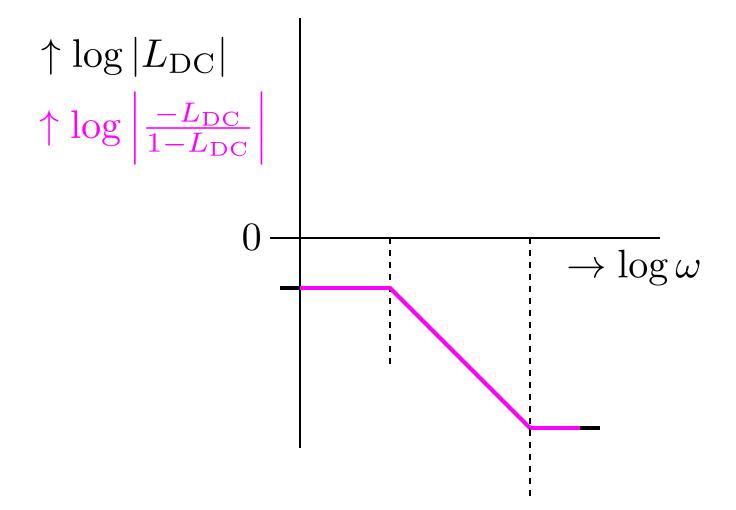


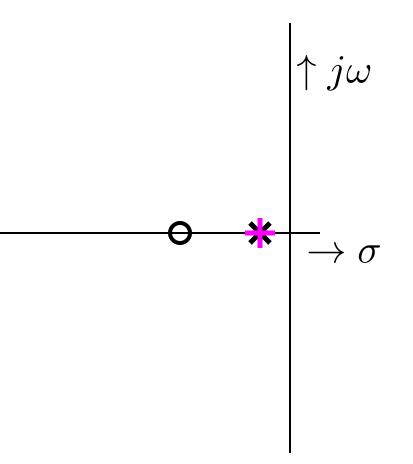


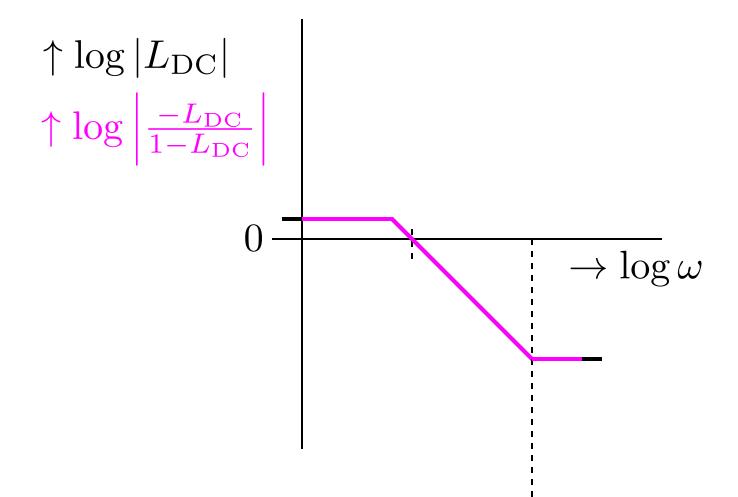


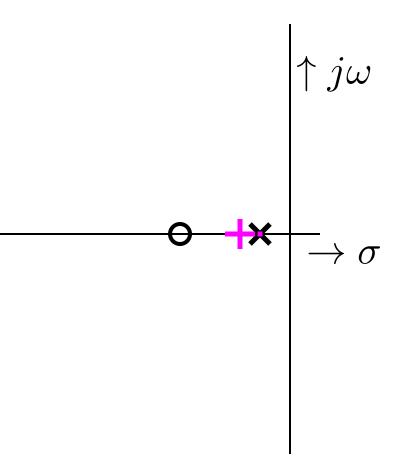


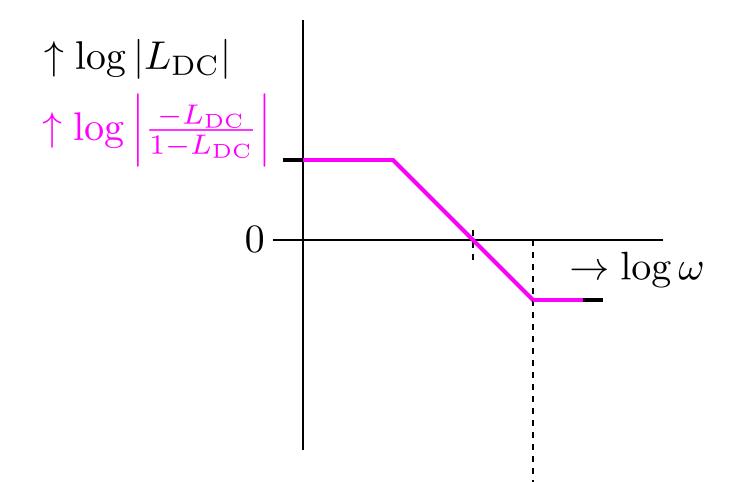


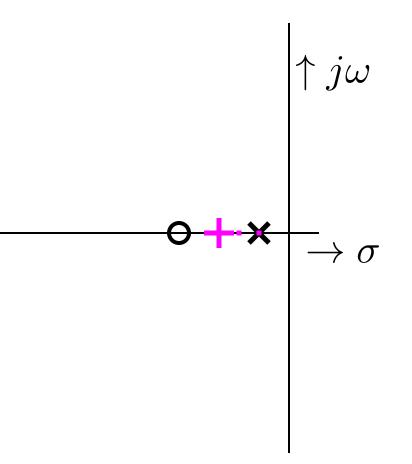


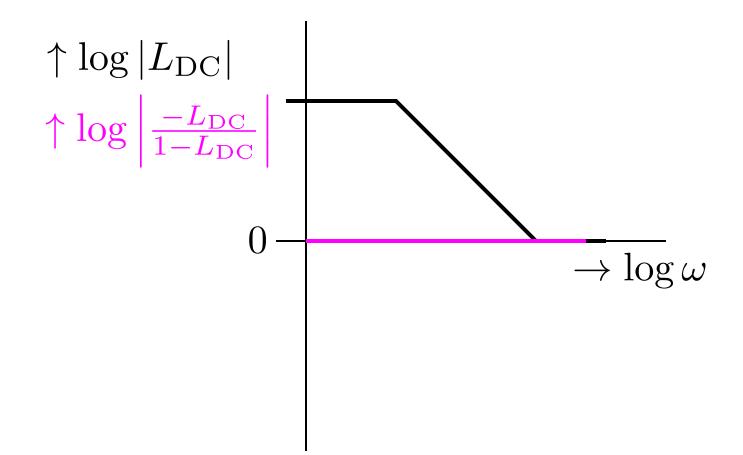


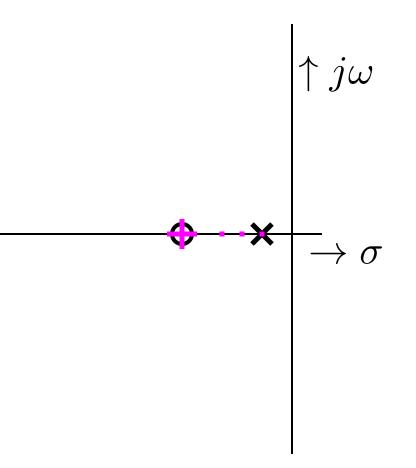


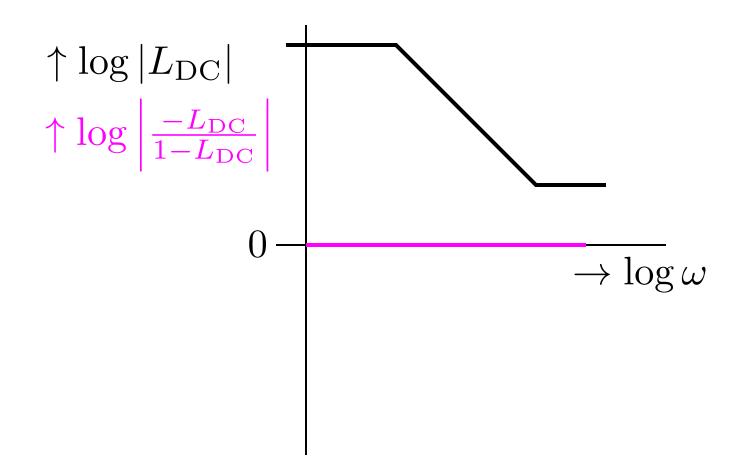


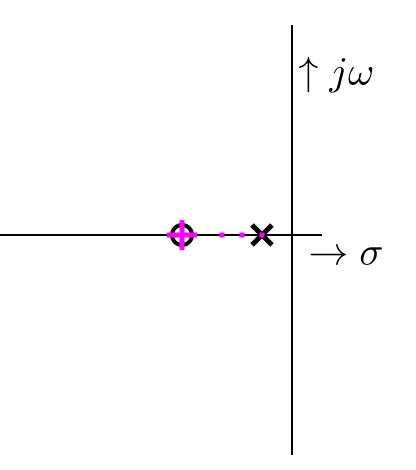


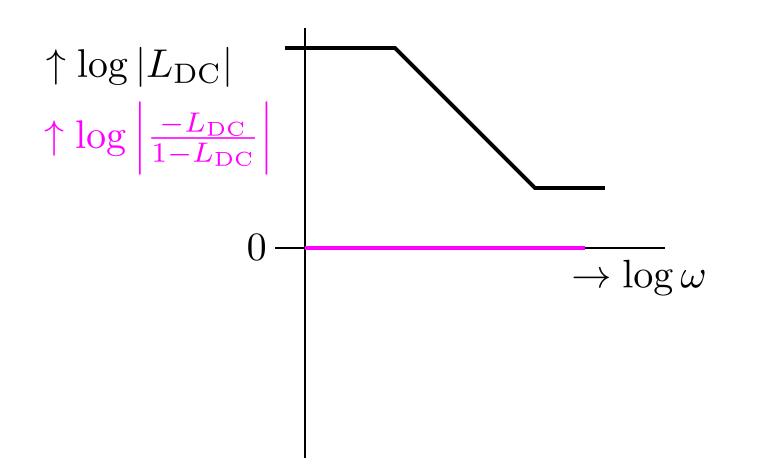




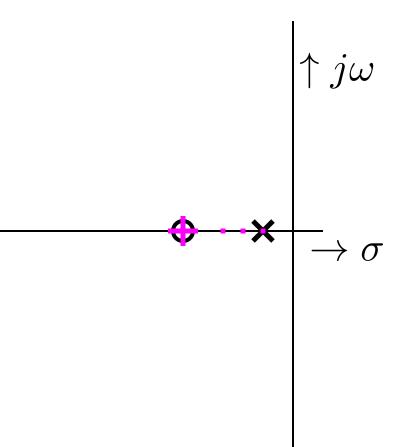


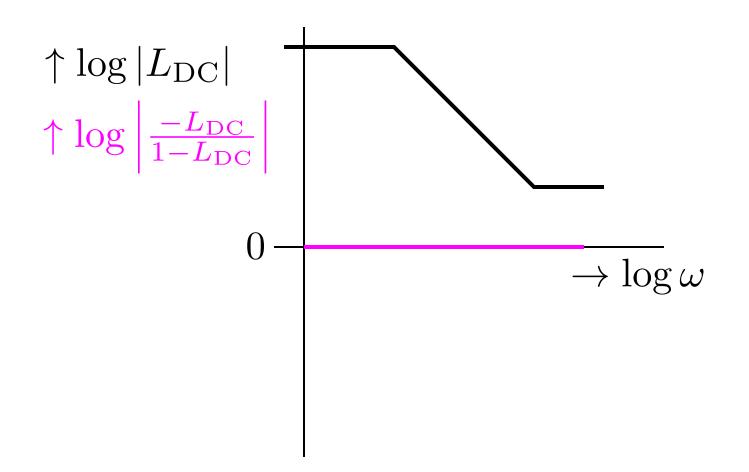




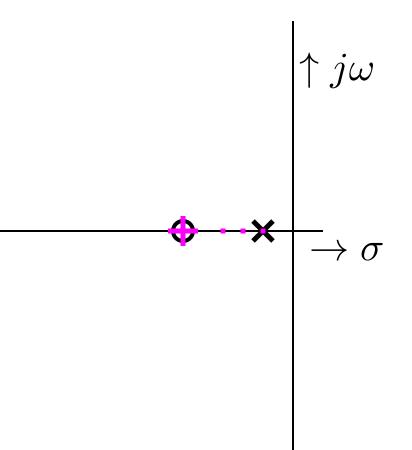


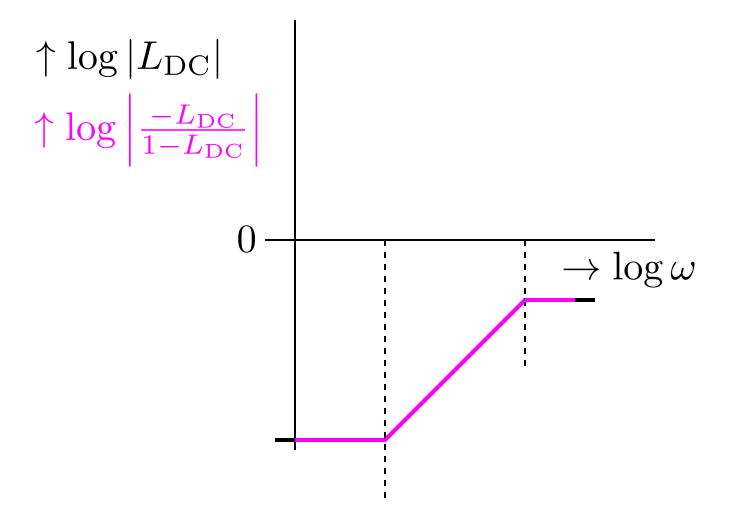
Note: pole only drops on the zero if DC loop gain is infinite!

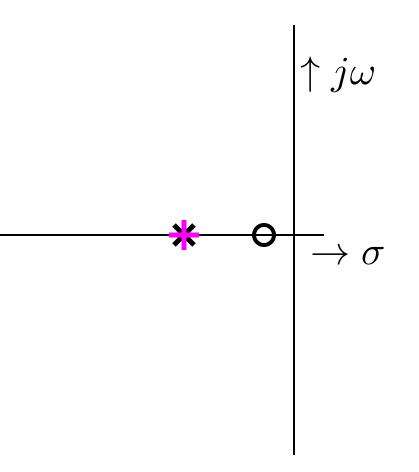


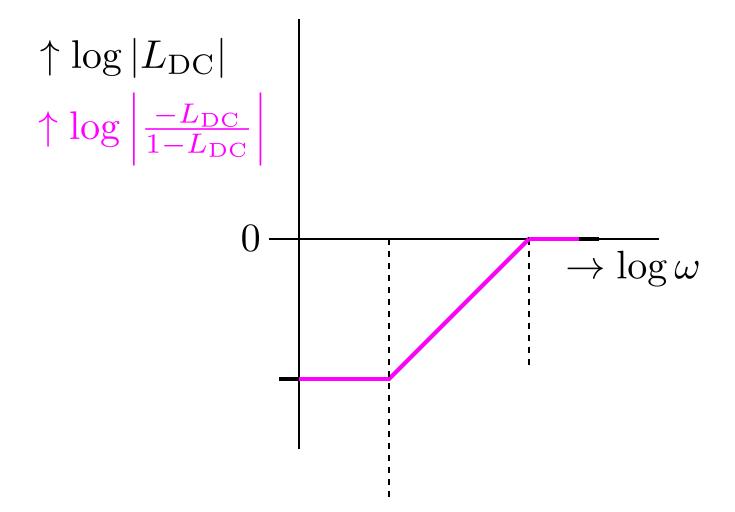


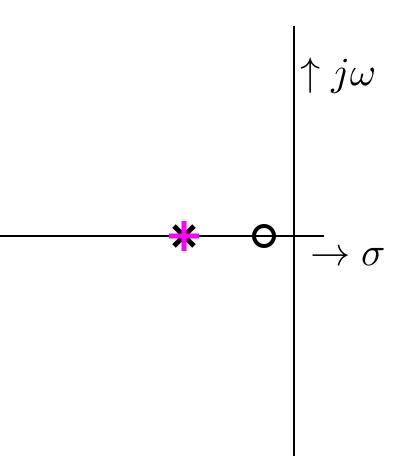
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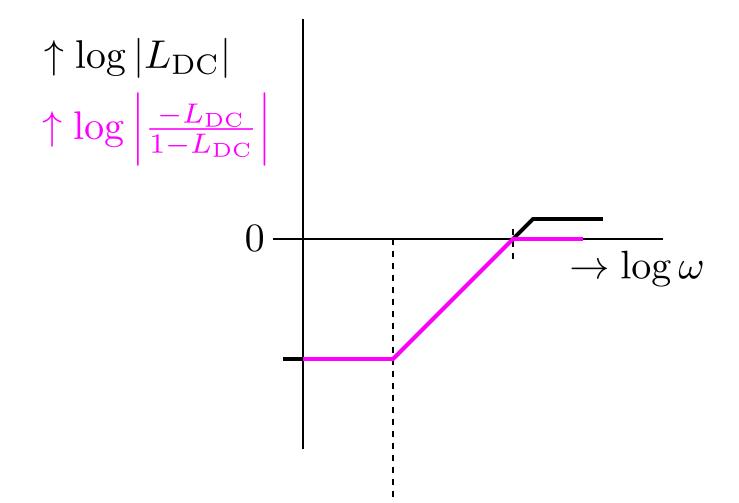


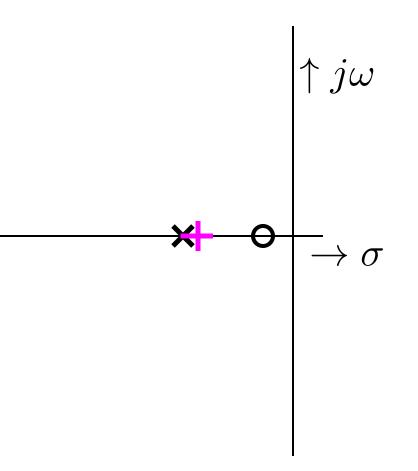


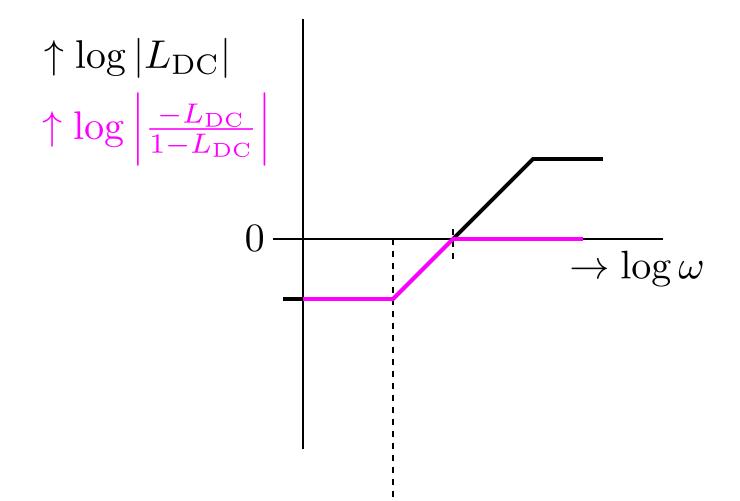


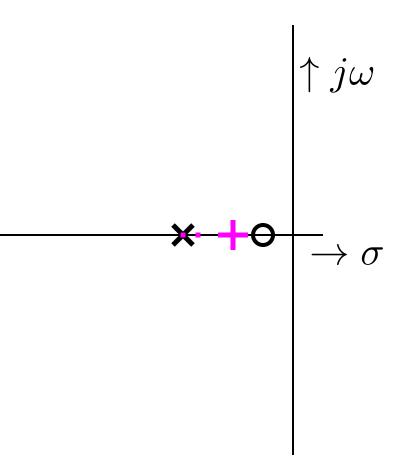


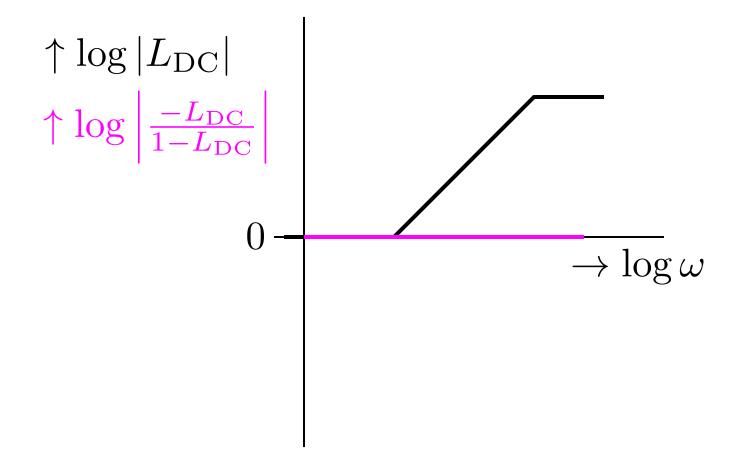


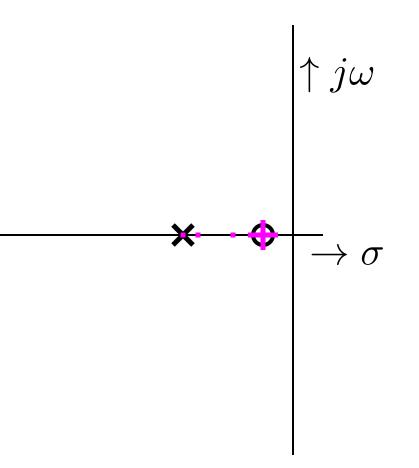


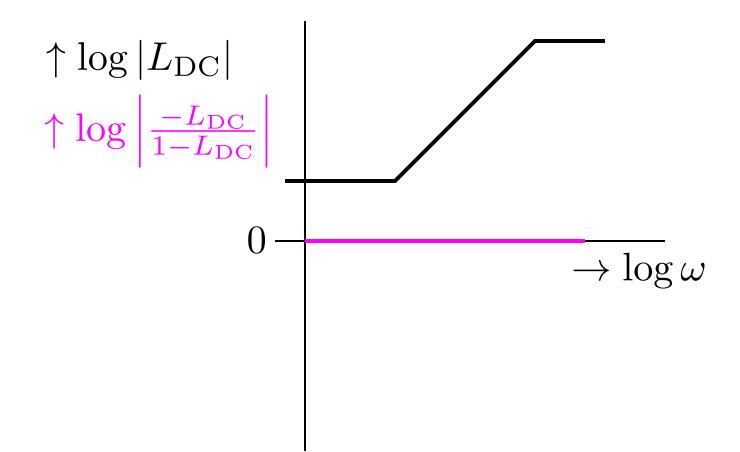


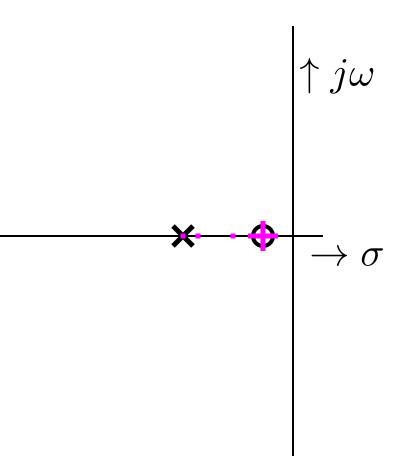


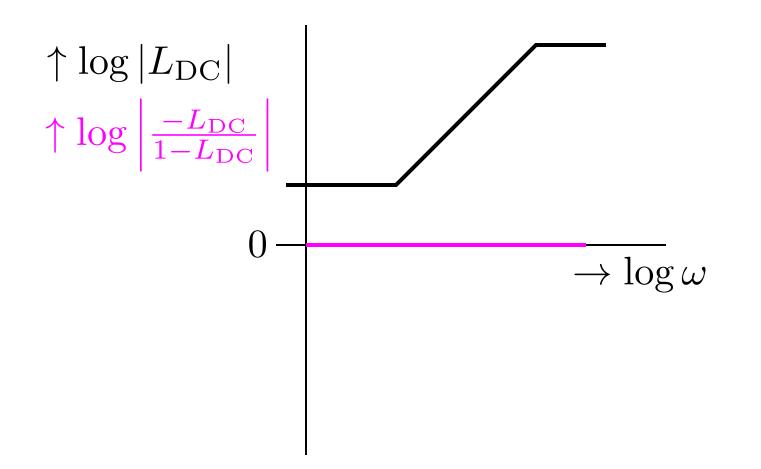




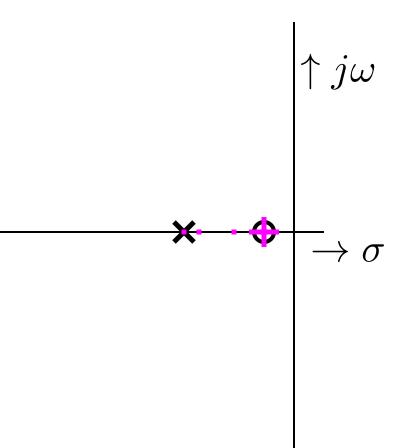


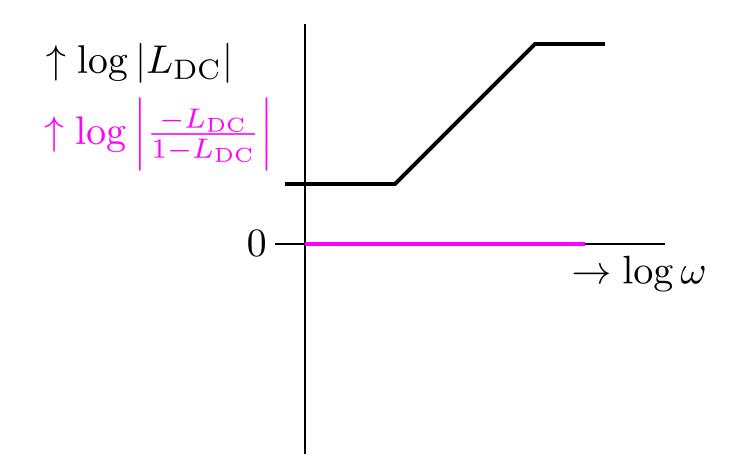




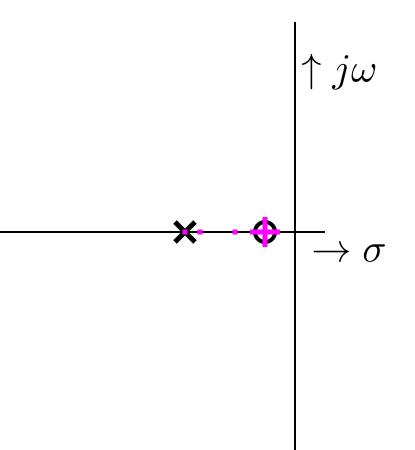


Note: pole only drops on the zero if DC loop gain is infinite!

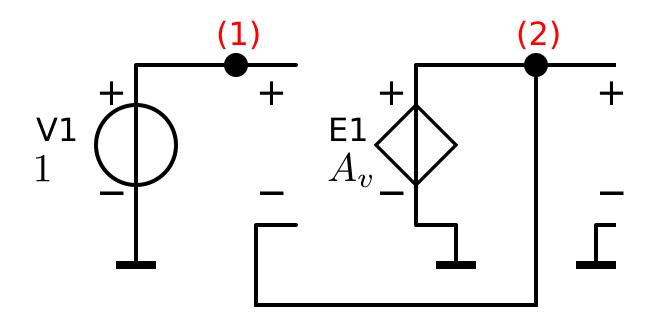




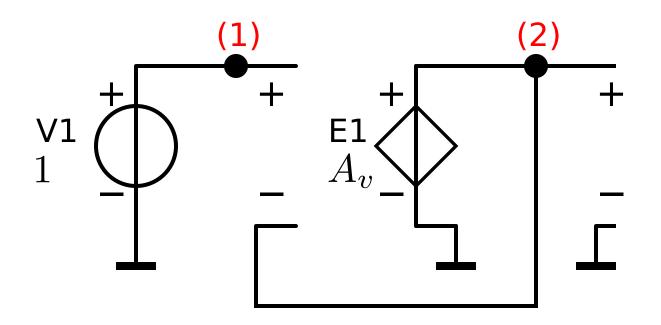
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Circuit for plotting root locus

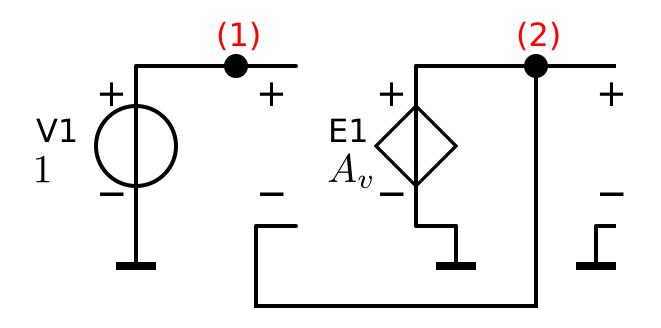


Circuit for plotting root locus



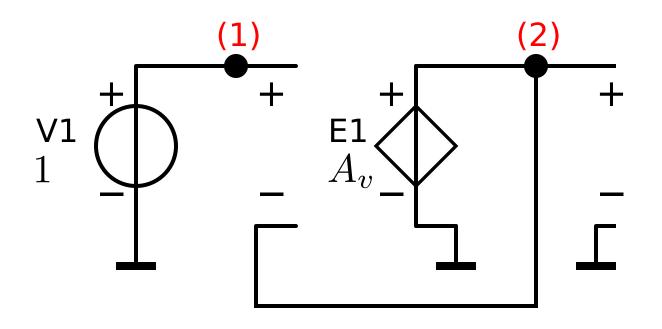
E1 = loop gain reference

Circuit for plotting root locus



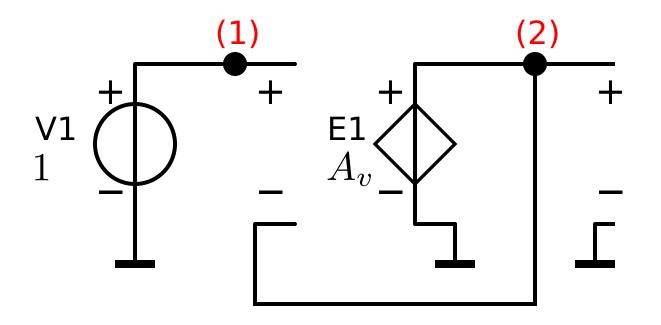
E1 = loop gain reference Loop gain equals voltage gain of E1

Circuit for plotting root locus



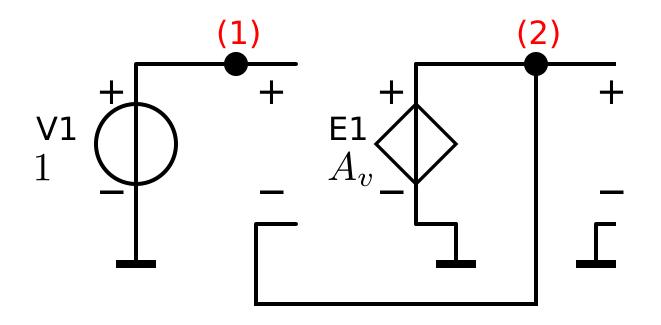
E1 = loop gain reference Loop gain equals voltage gain of E1 Transfer of E1 has DC gain, poles and zeros

Circuit for plotting root locus



E1 = loop gain reference Loop gain equals voltage gain of E1 Transfer of E1 has DC gain, poles and zeros Root locus plot:

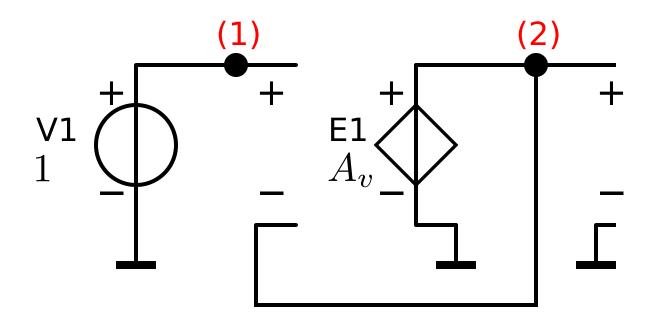
Circuit for plotting root locus



Root locus plot:1. Poles of the loop gain

E1 = loop gain reference Loop gain equals voltage gain of E1 Transfer of E1 has DC gain, poles and zeros

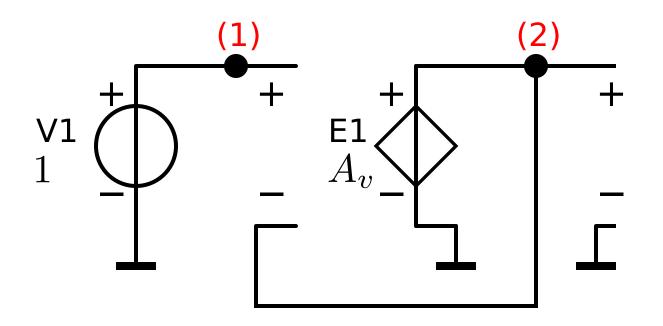
Circuit for plotting root locus



Root locus plot:1. Poles of the loop gain2. Zeros of the loop gain

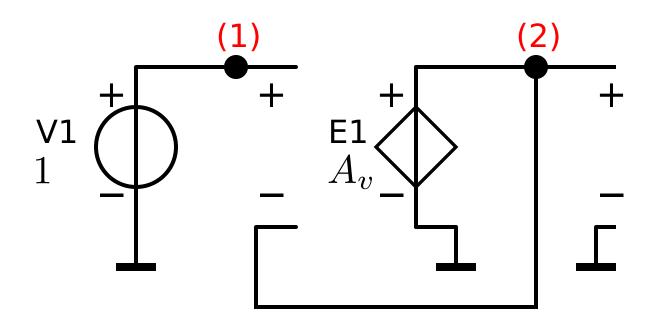
E1 = loop gain reference Loop gain equals voltage gain of E1 Transfer of E1 has DC gain, poles and zeros

Circuit for plotting root locus



E1 = loop gain referenceLoop gain equals voltage gain of E1 Transfer of E1 has DC gain, poles and zeros Root locus plot: 1. Poles of the loop gain 2. Zeros of the loop gain 3. Poles of the servo function while stepping the DC gain of E1

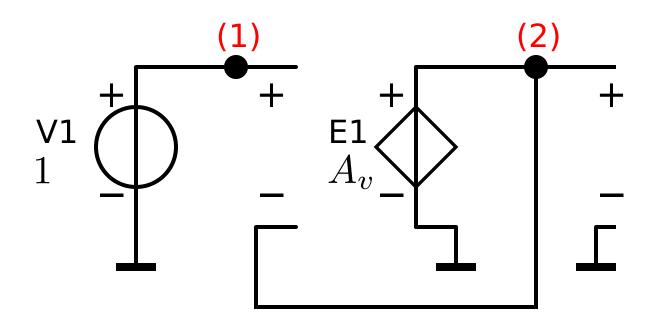




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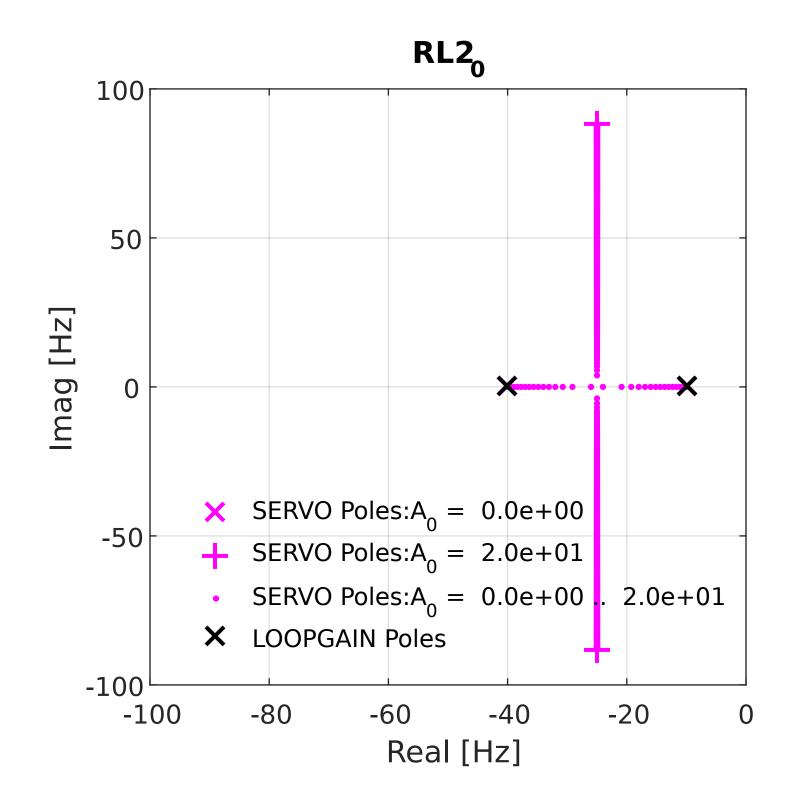
See section 11.5.3



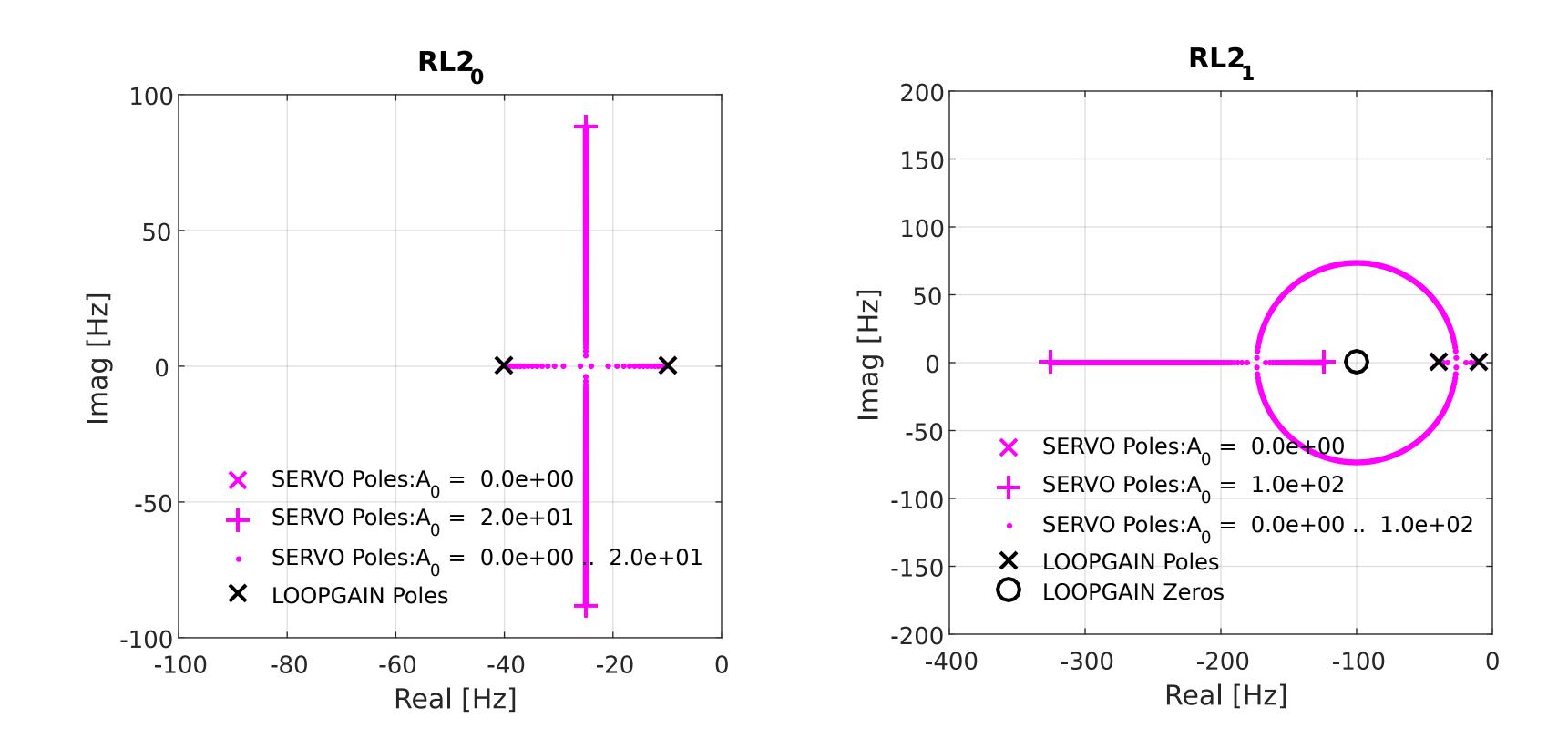


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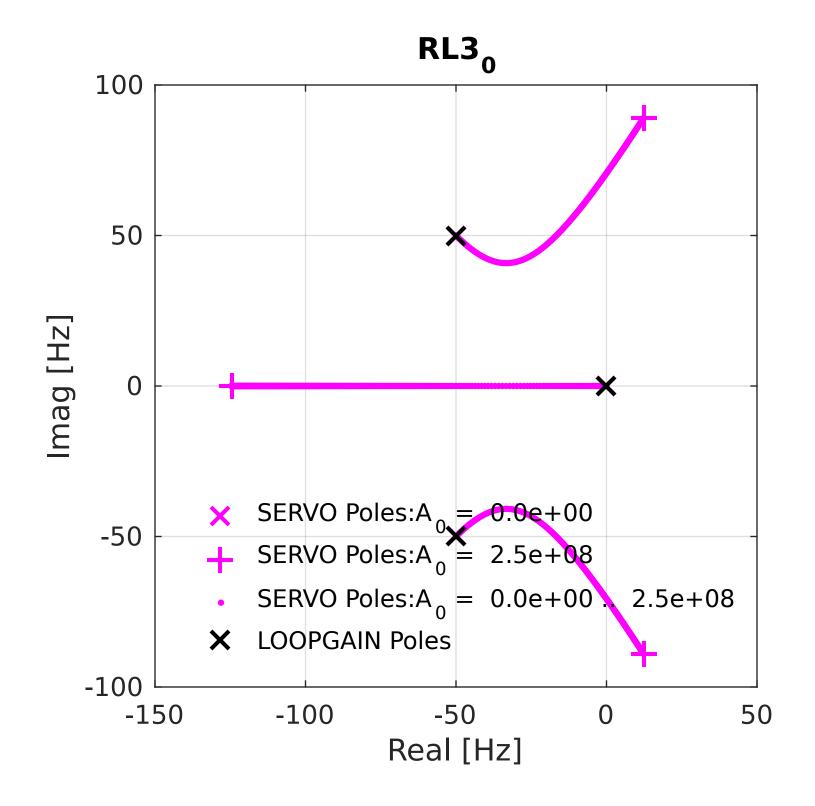
Root locus SLiCAP second order



Root locus SLiCAP second order



Root locus SLiCAP third order



Root locus SLiCAP third order

