

Structured Electronic Design

Phantom Zero Compensation 2nd-order System

Phantom compensation 2nd order system

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$$L(s) = L_{DC} \frac{1-s/z}{(1-s/p_1)(1-s/p_2)}$$

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$$S(s) = \frac{-L_{DC}}{1-L_{DC}} \frac{1-s/z}{\frac{(1-s/p_1)(1-s/p_2)}{1-L_{DC}} - \frac{L_{DC}}{1-L_{DC}} (1-s/z)}$$

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$$A_f = A_i(s) \frac{-L_{DC}}{1-L_{DC}} \frac{1}{1+s \left(\frac{L_{DC}}{z(1-L_{DC})} - \frac{p_1+p_2}{p_1 p_2 (1-L_{DC})} \right) + \frac{s^2}{p_1 p_2 (1-L_{DC})}}$$

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← Phantom zero canceled by pole in the ideal gain (= asymptotic gain)

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A negative real zero increases the coefficient of s

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 Absolute value of the sum of the poles can only be increased!

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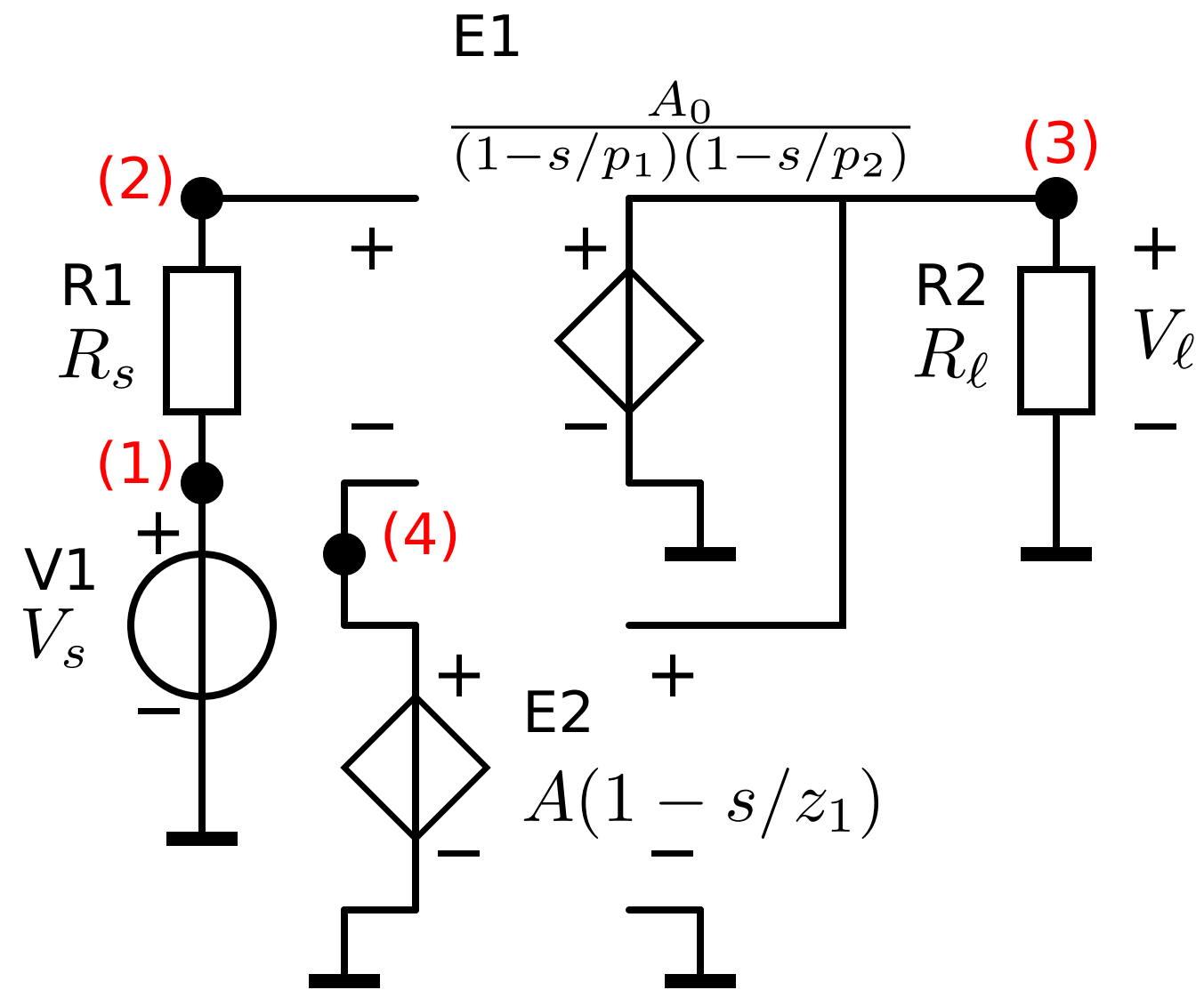
Phantom compensation 2nd order system

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Example 12.2

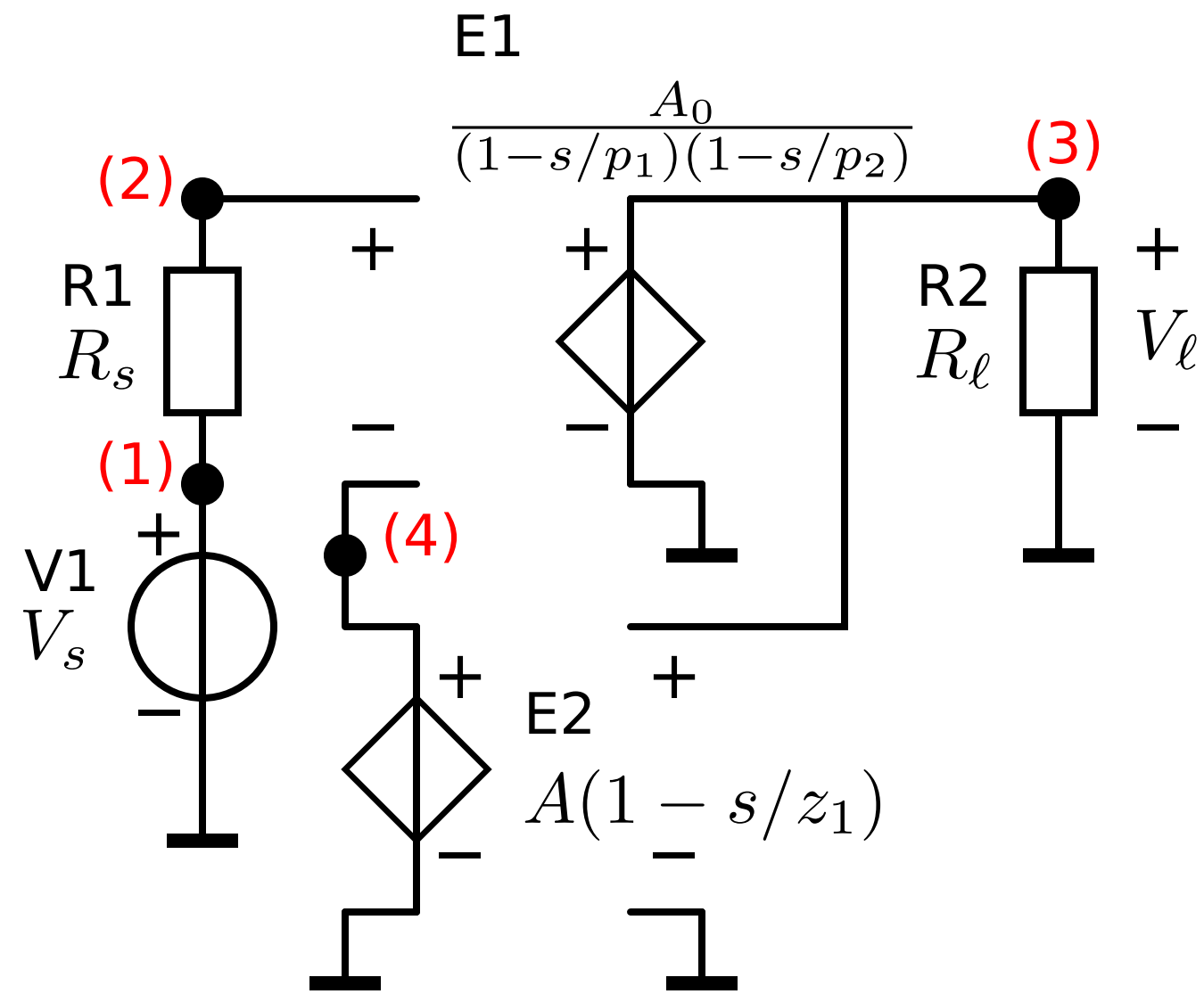
Phantom compensation 2nd order system

Example 12.2



Phantom compensation 2nd order system

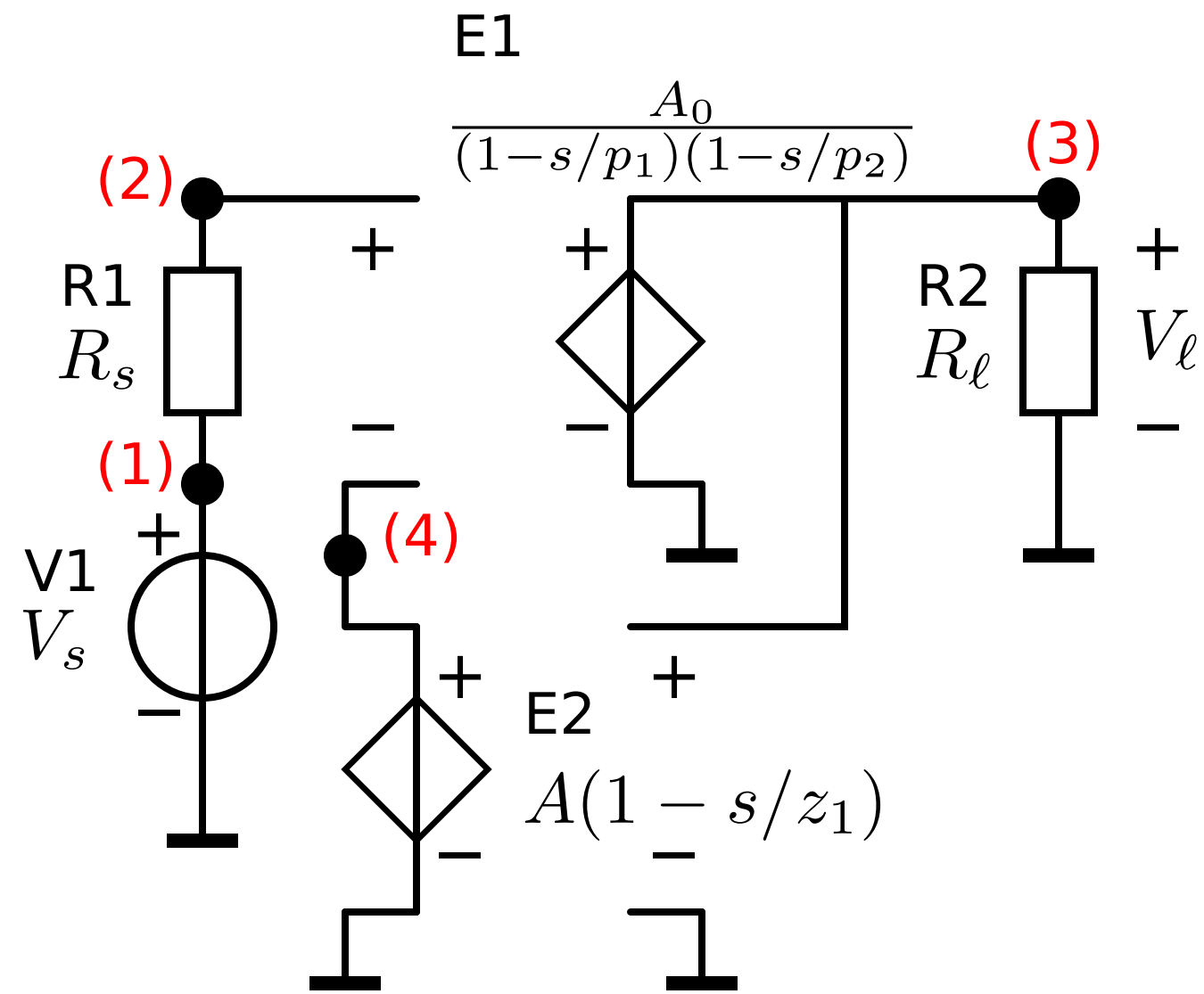
Example 12.2



$$\begin{aligned}
 p_1 &= -1 \text{ Hz}, \\
 p_2 &= -100 \text{ Hz}, \\
 A_0 &= 10^6 [-], \\
 A &= \frac{1}{100} [-].
 \end{aligned}$$

Phantom compensation 2nd order system

Example 12.2



$$p_1 = -1 \text{ Hz},$$

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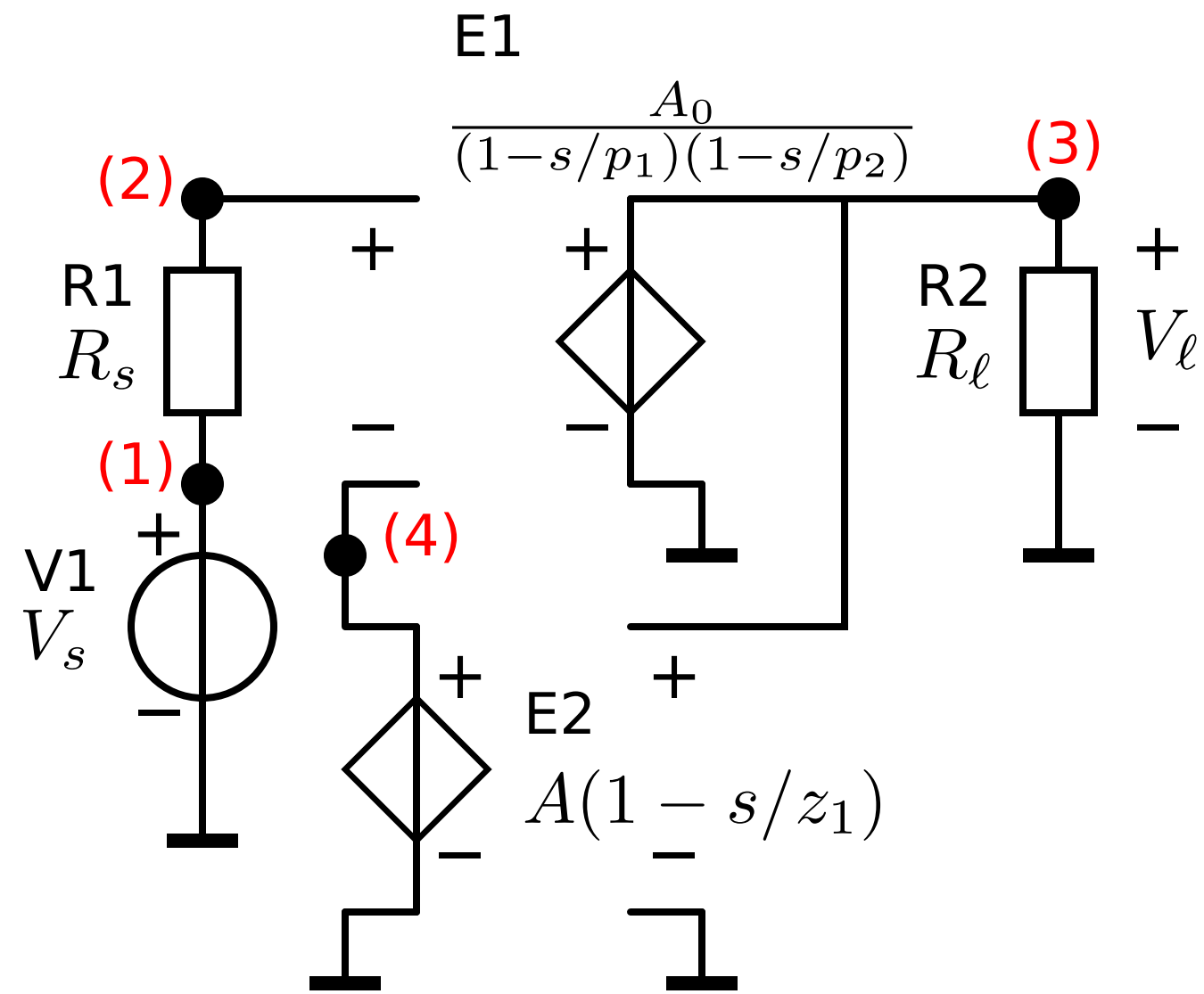
$$A_0 = 10^6 \text{ [-]},$$

$$A = \frac{1}{100} \text{ [-]}.$$

$$f_h = \sqrt{1 \cdot 100 \cdot \frac{1}{100} \cdot 10^6} = 1000 \text{ [Hz]}$$

Phantom compensation 2nd order system

Example 12.2



$$p_1 = -1 \text{ Hz},$$

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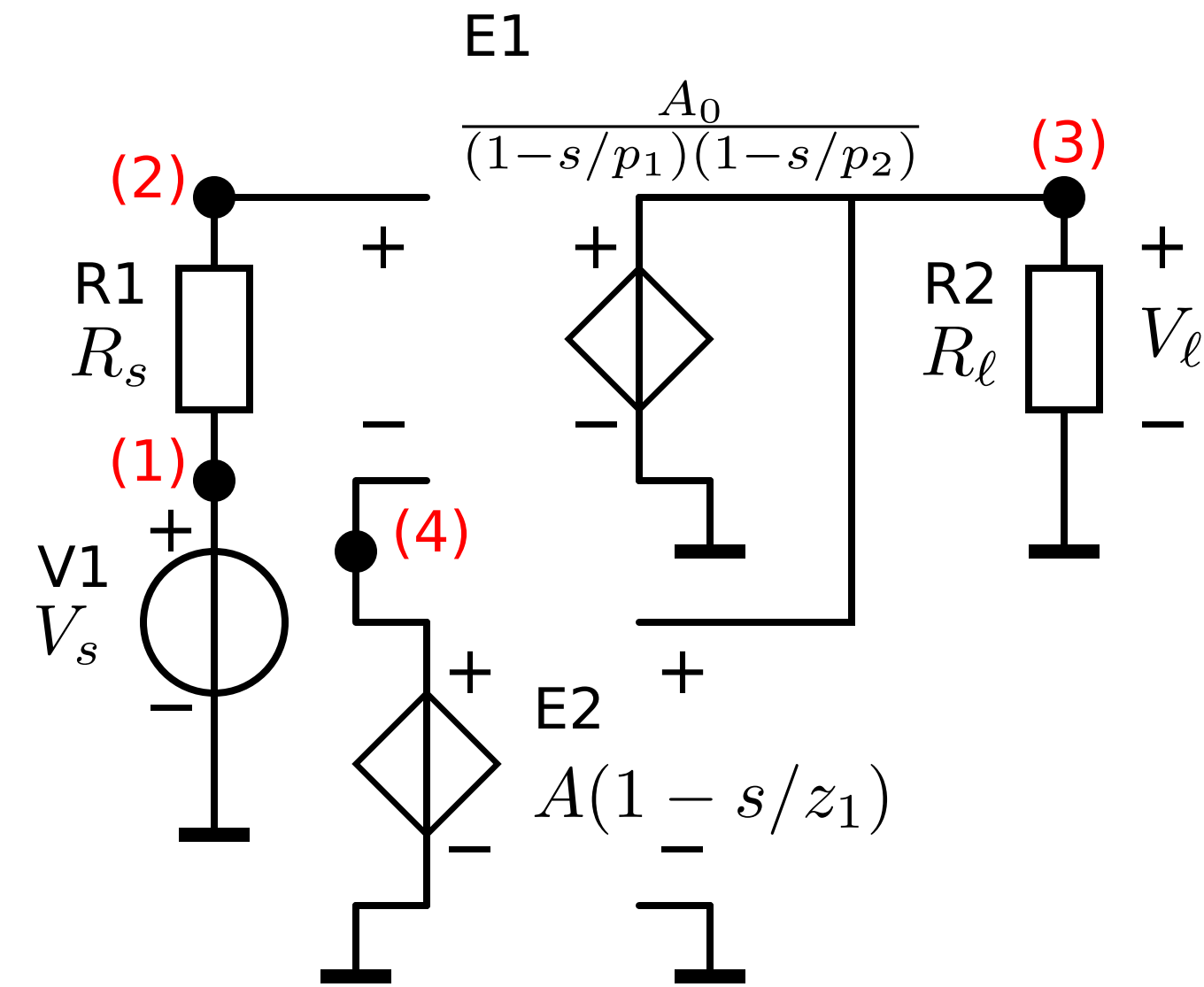
$$A = \frac{1}{100} \text{ [-]}.$$

$$f_h = \sqrt{1 \cdot 100 \cdot \frac{1}{100} \cdot 10^6} = 1000 \text{ [Hz]}$$

$$z = -\frac{10^6}{1000\sqrt{2}-101} = -761.49 \text{ [Hz]}$$

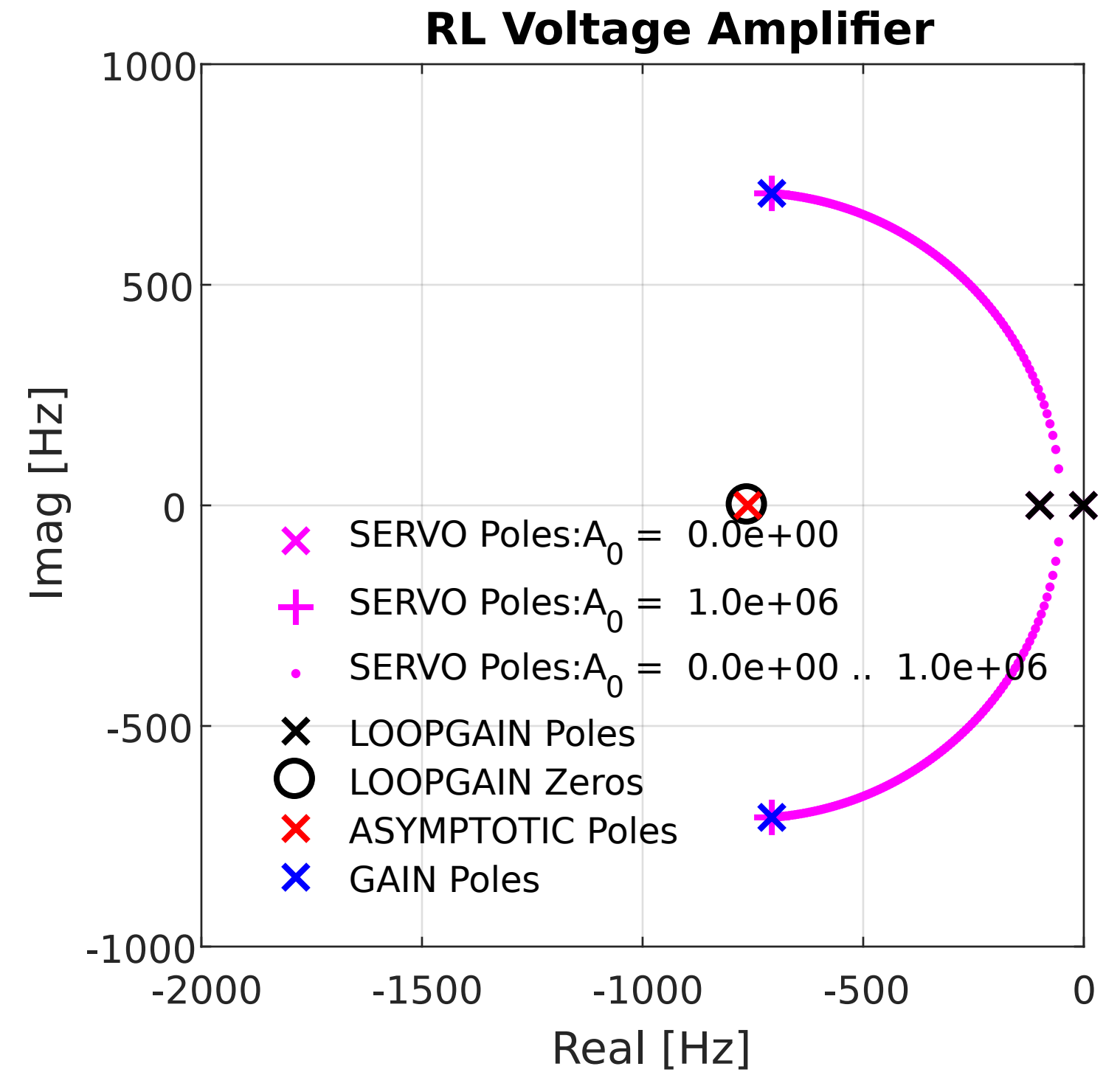
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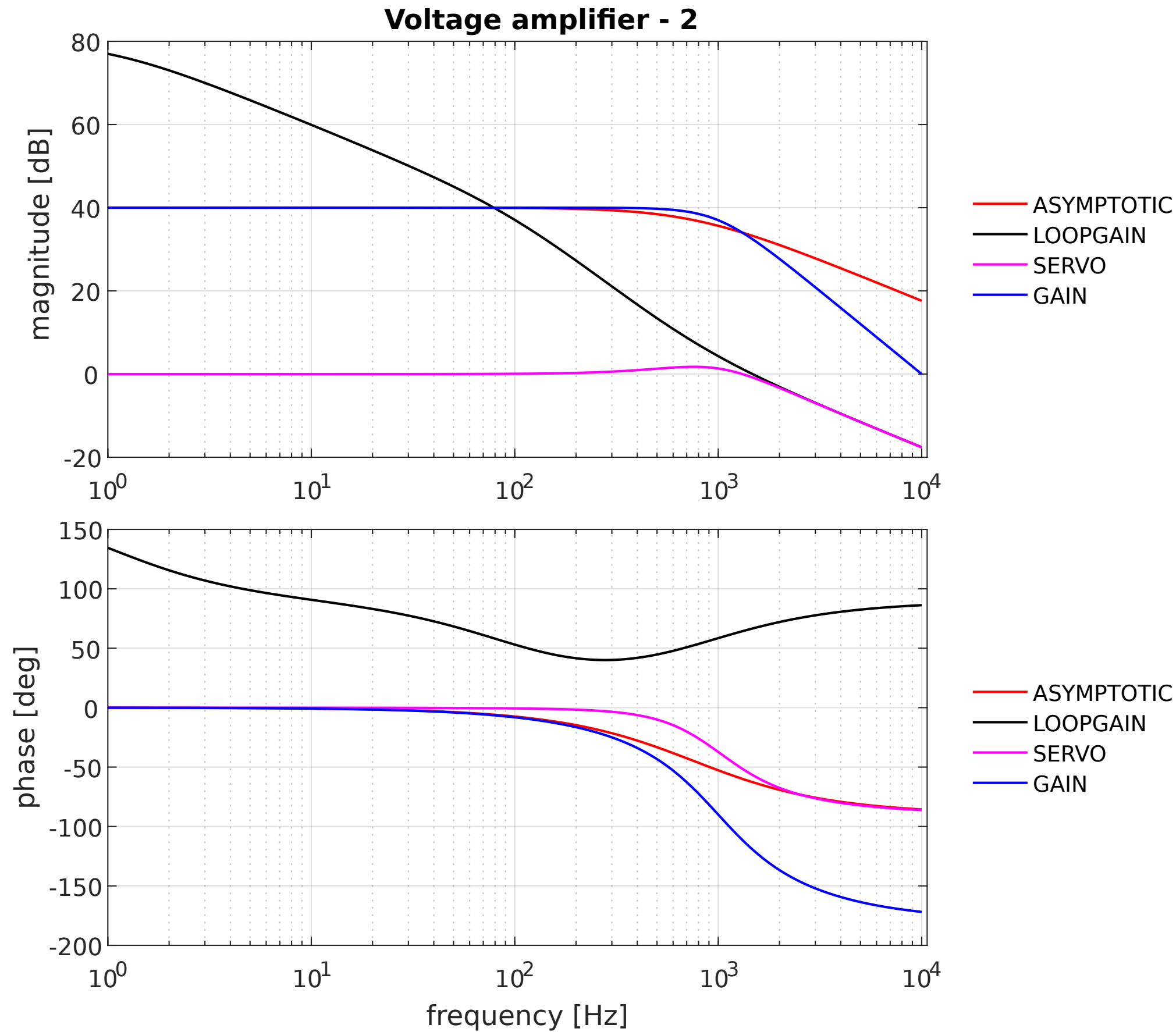
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Phantom compensation 2nd order system

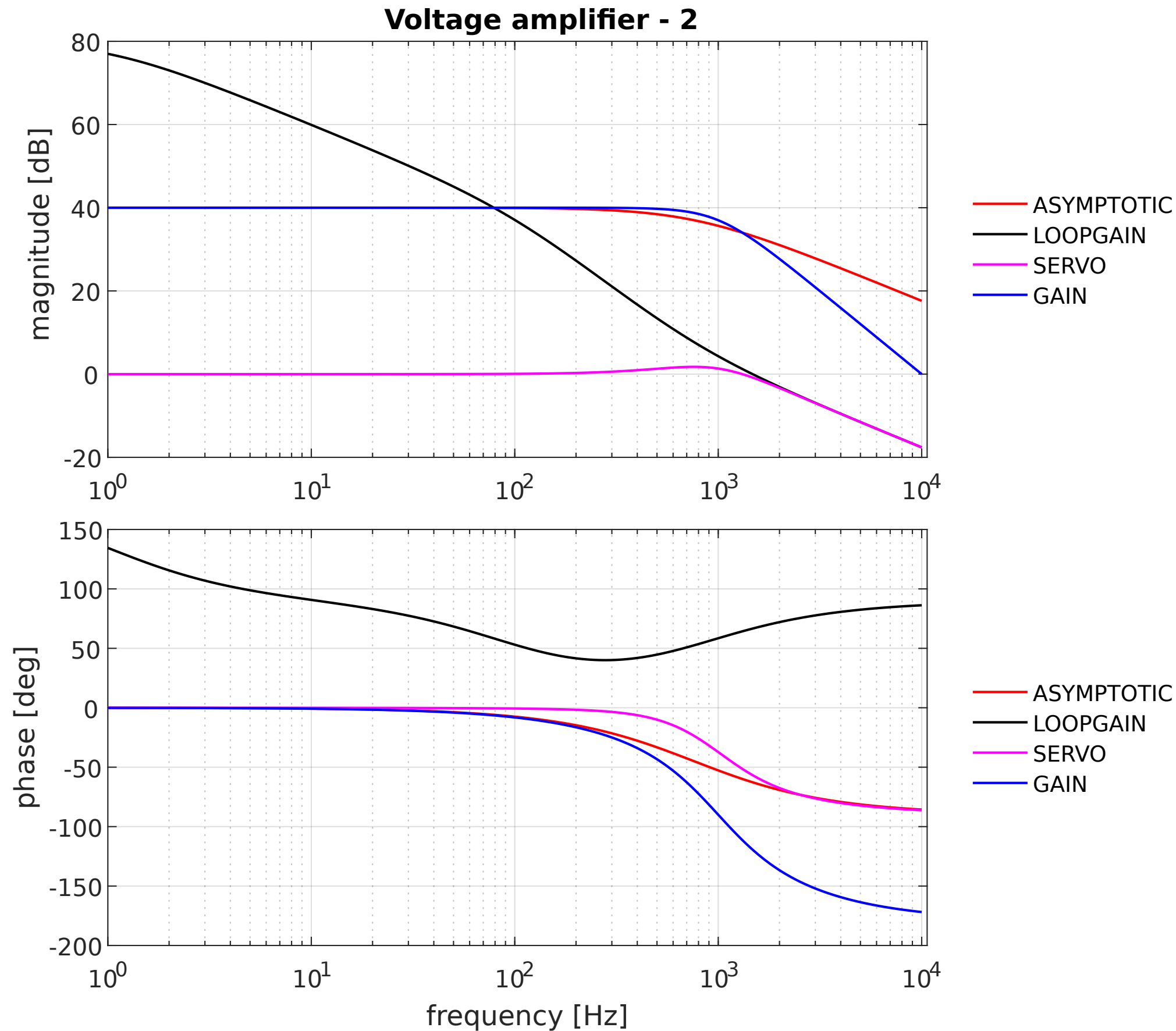
Example 12.2



Phantom compensation 2nd order system

Example 12.2

Phase margin:
67 degrees
at 1.5kHz



Phantom compensation 2nd order system

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at 1.5kHz

