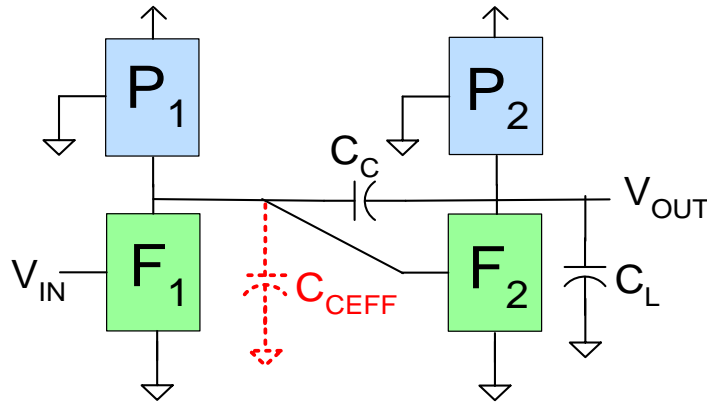


EE 435

Lecture 16

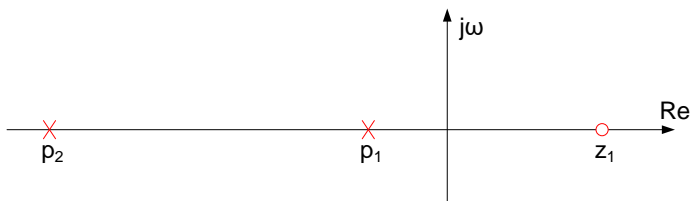
Compensation of Feedback Amplifiers

How does the Gain of the Two-Stage Miller-Compensated Op Amp Compare with Internal Compensated Op Amp?

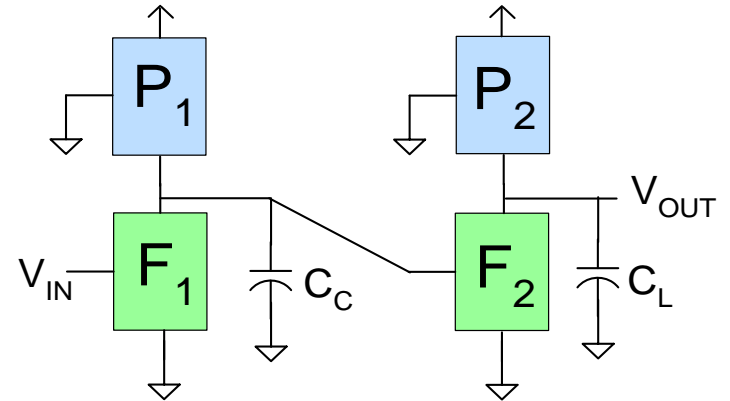


$$A(s) = \frac{g_{md}(g_{m0} - sC_C)}{s^2 C_C C_L + s g_{m0} C_C + g_{oo} g_{od}}$$

$$A(s) = A_0 \frac{\frac{s}{\tilde{z}_1} + 1}{\left(\frac{s}{\tilde{p}_1} + 1\right)\left(\frac{s}{\tilde{p}_2} + 1\right)}$$

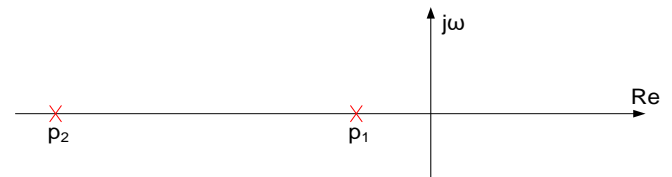


must be developed



$$A(s) \cong \frac{g_{md} g_{m0}}{s^2 C_C C_L + s C_C g_{oo} + g_{oo} g_{od}}$$

$$A(s) = A_0 \frac{1}{\left(\frac{s}{\tilde{p}_1} + 1\right)\left(\frac{s}{\tilde{p}_2} + 1\right)}$$



Compensation criteria:

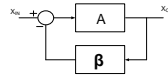
$$4\beta A_0 > \frac{p_2}{p_1} > 2\beta A_0$$

Feedback applications of the two-stage Op Amp

Open-loop Gain

$$A(s) = \frac{N(s)}{D(s)}$$

Standard Feedback Gain



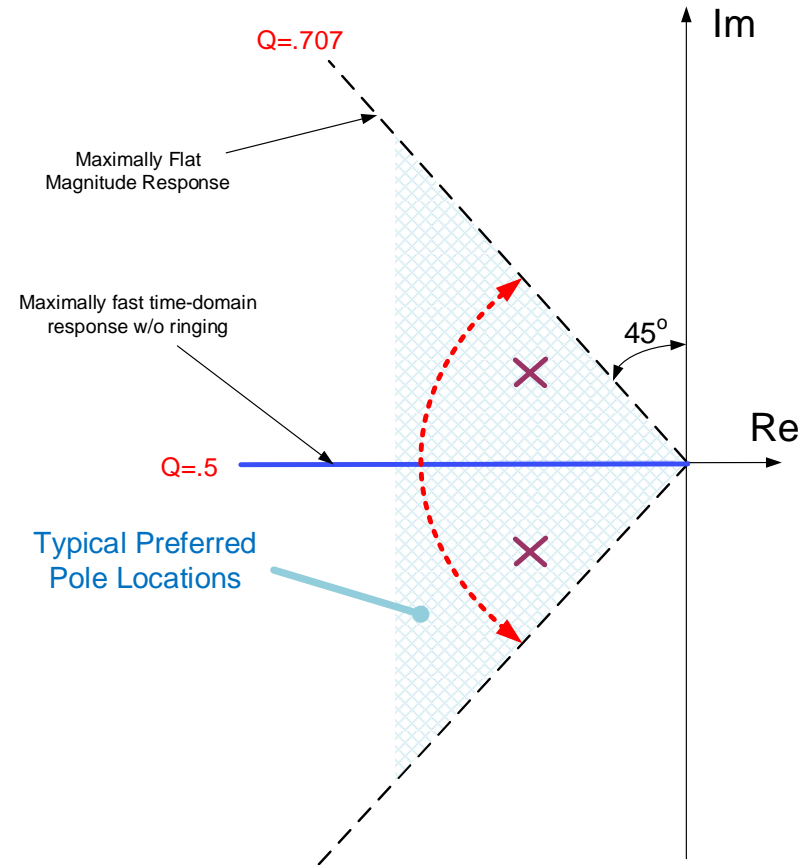
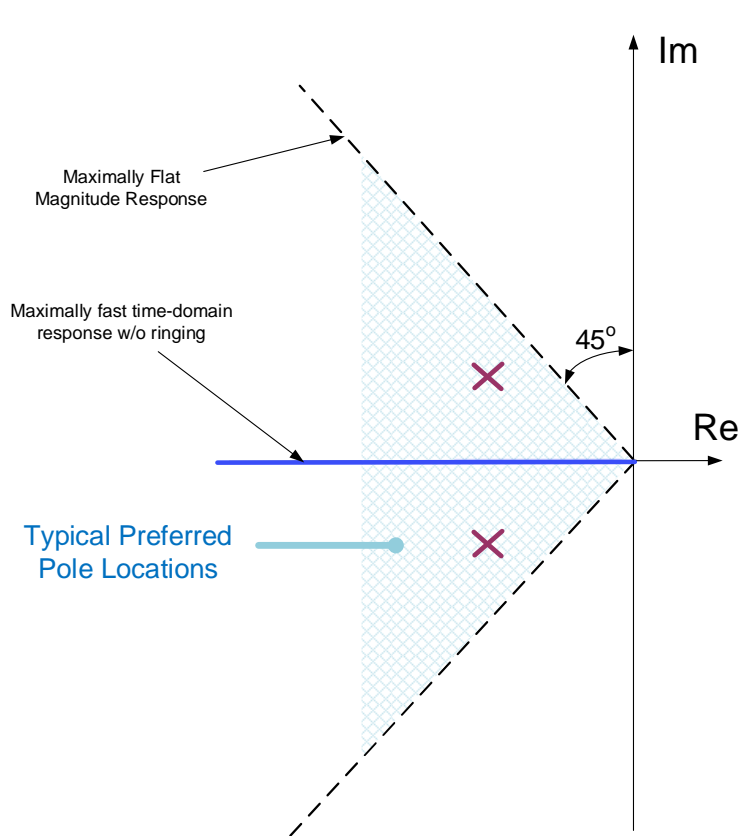
$$A_{FB}(s) = \frac{A(s)}{1 + A(s)\beta(s)} = \frac{N(s)}{D(s) + N(s)\beta(s)} \stackrel{\text{def n}}{=} \frac{N_{FB}(s)}{D_{FB}(s)}$$

$$N_{FB}(s) = N(s)$$

$$D_{FB}(s) = D(s) + \beta(s)N(s)$$

- Open-loop and closed-loop zeros identical
- Closed-loop poles different than open-loop poles
- Often $\beta(s)$ is not dependent upon frequency

What closed-loop pole Q is typically required when compensating an op amp?



Recall:

Typically compensate so closed-loop poles make angle between 45° and 90° from imaginary axis

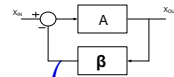
Equivalently:

$$0.5 < Q < .707$$

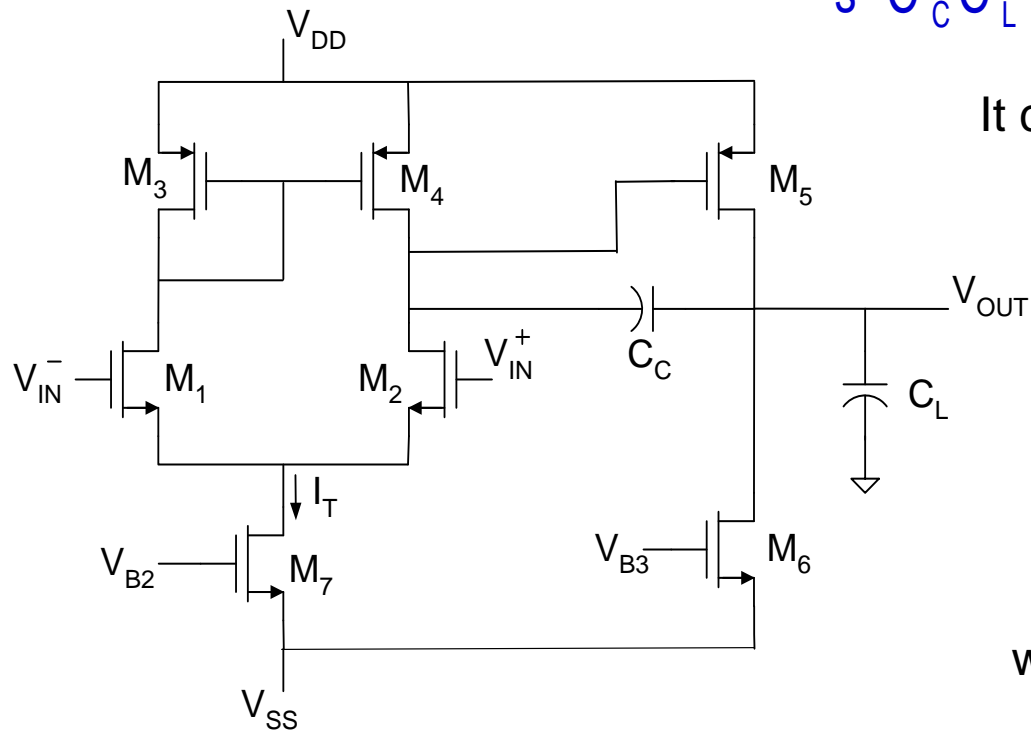
Basic Two-Stage Op Amp

(with Miller compensation)

Standard Feedback Gain



$$A_{FB}(s) \cong \frac{g_{md}(g_{m0} - sC_c)}{s^2 C_c C_L + s C_c (g_{m0} - \beta g_{md}) + \beta g_{md} g_{m0}}$$



It can be shown that

$$Q = \sqrt{\frac{C_L}{C_c}} \sqrt{\beta} \frac{\sqrt{g_{m0} g_{md}}}{g_{m0} - \beta g_{md}}$$

$$C_c = \frac{C_L \beta}{Q^2} \frac{g_{m0} g_{md}}{(g_{m0} - \beta g_{md})^2}$$

where $g_{md} = g_{m1}$ $g_{m0} = g_{m5}$

$g_{o0} = g_{o5} + g_{o6}$ and $g_{od} = g_{o2} + g_{o4}$

But what pole Q is desired? $.707 < Q < 0.5$

Right Half-Plane Zero in OL Gain (from Miller Compensation) Limits Performance

(because it increases the pole Q and thus requires a larger C_c !)

Closed-form expression for C_c !

Basic Two-Stage Op Amp with Feedback

(with Internal Node compensation)

Open-loop gain

$$A(s) = \frac{g_{m0}g_{md}}{s^2C_C C_L + sC_C g_{o0} + g_{o0}g_{od}}$$

$$A_{FB} = \frac{A}{1 + A\beta}$$

Standard feedback gain with constant β

$$A_{FB}(s) = \frac{g_{m0}g_{md}}{s^2C_C C_L + sC_C g_{o0} + g_{o0}g_{od} + \beta g_{m0}g_{md}}$$

$$A_{FB}(s) \cong \frac{g_{m0}g_{md}}{s^2C_C C_L + sC_C g_{o0} + \beta g_{m0}g_{md}}$$

where

$$g_{o0} = g_{o5} + g_{o6}$$

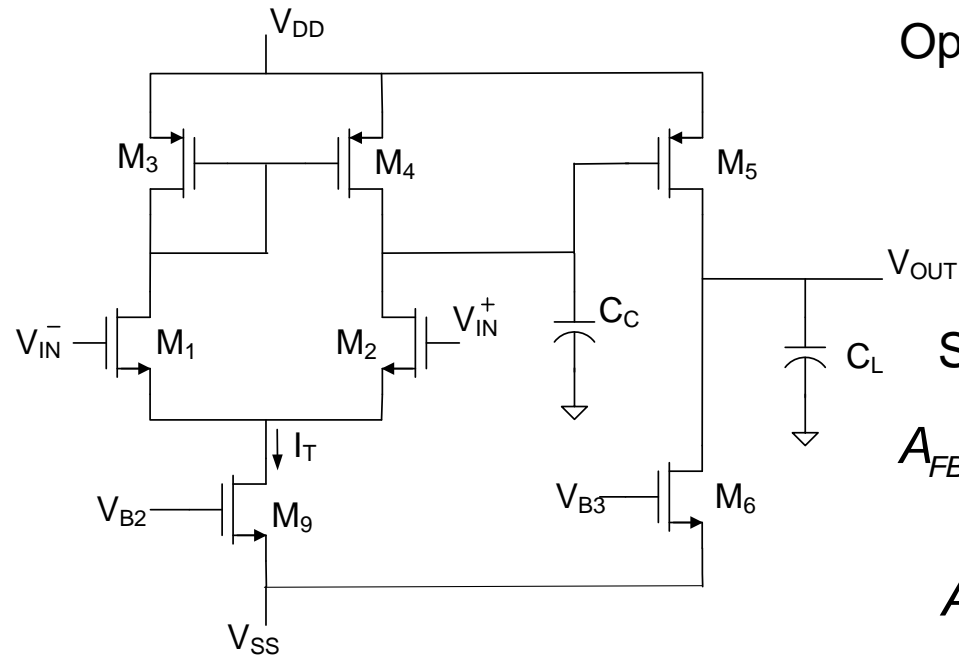
$$g_{m0} = g_{m5}$$

$$g_{od} = g_{o2} + g_{o4}$$

$$g_{md} = g_{m1}$$

OR

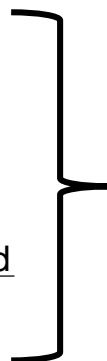
$$C_C = C_L \beta \frac{g_{m0}g_{md}}{Q^2 g_{o0}^2} = C_L \beta \frac{g_{m5}g_{m1}}{Q^2 (g_{o5} + g_{o6})^2}$$



$$4\beta A_0 > \frac{p_2}{p_1} > 2\beta A_0$$

$$p_2 = \frac{g_{o0}}{C_L} \quad p_1 = \frac{g_{od}}{C_C} \quad A_0 = \frac{g_{m0}g_{md}}{g_{o0}g_{od}}$$

$$C_L 4\beta \frac{g_{m0}g_{md}}{g_{o0}^2} > C_C > C_L 2\beta \frac{g_{m0}g_{md}}{g_{o0}^2}$$



Status on Compensation

Generally not needed for single-stage op amps

Analytical expressions were developed with $A_{FB} = \frac{A}{1 + A\beta}$ for

Two-stage with internal node compensation (no OL zeros)

Two-stage with load compensation (no OL zeros)

Two-stage with basic Miller compensation (OL zero, single series comp cap)

Will now develop a more general compensation strategy

Compensation

What is “compensation” or “frequency compensation”?

From Wikipedia: In [electrical engineering](#), **frequency compensation** is a technique used in [amplifiers](#), and especially in amplifiers employing negative feedback. It usually has two primary goals: To avoid the unintentional creation of [positive feedback](#), which will cause the amplifier to [oscillate](#), and to control [overshoot](#) and [ringing](#) in the amplifier's [step response](#).

From Martin and Johns – no specific definition but makes comparisons with “optimal compensation” which also is not defined

From Allen and Holberg (p 243) The goal of compensation is to maintain stability when negative feedback is applied around the op amp.

Compensation

From Gray and Meyer (p634) Thus if this amplifier is to be used in a feedback loop with loop gain larger than $a_0 f_1$, efforts must be made to increase the phase margin. This process is known as compensation.

From Sedra and Smith (p 90) This process of modifying the open-loop gain is termed frequency compensation, and its purpose is to ensure that op-amp circuits will be stable (as opposed to oscillatory).

From Razavi (p355) Typical op amp circuit contain many poles. In a folded-cascode topology, for example, both the folding node and the output node contribute poles. For this reason, op amps must usually be “compensated”, that is, their open-loop transfer function must be modified such that the closed-loop circuit is stable and the time response is well-behaved.

Compensation

What is “compensation” or “frequency compensation” and what is the goal of compensation?

Nobody defines it or defines it correctly but everybody tries to do it !

Compensation

Compensation (alt Frequency Compensation) is the manipulation of the poles and/or zeros of the open-loop amplifier so that when feedback is applied, the closed-loop amplifier will perform acceptably

Note this definition does not mention stability, positive feedback, negative feedback, phase margin, or oscillation.

Note that acceptable performance is strictly determined by the user in the context of the specific application

Compensation (better definition)

Compensation (alt Frequency Compensation) is the manipulation of the poles and/or zeros of the open-loop amplifier so that when feedback is applied, the closed-loop ~~amplifier~~ will perform acceptably.
circuit

Note this definition does not mention stability, positive feedback, negative feedback, phase margin, or oscillation.

Note that acceptable performance is strictly determined by the user in the context of the specific application

Note this covers linear applications of op amps beyond just finite-gain amplifiers

Approach to Studying Compensation

Will attempt to develop a correct understanding of the concept of compensation rather than plunge into a procedure for “doing compensation”

Compensation requires the use of some classical mathematical concepts

Compensation

Compensation is the manipulation of the poles and/or zeros of the open-loop amplifier so that when feedback is applied, the closed-loop circuit will perform acceptably

Acceptable performance is often application dependent and somewhat interpretation dependent

Acceptable performance should include affects of process and temperature variations

Although some think of compensation as a method of maintaining stability with feedback, acceptable performance generally dictates much more stringent performance than simply stability

Compensation criteria are often an indirect indicator of some type of desired (but unstated) performance

Varying approaches and criteria are used for compensation often resulting in similar but not identical performance

Over compensation often comes at a considerable expense (increased power, decreased frequency response, increased area, ...)

Compensation

Compensation requirements usually determined by closed-loop pole locations:

$$D_{FB}(s) = D(s) + \beta(s)N(s)$$

- Often Phase Margin or Gain Margin criteria are used instead of pole Q criteria when compensating amplifiers
(for historical reasons but must still be conversant with this approach)
- Nyquist plots are an alternative stability criteria that is used some in the design of amplifiers
- Phase Margin and Gain Margin criteria are directly related to the Nyquist Plots
- Compensation requirements are strongly β dependent

Characteristic Polynomial obtained from denominator term of basic feedback equation

$$D_{FB}(s) = 1 + A(s)\beta(s)$$

$$A(s)\beta(s)$$

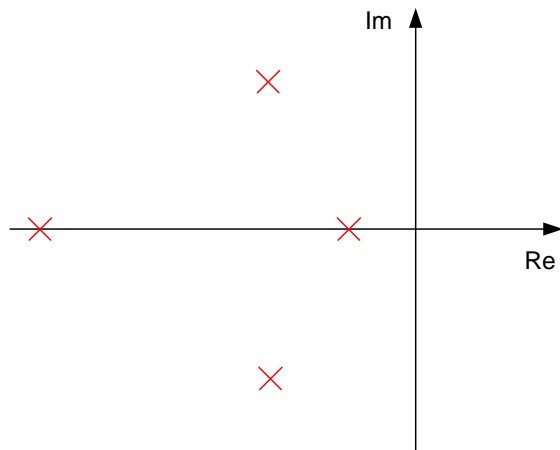
defined to be the “loop gain” of a feedback amplifier

Review of Basic Concepts

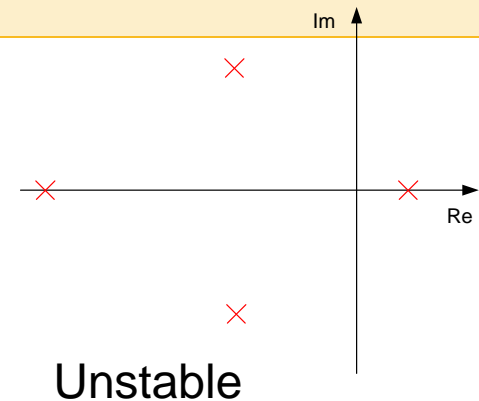
Pole Locations and Stability

$$D_{\text{FB}}(s) = 1 + A(s)\beta(s)$$

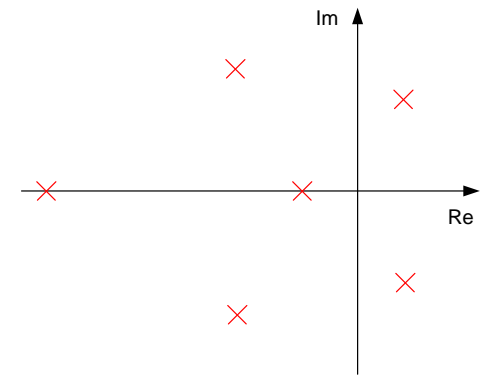
Theorem: A system is stable iff all closed-loop poles lie in the open left half-plane.



Stable



Unstable



Unstable

Review of Basic Concepts (from last lecture)

Consider a second-order factor of a denominator polynomial, $P(s)$, expressed in integer-monic form

$$P(s) = s^2 + a_1s + a_0$$

Then $P(s)$ can be expressed in several alternative but equivalent ways

$$(s - p_1)(s - p_2)$$

if complex conjugate poles or real axis poles of same sign

$$s^2 + s \frac{\omega_0}{Q} + \omega_0^2$$

$$s^2 + s2\zeta\omega_0 + \omega_0^2$$

if real – axis poles

$$(s - p_1)(s - kp_1)$$

and if complex conjugate poles,

$$(s + \alpha + j\beta)(s + \alpha - j\beta)$$

$$(s + re^{j\theta})(s + re^{-j\theta})$$

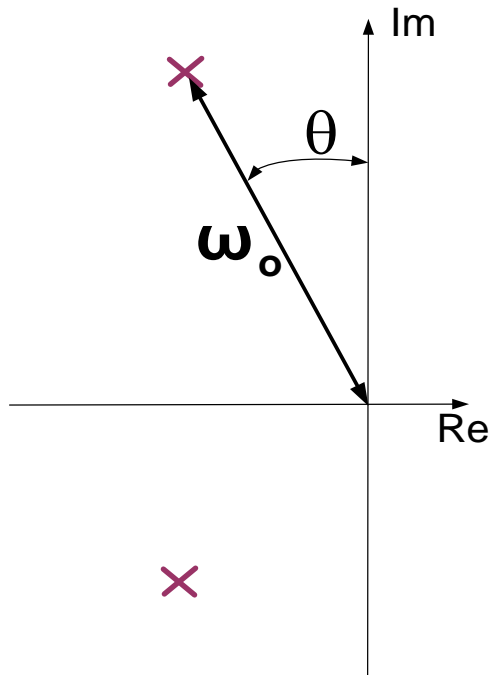
Widely used alternate parameter sets:

$$\{ (a_1, a_2) (\omega_0, Q) (\omega_0, \zeta) (p_1, p_2) (p_1, k) (\alpha, \beta) (r, \theta) \}$$

These are all 2-parameter characterizations of the second-order factor and it is easy to map from any one characterization to any other

Review of Basic Concepts (from last lecture)

$$s^2 + s \frac{\omega_0}{Q} + \omega_0^2$$



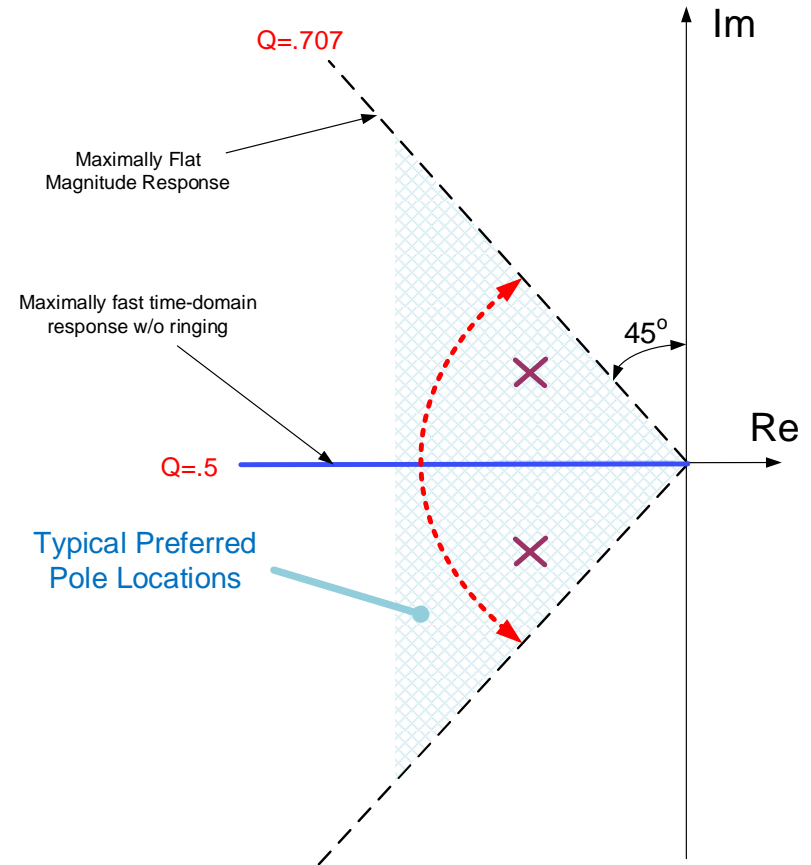
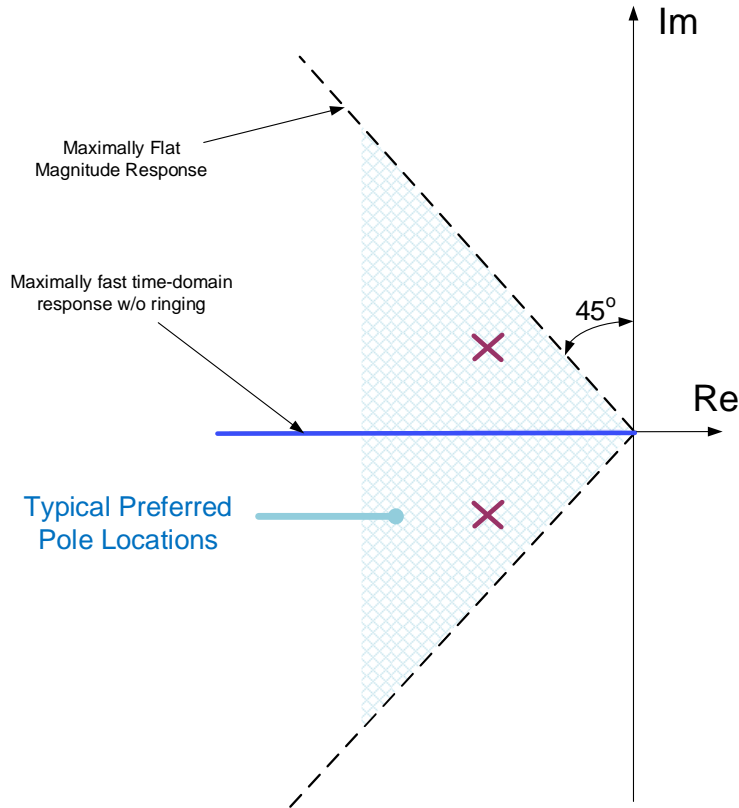
$$\sin\theta = \frac{1}{2Q}$$

ω_0 = magnitude of pole
Q determines the angle of the pole

Observe: Q=0.5 corresponds to two identical real-axis poles
Q=.707 corresponds to poles making 45° angle with Im axis

What closed-loop pole Q is typically required when compensating an op amp?

Review of Basic Concepts (from last lecture)



Recall:

Typically compensate so closed-loop poles make angle between 45° and 90° from imaginary axis

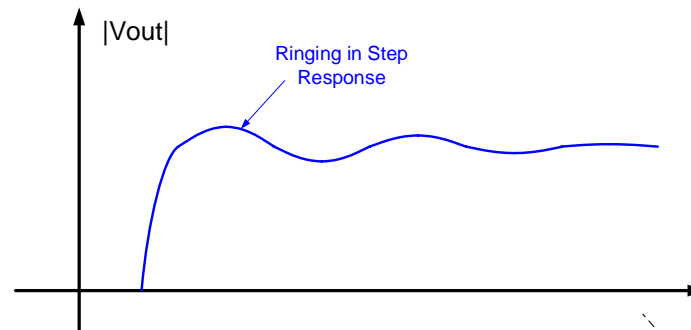
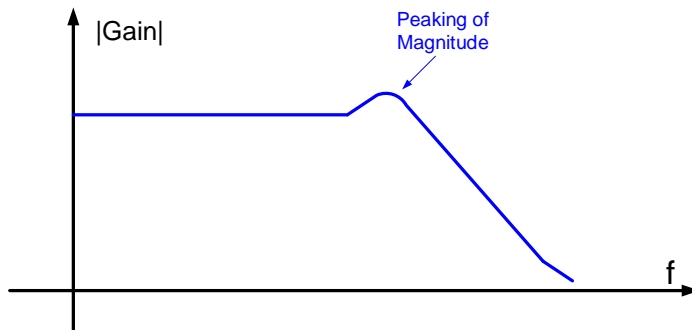
Equivalently:

$$0.5 < Q < .707$$

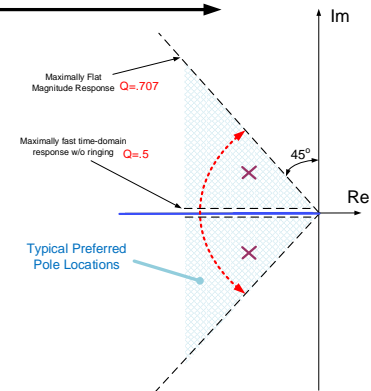
Pole Locations and Stability

Theorem: A system is stable iff all closed-loop poles lie in the open left half-plane.

Note: When designing finite-gain amplifiers with feedback, want to avoid having closed-loop amplifier poles close to the imaginary axis to provide reasonable “stability margin” (i.e. to minimize ringing in the time-domain and/or to minimize peaking in the frequency domain).



45° pole-pair angle corresponds to $Q = \frac{1}{\sqrt{2}}$
 90° pole angle (on pole pair) corresponds to $Q = \frac{1}{2}$



Nyquist Plots

$$D_{\text{FB}}(s) = 1 + A(s)\beta(s)$$

The Nyquist Plot is a plot of the Loop Gain ($A\beta$) versus $j\omega$ in the complex plane for $-\infty < \omega < \infty$

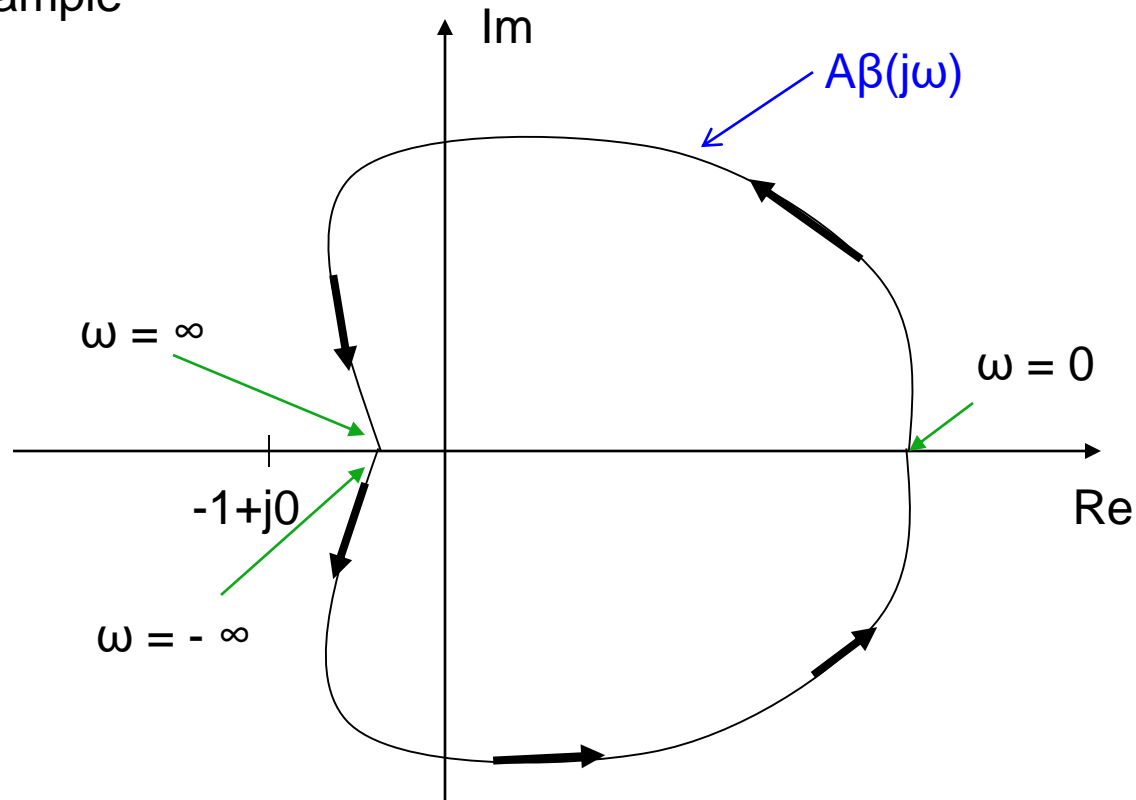
Theorem: A system is stable iff the Nyquist Plot does not encircle the point $-1+j0$.

Note: If there are multiple crossings of the real axis by the Nyquist Plot, the term encirclement requires a formal definition that will not be presented here

Nyquist Plots

$$D_{\text{FB}}(s) = 1 + A(s)\beta(s)$$

Example



- Stable since $-1+j0$ is not encircled
- Useful for determining stability when few computational tools are available
- Legacy of engineers and mathematicians of pre-computer era

Review of Basic Concepts

Nyquist Plots

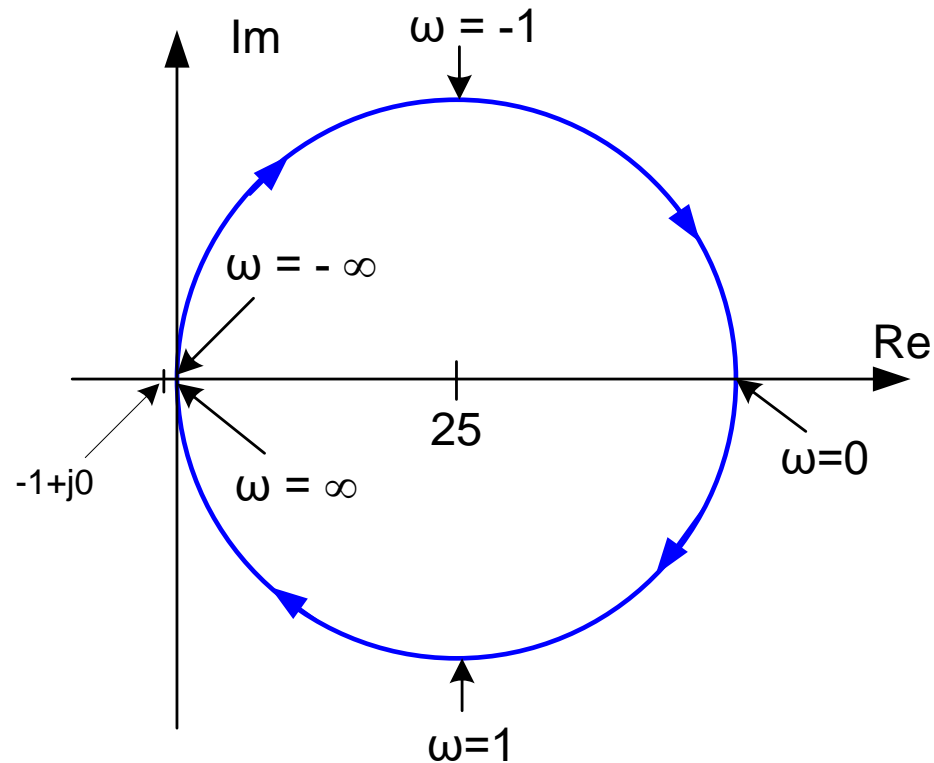
$$D_{\text{FB}}(s) = 1 + A(s)\beta(s)$$

Example

$$A(s) = \frac{100}{s+1}$$

$$\beta = 1/2$$

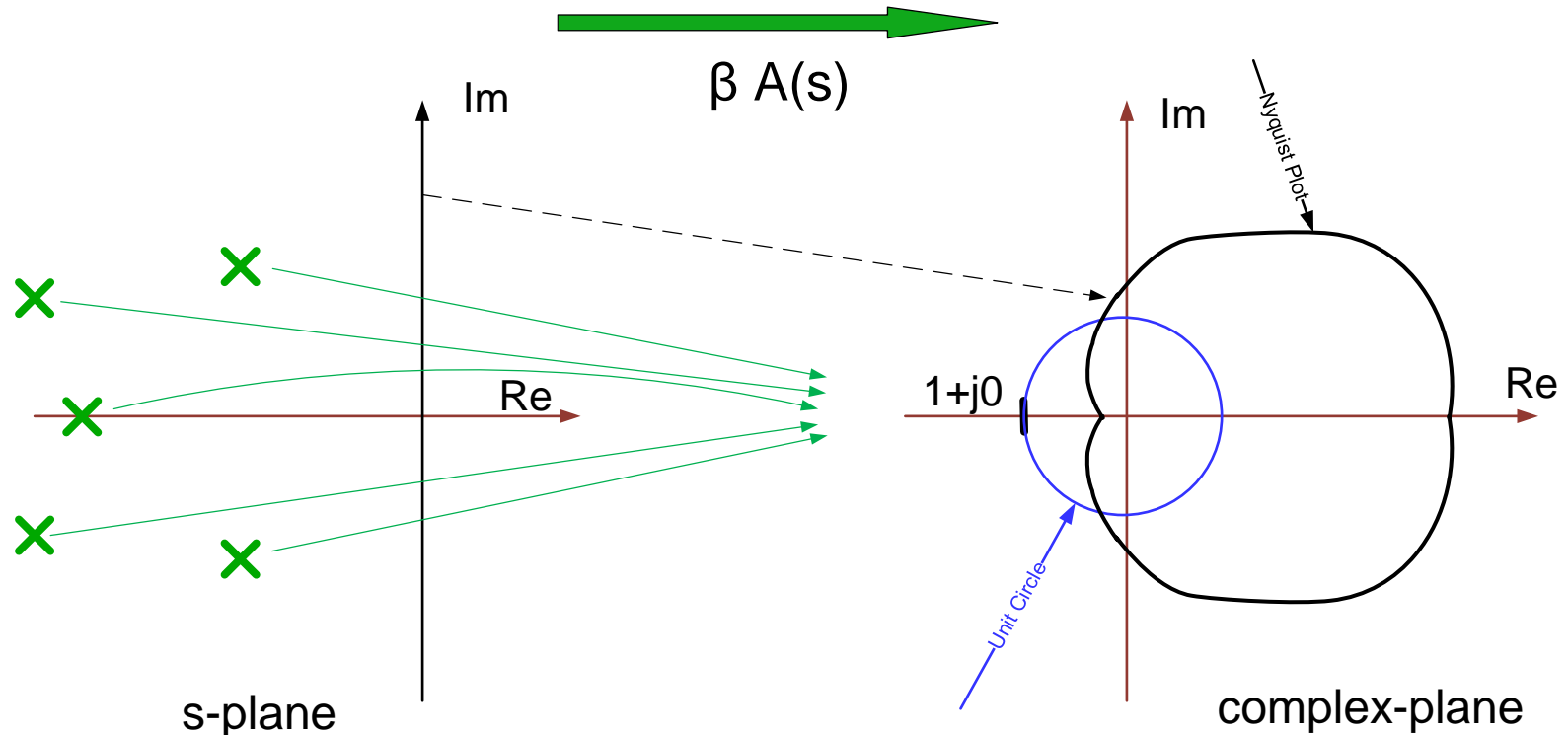
$$A\beta(j\omega) = \frac{50}{j\omega+1}$$



In this example, Nyquist plot is circle of radius 25

Nyquist Plots

$$D_{FB}(s) = 1 + A(s)\beta(s)$$



$-1+j0$ is the image of ALL poles

The Nyquist Plot is the image of the entire imaginary axis and separates the image complex plane into two parts

Everything outside of the Nyquist Plot is the image of the LHP

Nyquist plot can be generated with pencil and paper

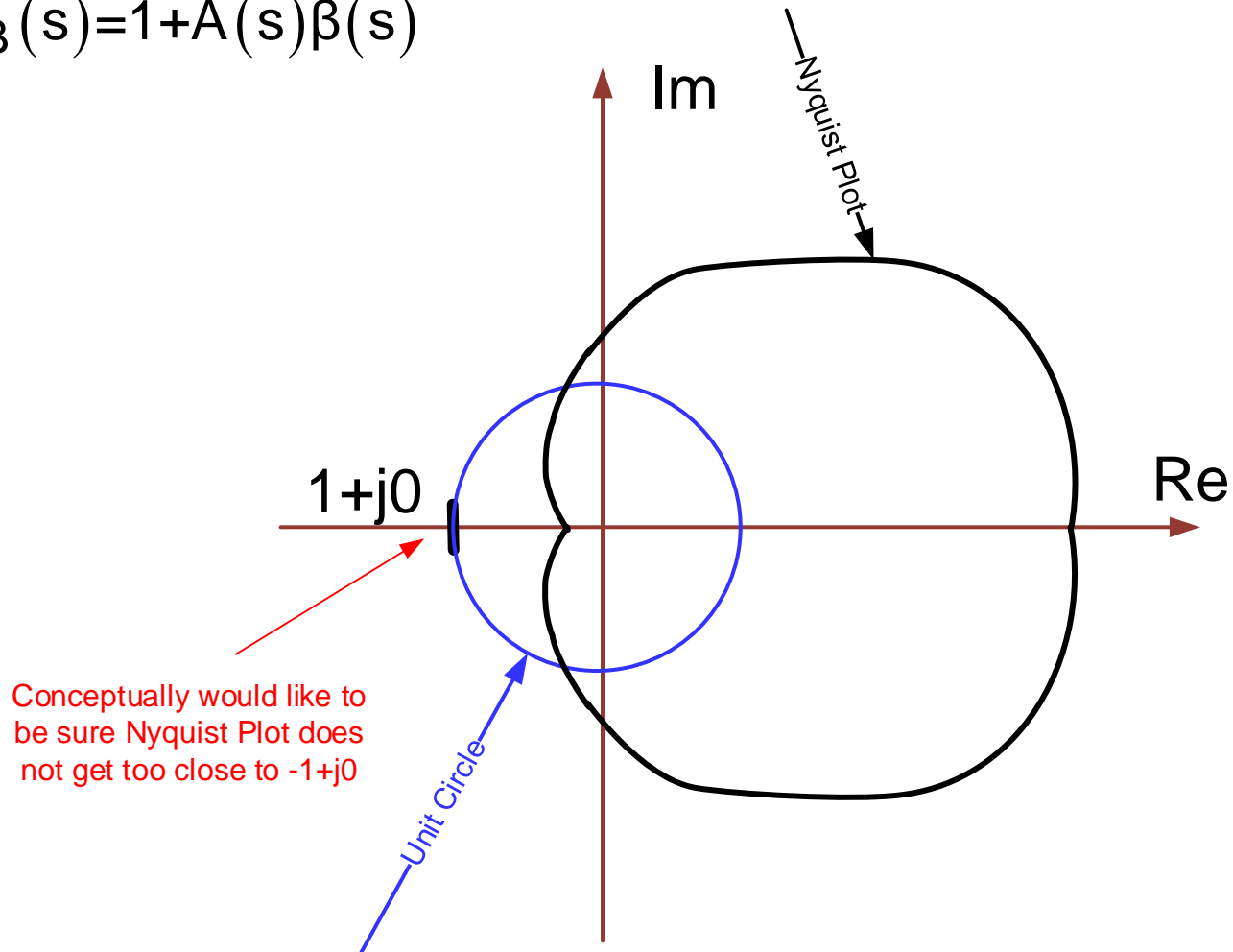


Important in the '30s - '60's

Review of Basic Concepts

Nyquist Plots

$$D_{\text{FB}}(s) = 1 + A(s)\beta(s)$$

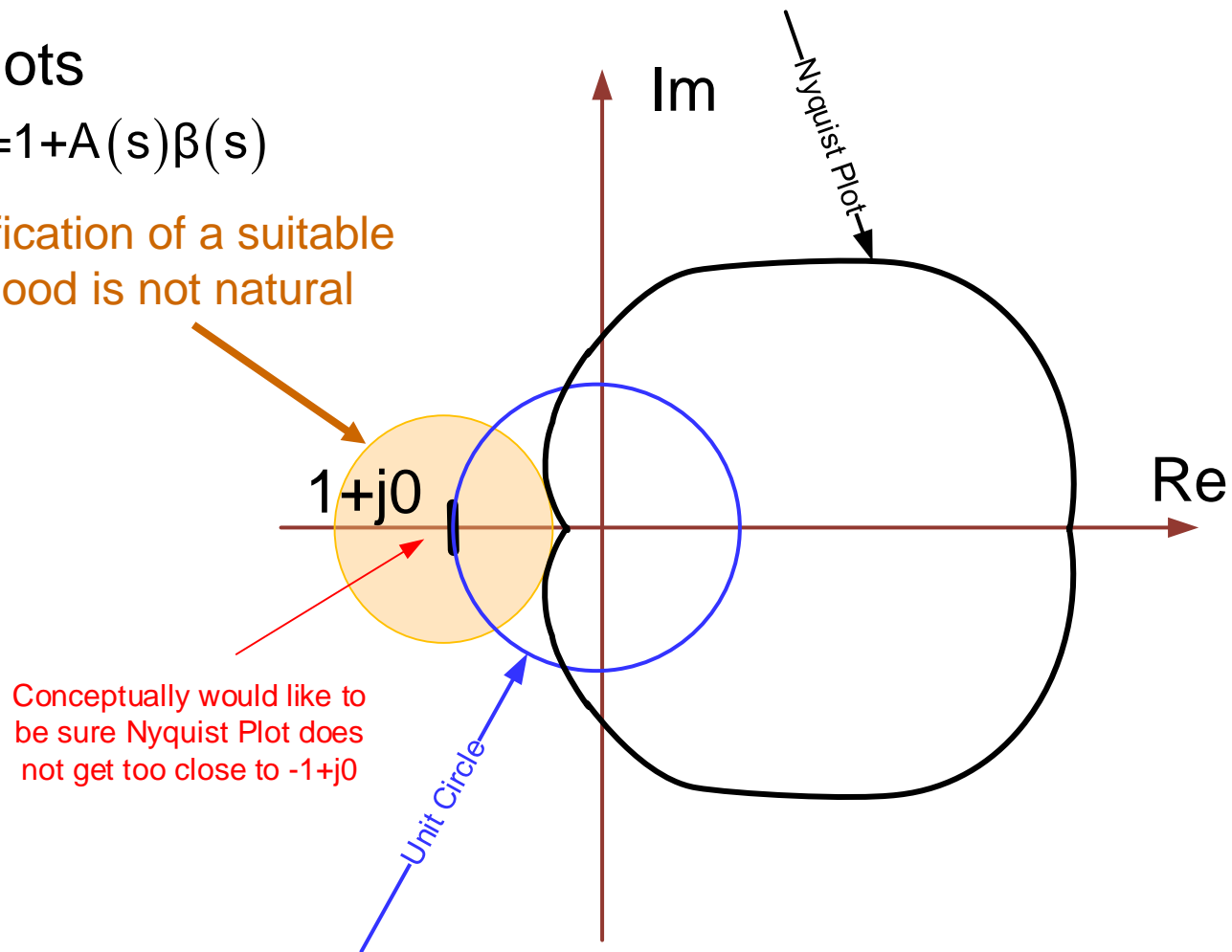


Review of Basic Concepts

Nyquist Plots

$$D_{FB}(s) = 1 + A(s)\beta(s)$$

But identification of a suitable neighborhood is not natural



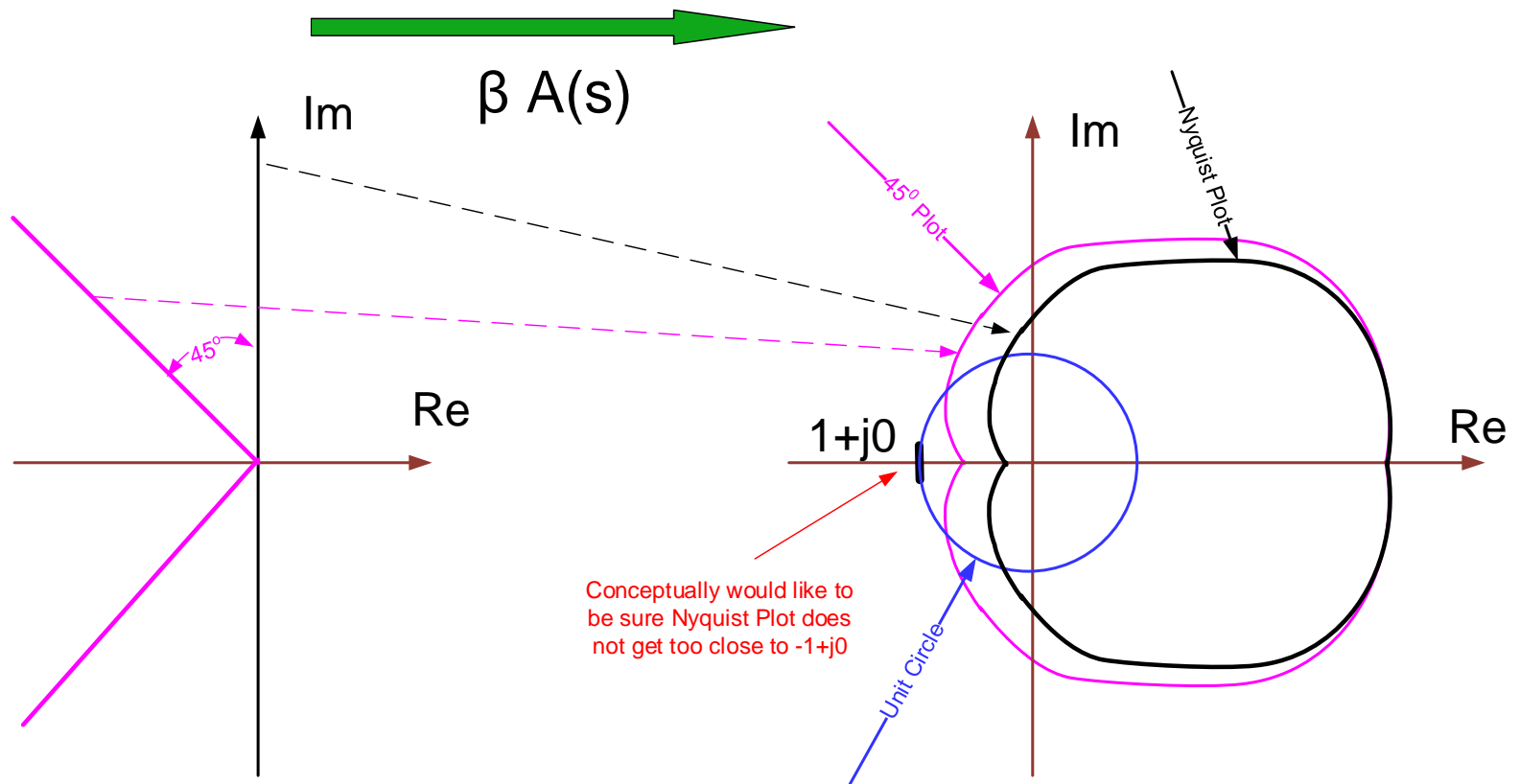
Conceptually would like to be sure Nyquist Plot does not get too close to $-1+j0$

Unit Circle

Review of Basic Concepts

Nyquist Plots

Might be useful to be sure image of 45° lines do not encircle $-1+j0$

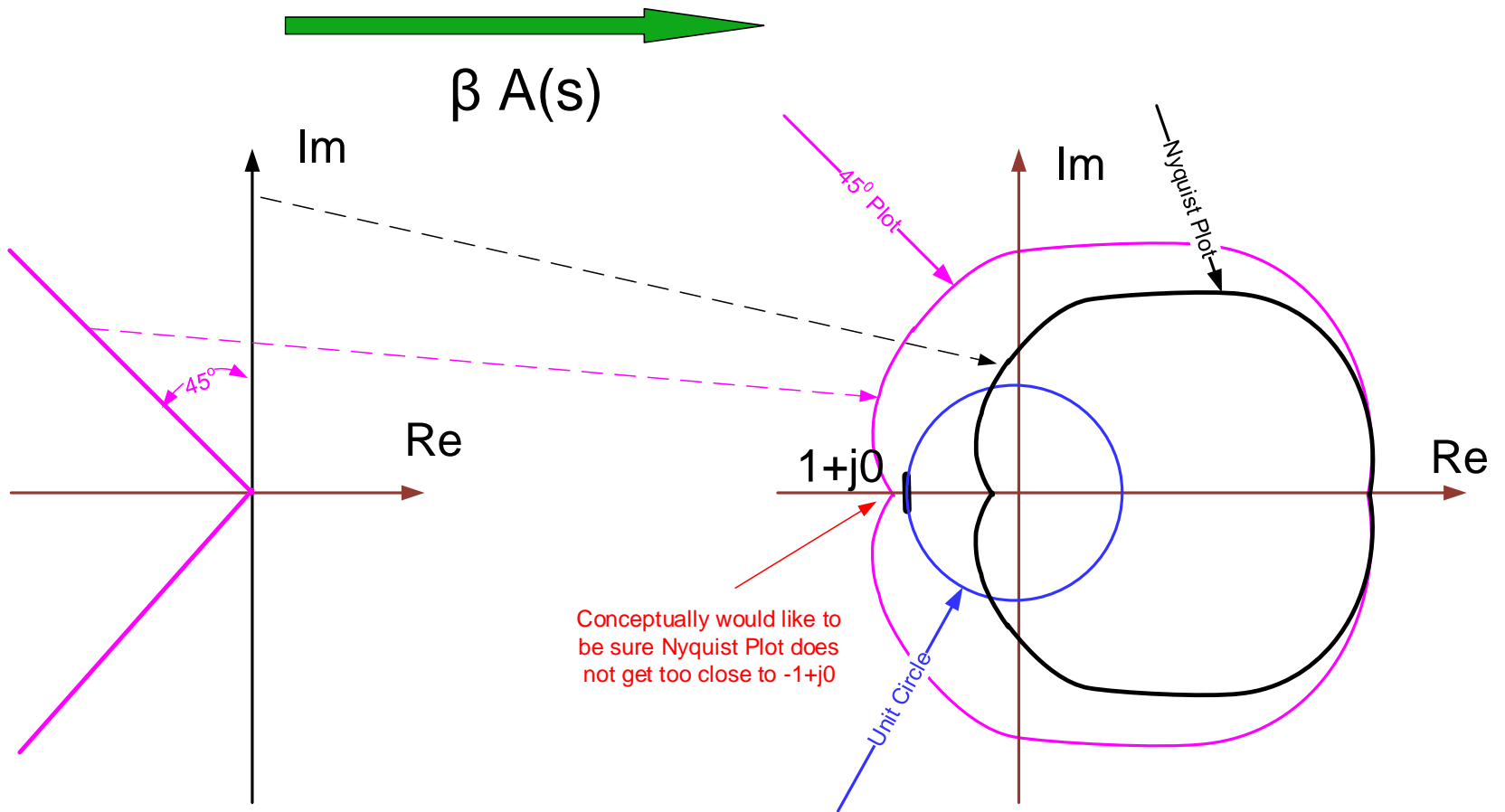


Review of Basic Concepts

Nyquist Plots

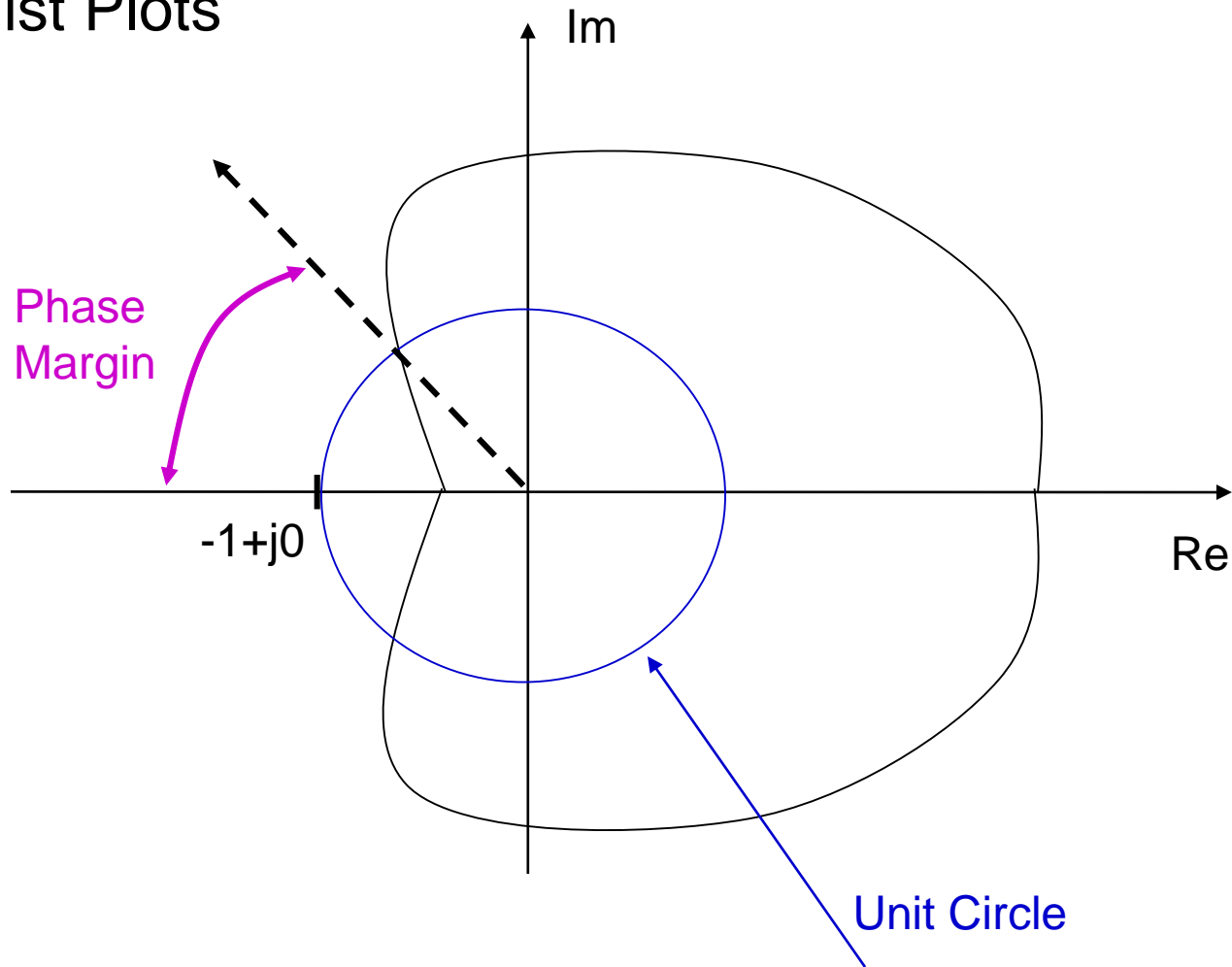
What if this happened ?

At least one pole would make an angle of less than 45° wrt Im axis



Review of Basic Concepts

Nyquist Plots

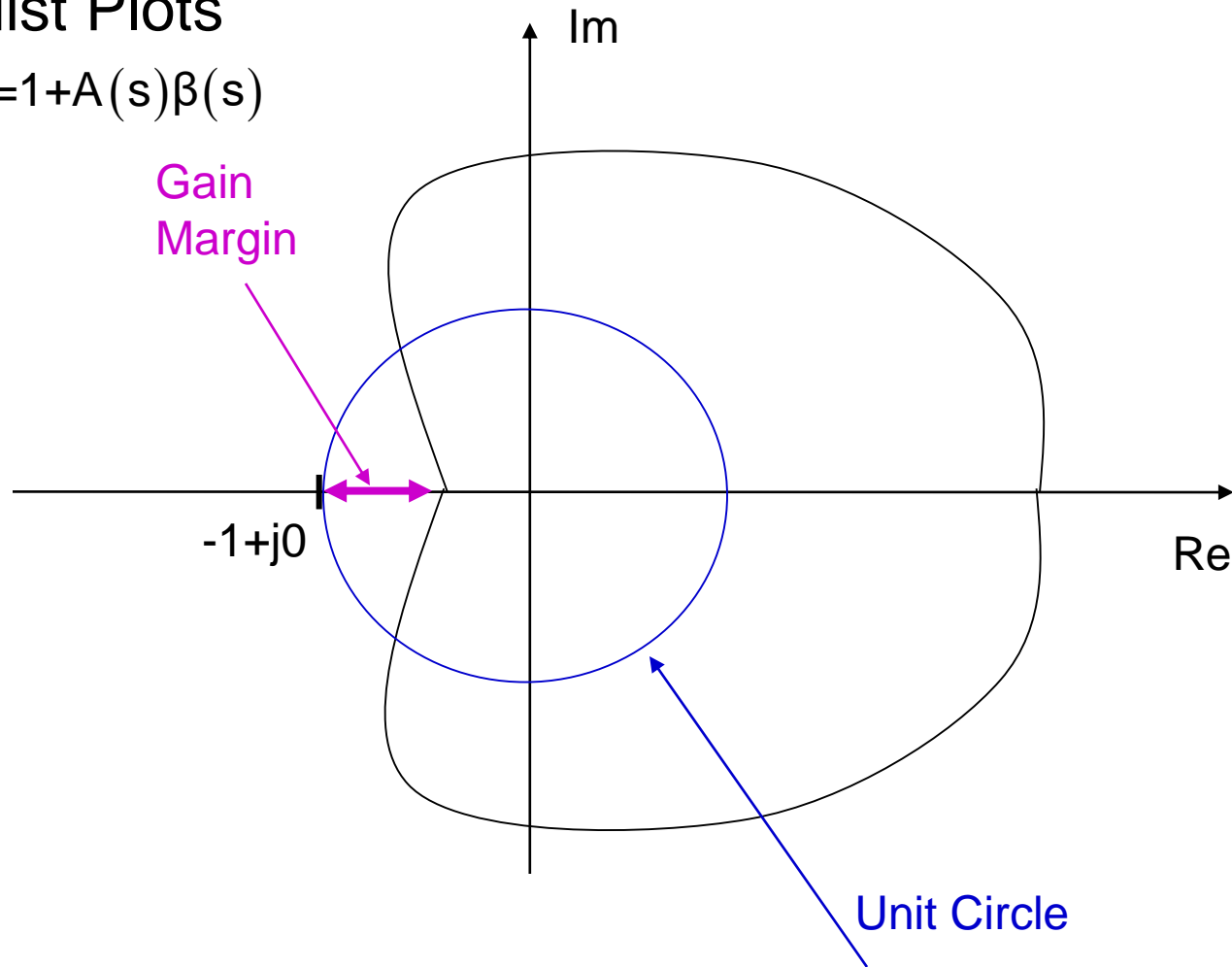


Phase margin is $180^\circ - \text{angle of } A\beta \text{ when the magnitude of } A\beta = 1$

Review of Basic Concepts

Nyquist Plots

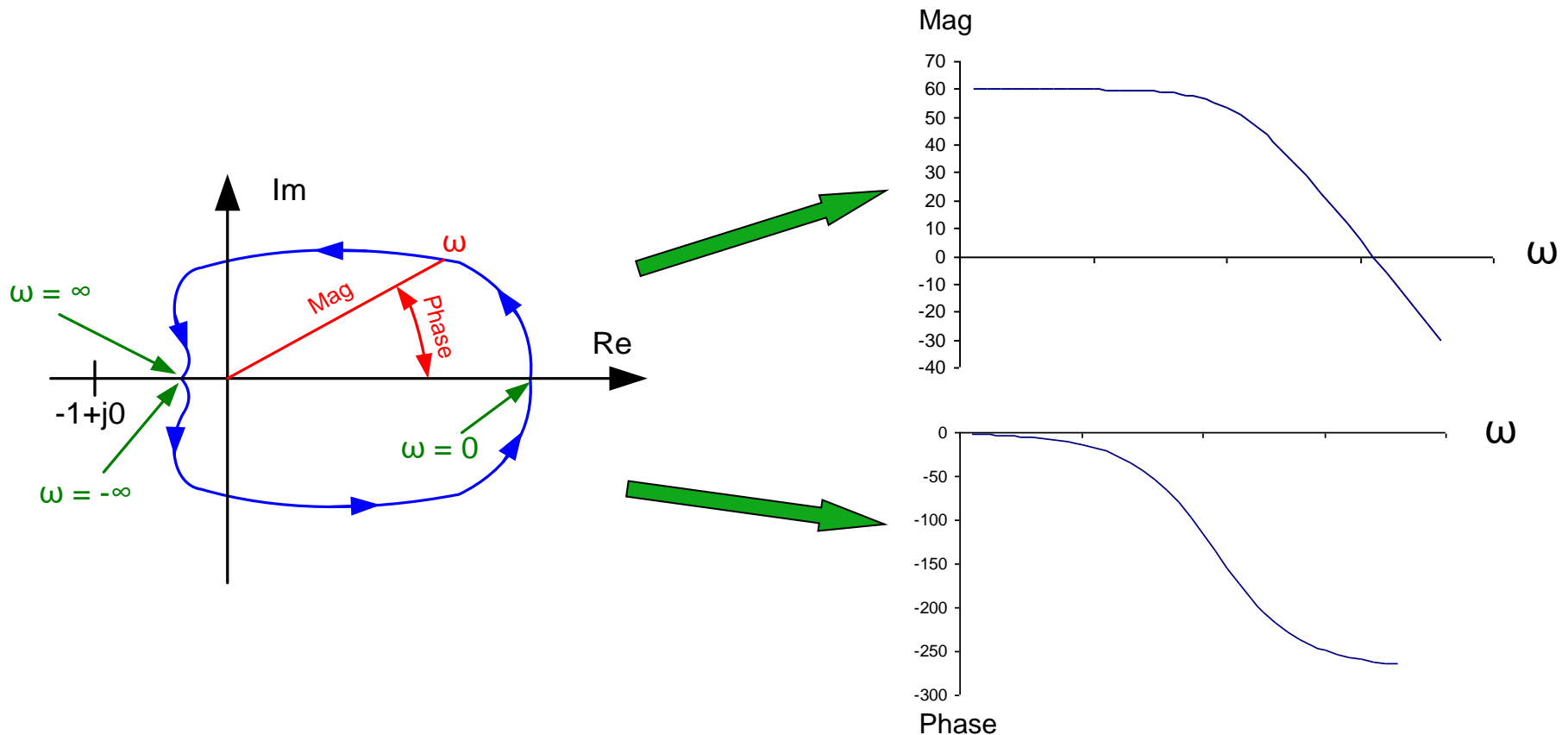
$$D_{FB}(s) = 1 + A(s)\beta(s)$$



Gain margin is $1 - \text{magnitude of } A\beta$ when the angle of $A\beta = 180^\circ$

Nyquist and Gain-Phase Plots

Nyquist and Gain-Phase Plots convey identical information but gain-phase plots often easier to work with

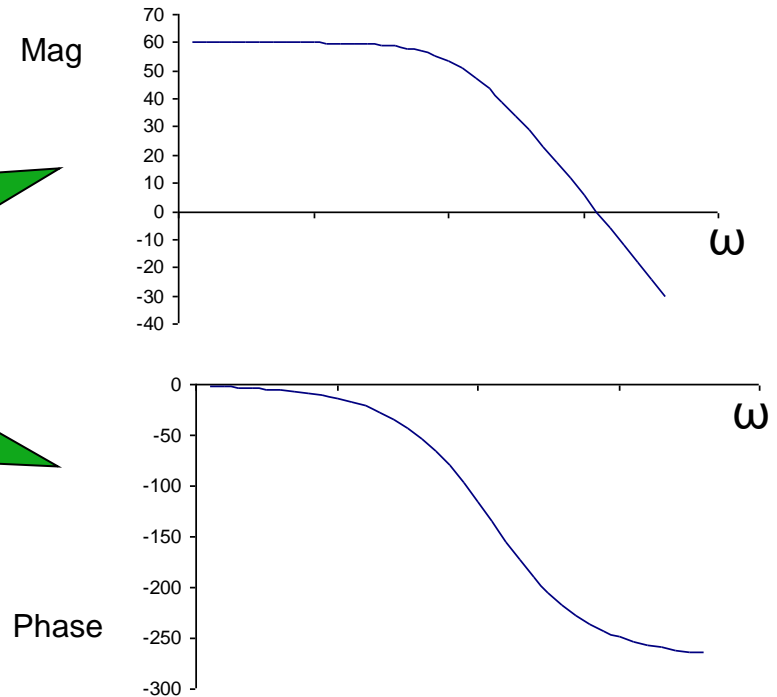
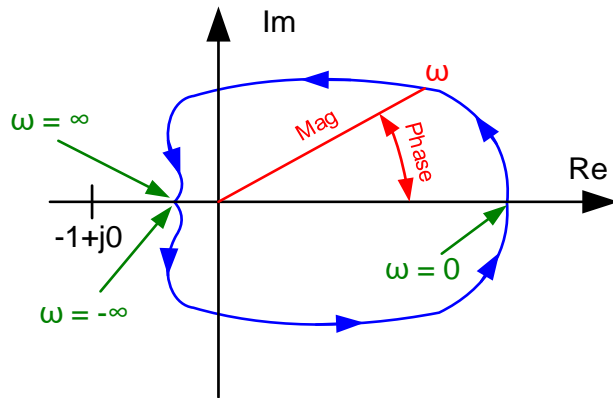


Note: The two plots do not correspond to the same system in this slide

Nyquist and Gain-Phase Plots

Nyquist and Gain-Phase Plots convey **identical** information but gain-phase plots often easier to work with

$$D_{FB}(s) = 1 + A(s)\beta(s)$$



$A\beta$ plots change with different values of β
Often β is independent of frequency

in this case $A\beta$ plot is just a shifted version of A

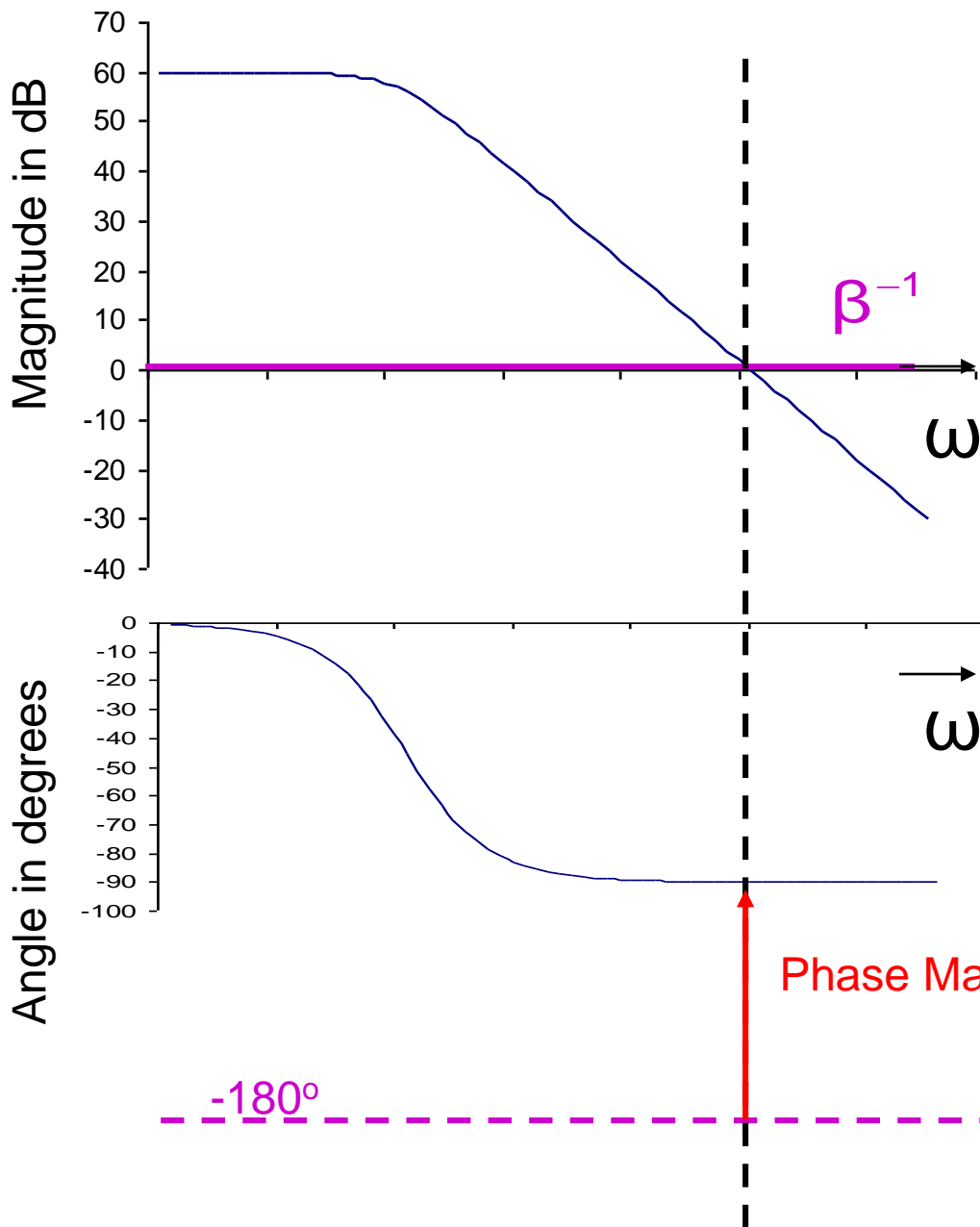
in this case phase of $A\beta$ is equal to the phase of A

Instead of plotting $A\beta$, often plot $|A|$ and phase of A and superimpose $|\beta^{-1}|$ and phase of β to get gain and phase margins

do not need to replot $|A|$ and phase of A to assess performance with different β

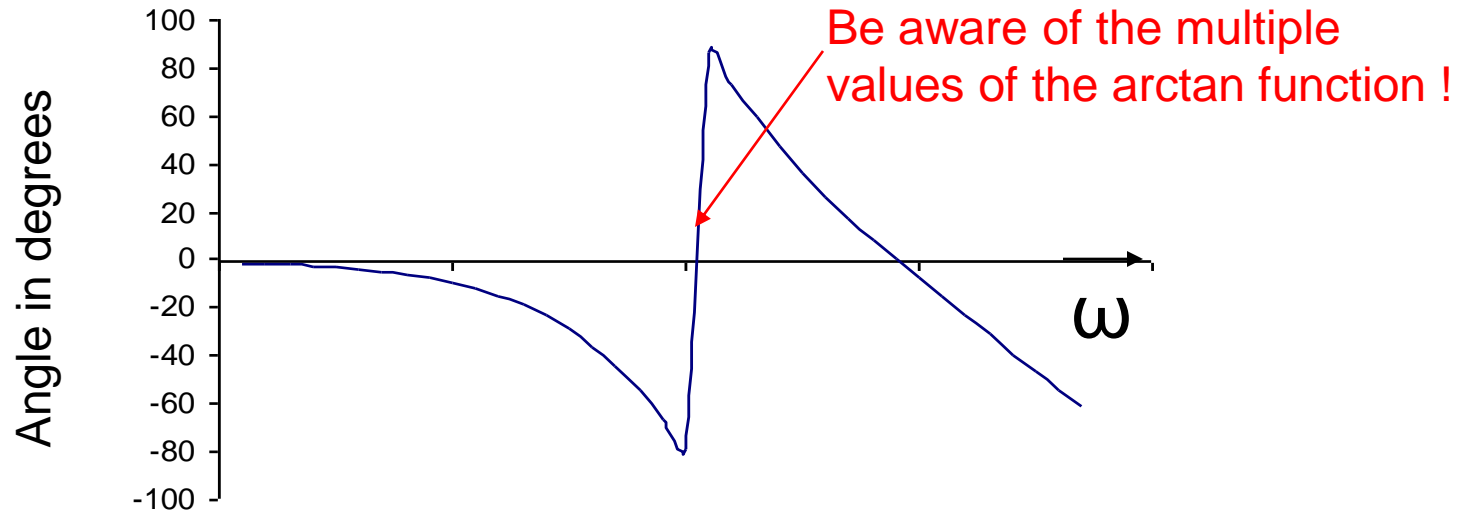
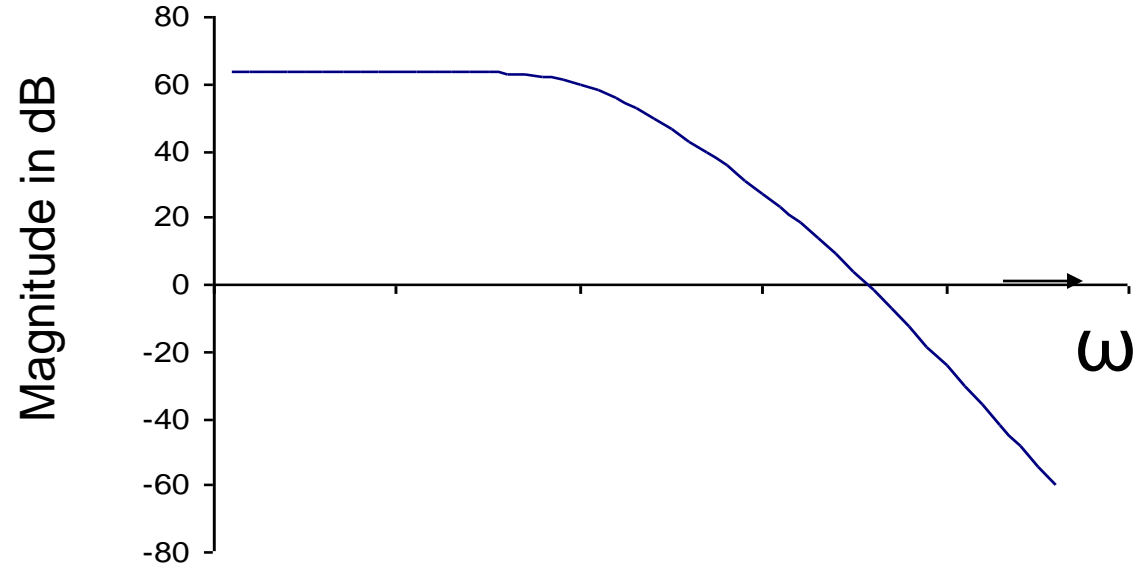
Gain and Phase Margin Examples

$$T(s) = \frac{1000}{(s+1)}$$



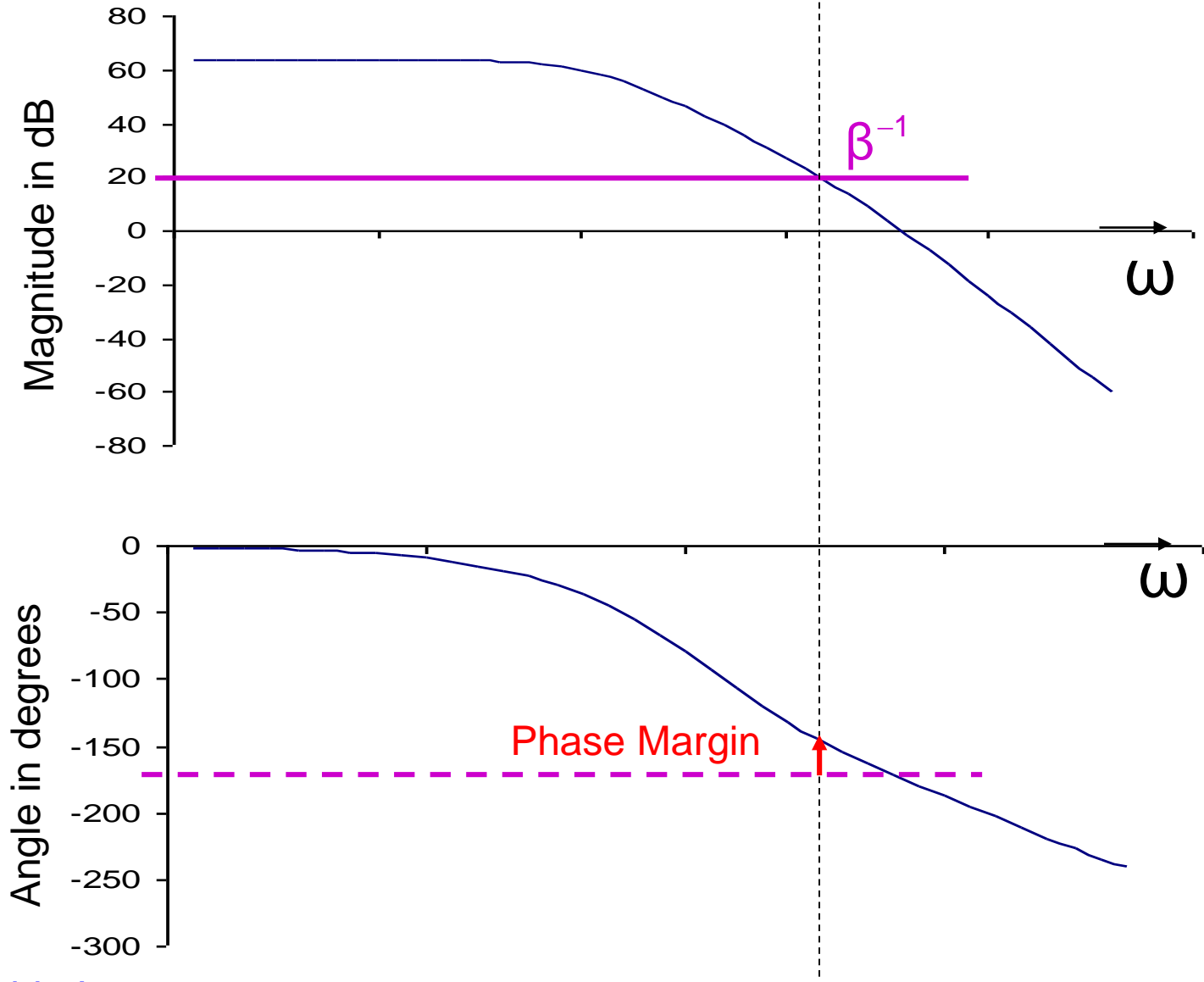
Stable !

Gain and Phase Margin Examples



Discontinuities do not exist in magnitude or phase plots

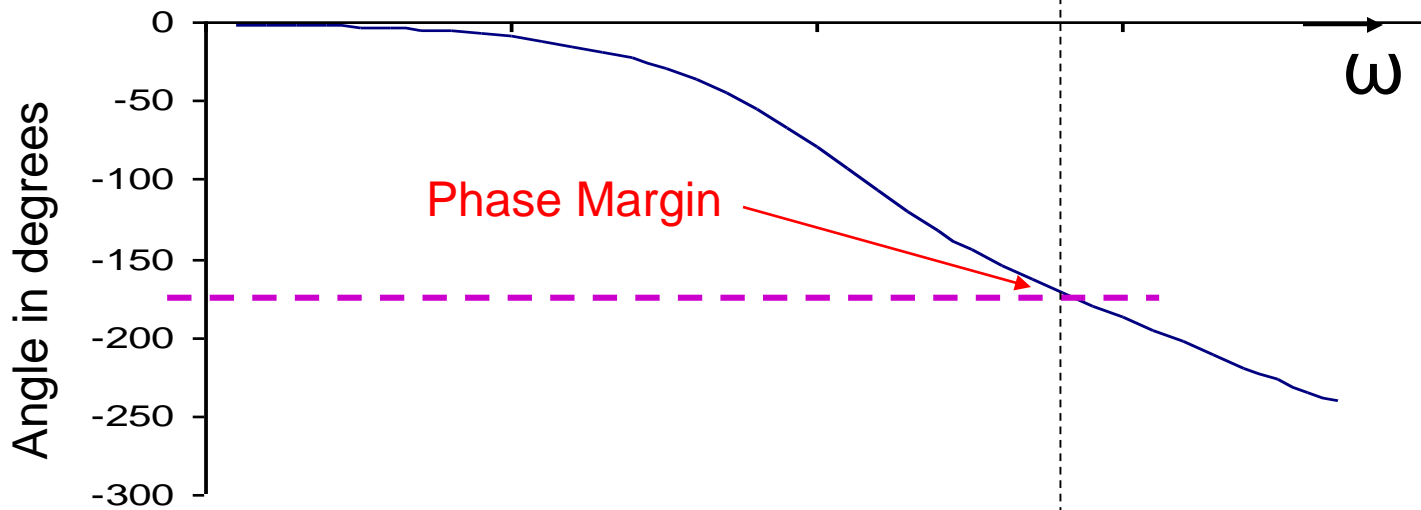
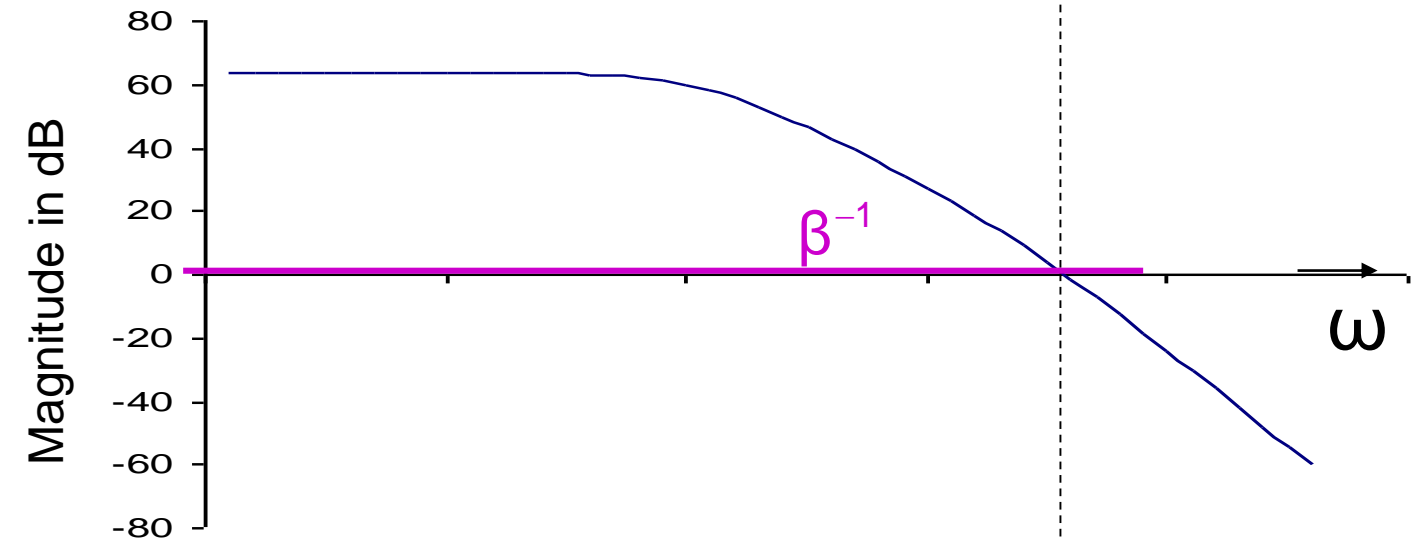
Gain and Phase Margin Examples



Stable !

But is it a good compensation ?

Gain and Phase Margin Examples



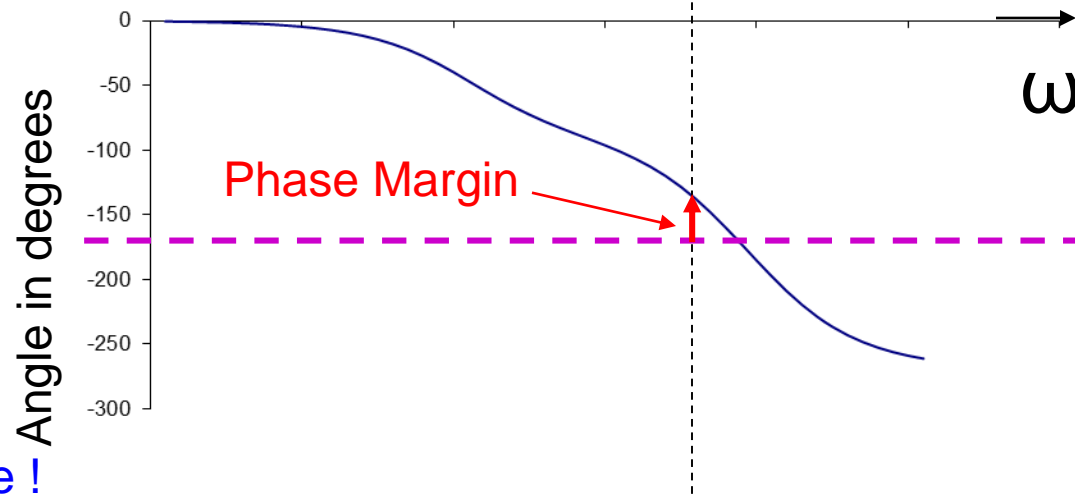
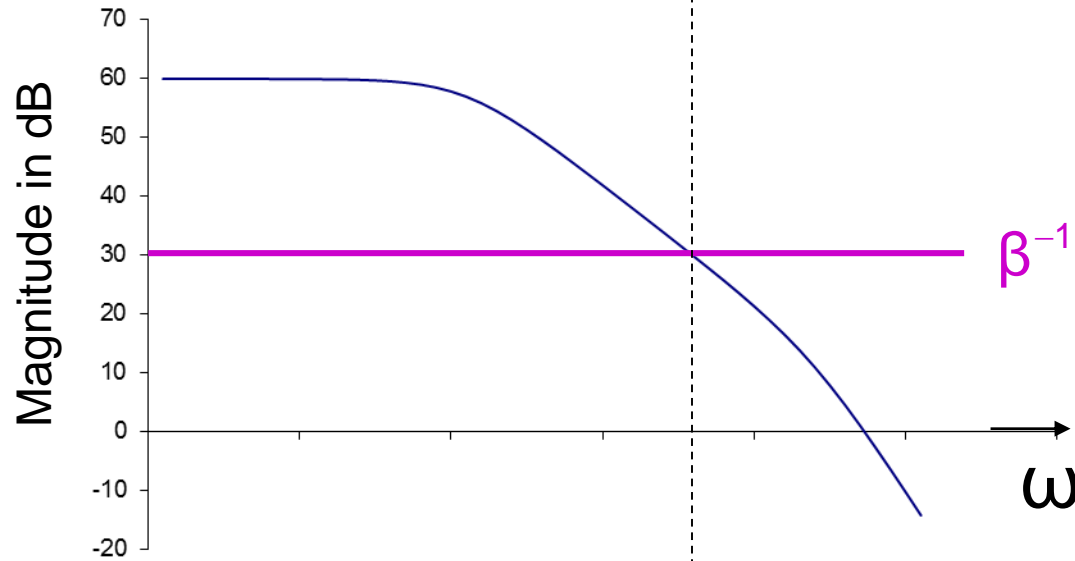
Stable !

But is it a good compensation ?

Gain and Phase Margin Examples

$$A(s) = \frac{1000}{(s+1)\left(\frac{s}{200}+1\right)}$$

$$\beta = .031$$



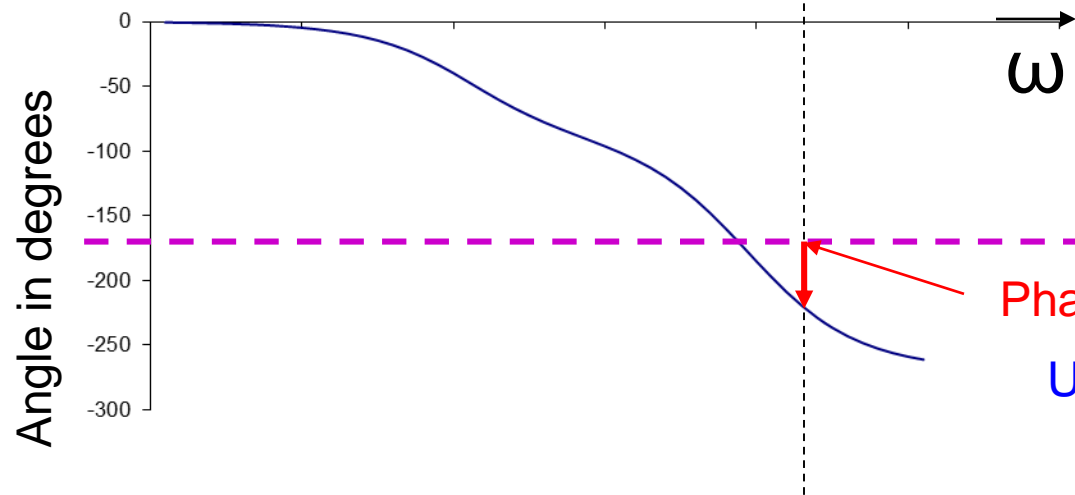
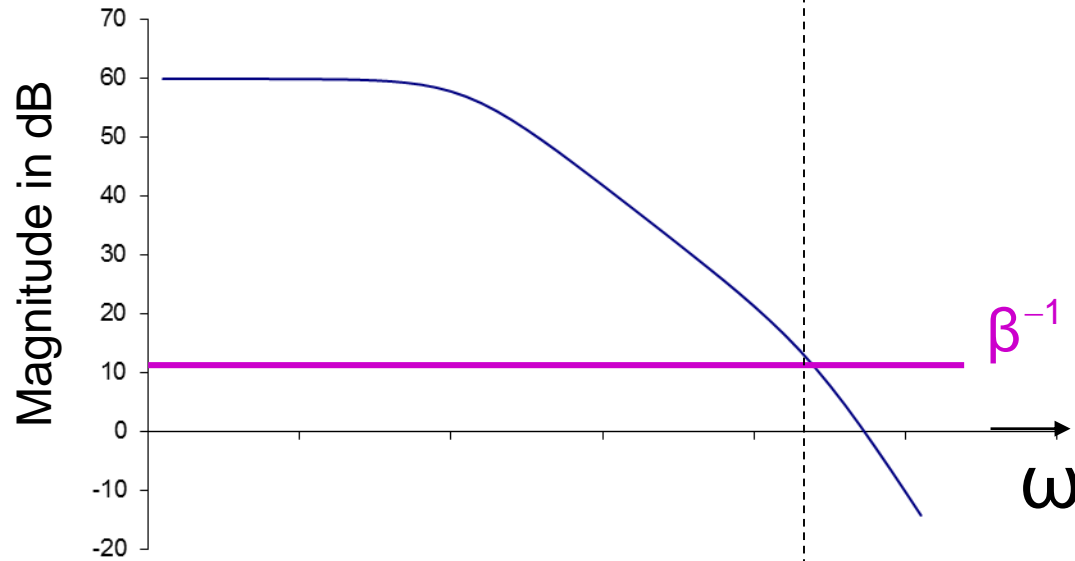
Stable !

But is it a good compensation ?

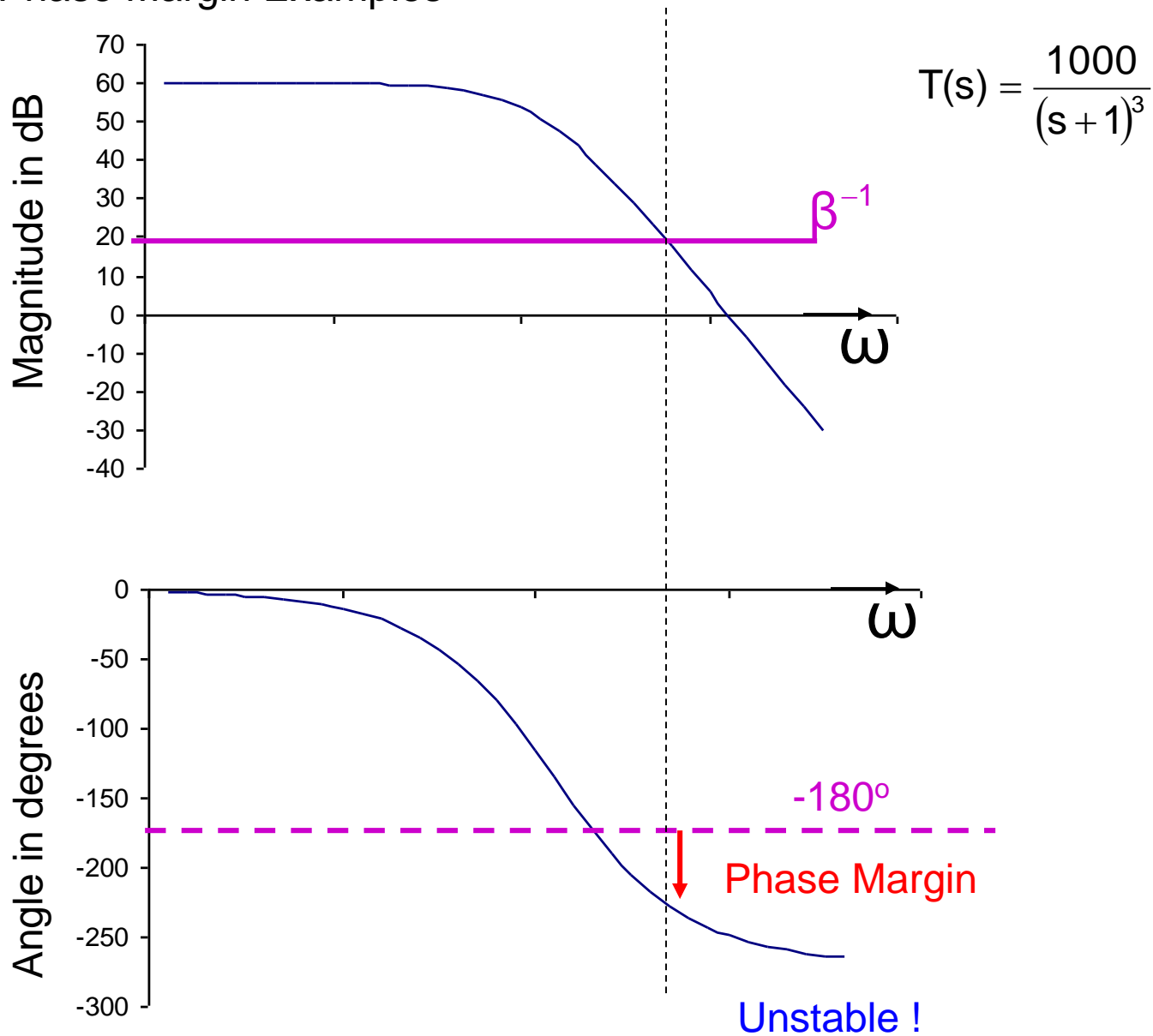
Gain and Phase Margin Examples

$$A(s) = \frac{1000}{(s+1)\left(\frac{s}{200}+1\right)}$$

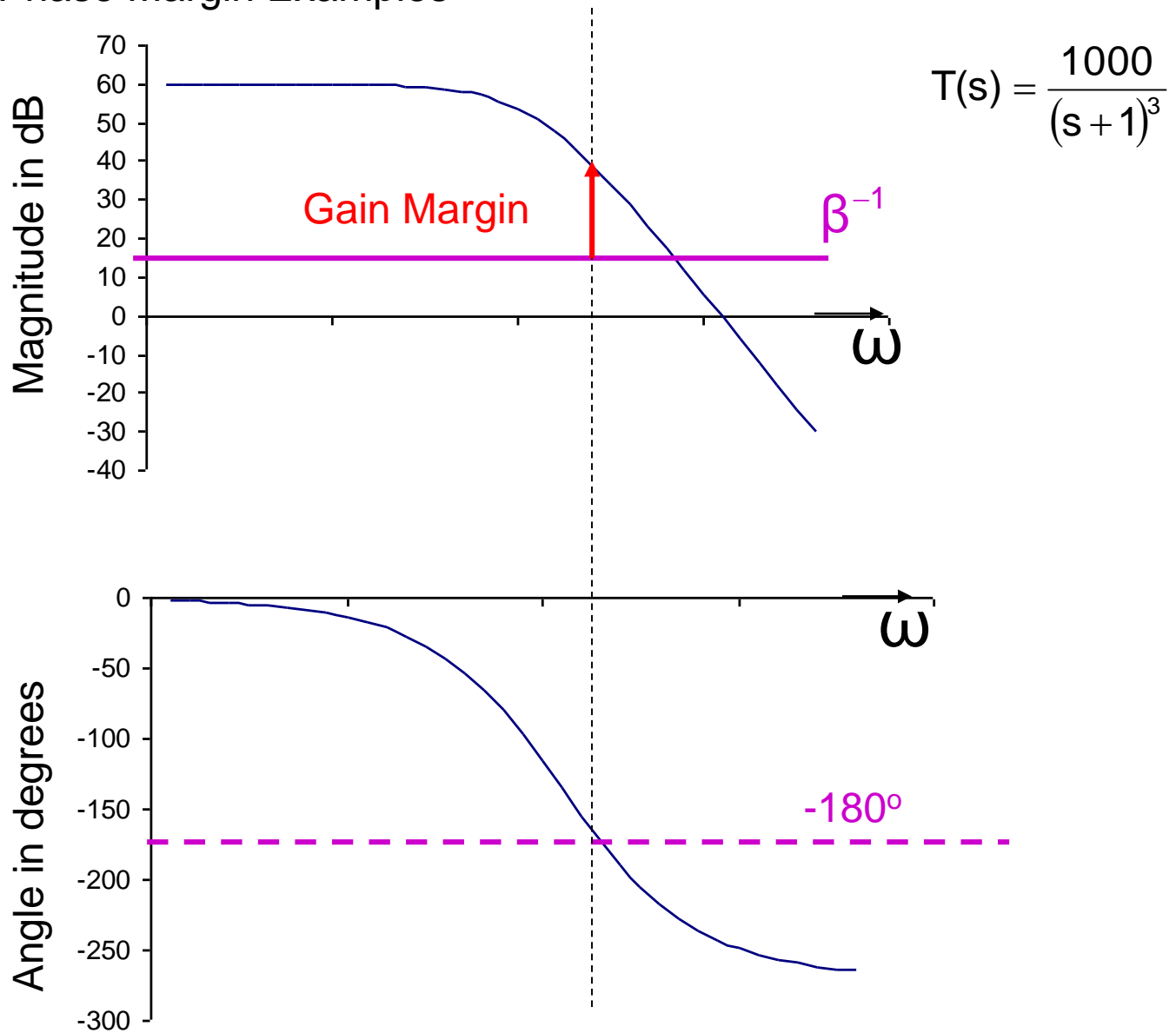
$$\beta = .31$$



Gain and Phase Margin Examples

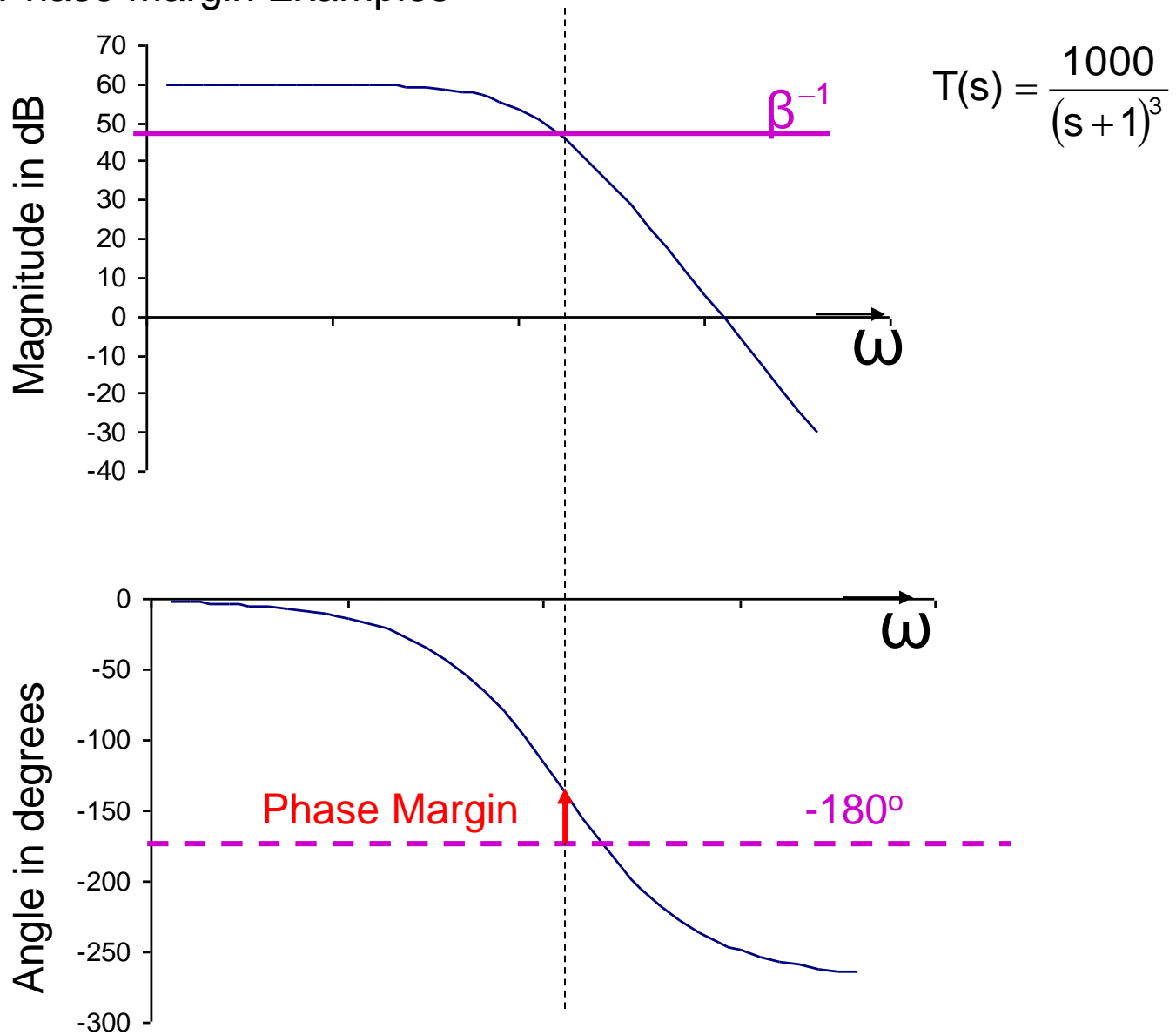


Gain and Phase Margin Examples



Unstable !

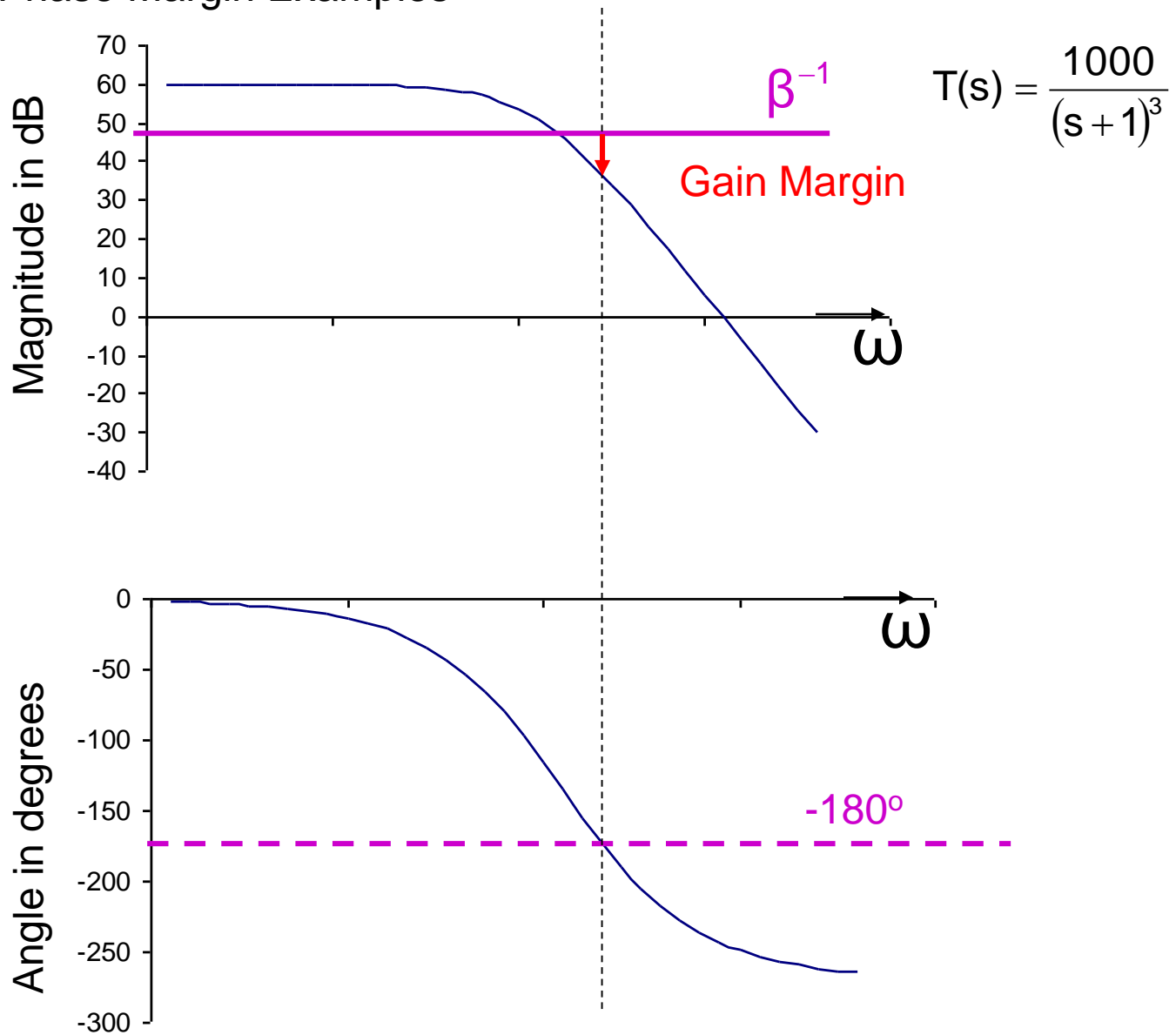
Gain and Phase Margin Examples



Stable !

But is it a good compensation ?

Gain and Phase Margin Examples



Stable !

But is it a good compensation ?



Stay Safe and Stay Healthy !

End of Lecture 16