Linear Power Supplies

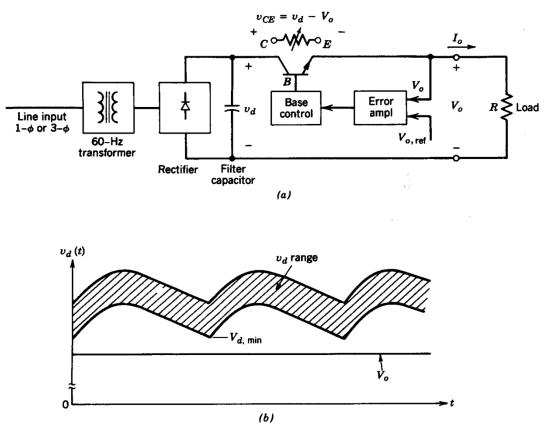


Figure 10-1 Linear power supply: (a) schematic; (b) selection of transformer turns ratio so that $V_{d,\min} > V_o$ by a small margin.

Very poor efficiency and large weight and size

Switching DC Power Supply: Block Diagram

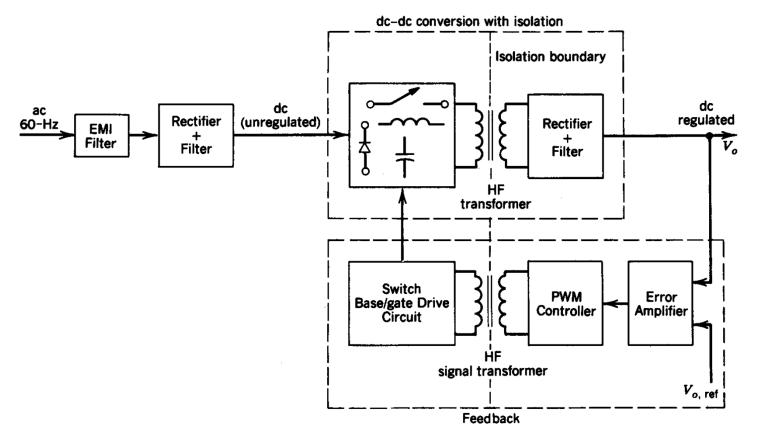


Figure 10-2 Schematic of a switch-mode dc power supply.

• High efficiency and small weight and size

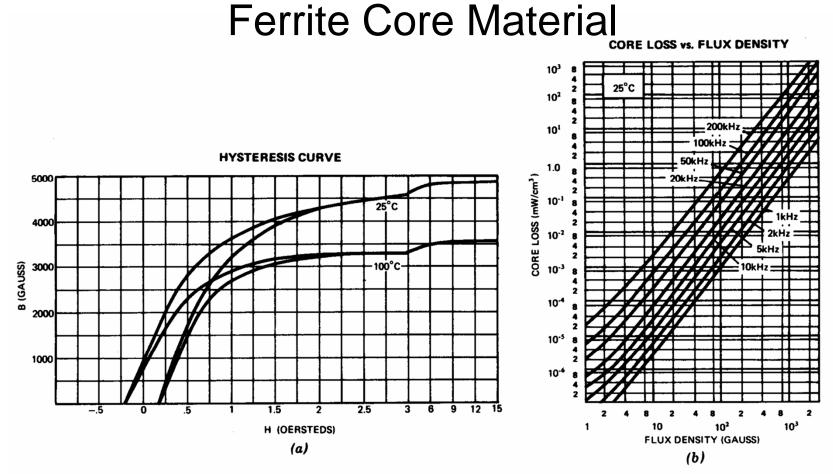


Figure 10-17 3C8 ferrite characteristic curves: (a) B-H loop; (b) core loss curves. (Courtesy of Ferroxcube Division of Amperex Electronic Corporation.)

• Several materials to choose from based on applications

Flyback Converter

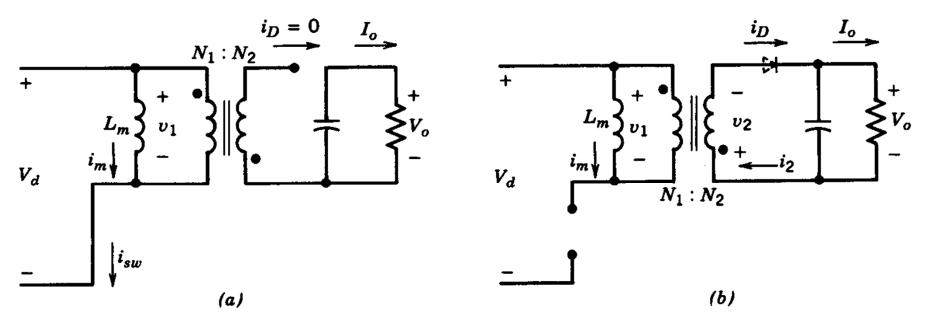
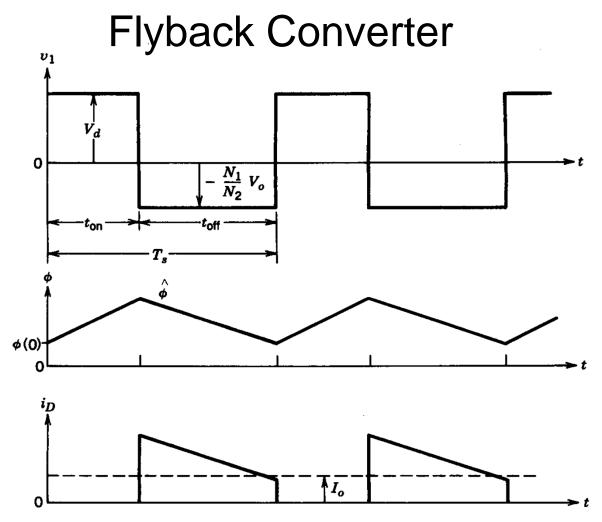
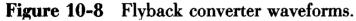


Figure 10-7 Flyback converter circuit states: (a) switch on; (b) switch off.

• Switch on and off states (assuming incomplete core demagnetization)





• Switching waveforms (assuming incomplete core demagnetization)

by John Wiley & Sons, Inc.

Forward Converter: in Practice

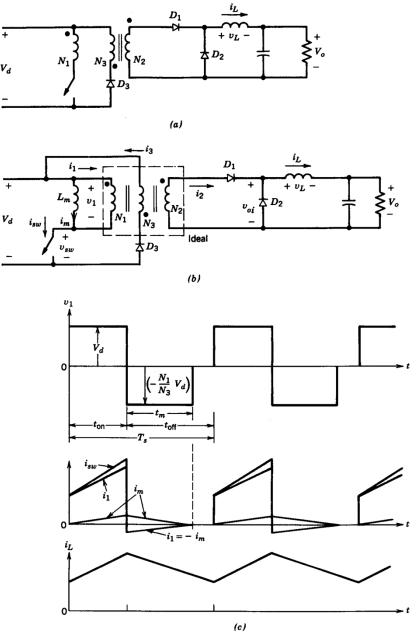


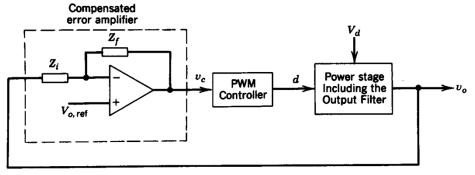
Figure 10-11 Practical forward converter.

+

 V_d

• Switching waveforms (assuming incomplete core demagnetization)

Control to Regulate Voltage Output



(a)

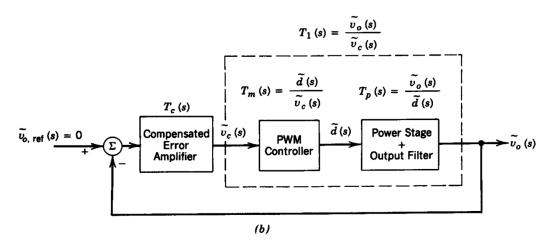


Figure 10-19 Voltage regulation: (a) feedback control system; (b) linearized feedback control system.

Linearized representation of the feedback control

State-space averaging description

State-space model
$$\dot{x} = Ax + Bu$$

 $y = Cx(+Du)$ $x = \{e.g.\} = \begin{bmatrix} v_c \\ i_L \end{bmatrix}$ Averaging $\dot{x} = A_1x + B_1v_d$ during t_{on}
 $\dot{x} = A_2x + B_2v_d$ during t_{off} Weighted sum $\dot{x} = \begin{bmatrix} A_1d + A_2(1-d) \end{bmatrix} x + \begin{bmatrix} B_1d + B_2(1-d) \end{bmatrix} v_d$ Small perturburations $x = X + \tilde{x}, \quad d = D + \tilde{d}, \quad v_d = V_d$ Simplify $\dot{\tilde{x}} = A\tilde{x} + \begin{bmatrix} (A_1 - A_2) X + (B_1 - B_2) V_d \end{bmatrix} \tilde{d}$
 $A = A_1D + A_2(1-D)$

Transfer function

Laplace domain
$$\tilde{x} = [sI - A]^{-1} [(A_1 - A_2)X + (B_1 - B_2)V_d]\tilde{d}$$

Transfer function

$$T_p(s) = \frac{\tilde{v}_o(s)}{\tilde{d}(s)}$$