HW #1

1) 
$$V_o = DV_q$$
,  $D = 0.6$ 

2) 
$$\frac{\Delta i_L}{i_L}$$
,  $\frac{\Delta i_L}{6} * 100 = 0.1$ ,  $\Delta i_L = 6m[A]$ 

$$L = \frac{V_g - V}{2\Delta i_L} = \frac{50 - 30}{2 * 6 * 10^{-3}} * 0.6 * \frac{1}{50 * 10^3} = 0.02 = 20m[H]$$

3) 
$$I_L = 6[A]$$
,  $i_{Lmax} = 6.006[A]$ ,  $i_{Lmin} = 5.994[A]$ 

4) 
$$q = c2\Delta V$$
,  $\Delta v = \frac{q}{2c} = \frac{\Delta i_L T_S}{8C}$ 

$$\frac{\Delta v}{v_o} = 0.5\% = \frac{\Delta i_L T_S}{8C} * \frac{1}{30}, \qquad C = \frac{6 * 10^{-3} * \left(\frac{1}{50 * 10^3}\right) * 100}{30 * 8 * 0.5} = 0.1\mu[F]$$

$$\Delta v = 0.15[V]$$

HW #2

1) 
$$V_o = \frac{V_g}{D'}$$
 400 =  $\frac{100}{D'}$ ,  $D' = 0.25$ ,  $D = \mathbf{0}.75$ 

$$I_o = \frac{V_{out}}{R_{out}} = \frac{400}{10} = \mathbf{40}[A]$$

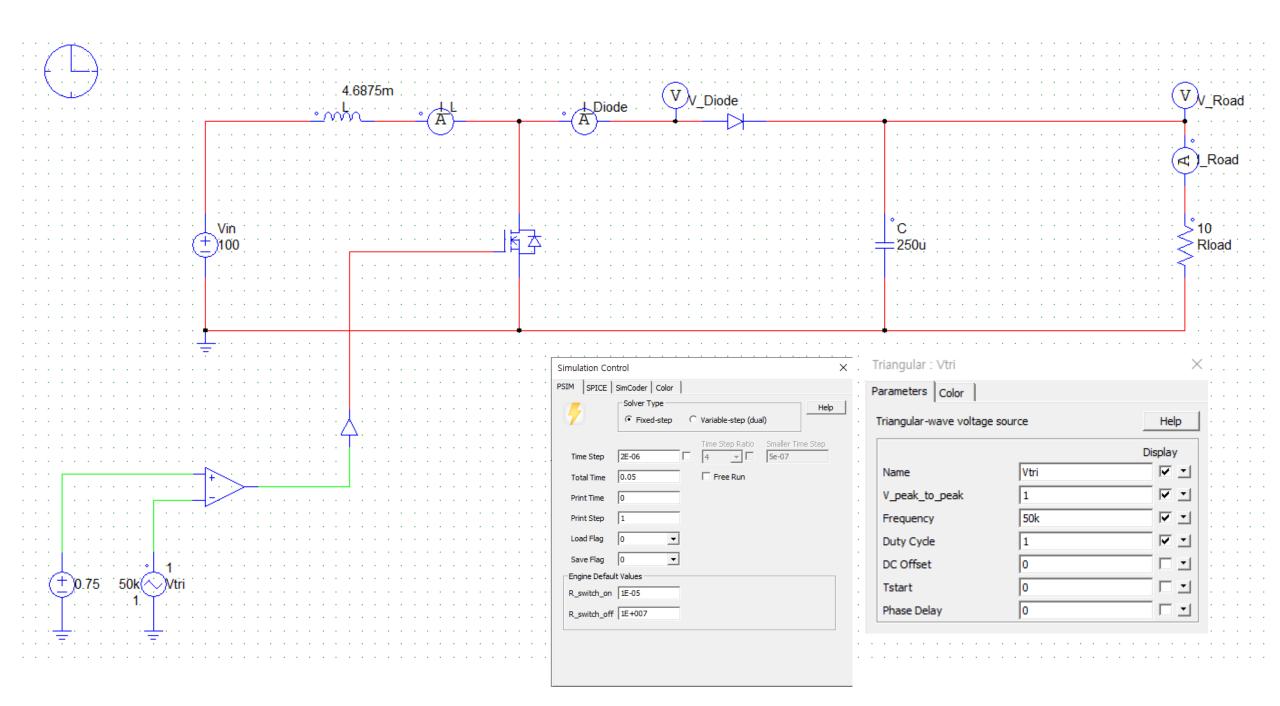
2) 
$$L = \frac{V_{in}}{2\Delta i_L}DT_S$$
,  $I = \frac{V_{out}}{D'R} = \frac{400}{0.25*10} = 160[A]$ ,  $\frac{\Delta i_L}{160} * 100 = 0.1$ ,  $\Delta i_L = 0.16 = 160m[A]$ 

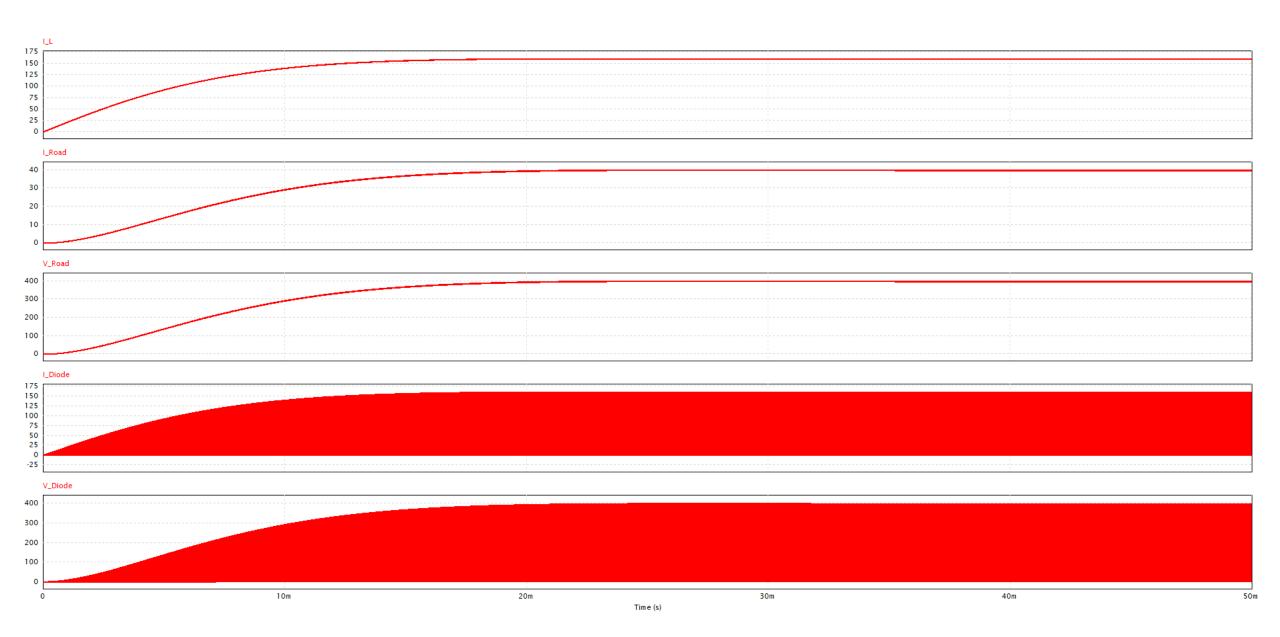
$$i_{Lmax}$$
 = **160**. **16**[*A*],  $i_{Lmin}$  = **159**. **84**[*A*]

$$L = \frac{V_{in}}{2\Delta i_I} DT_S = \frac{100}{2*0.16} * 0.75 * \frac{1}{50*10^3} = 4.6875m[H]$$

$$\frac{\Delta v}{400} * 100 = 0.3, \quad \Delta v = 1.2[V]$$

$$C = \frac{V_{out}}{2R\Delta v}DT_s = \frac{400}{2*10*1.2}*0.75*\frac{1}{50*10^3} = 250\mu[F]$$





## 파형 (x-axis 조절 32.6m to 33msec)

