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Slope Compensation in PCMC DC-DC Converters

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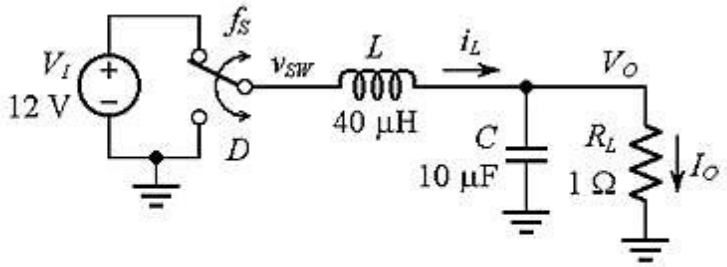
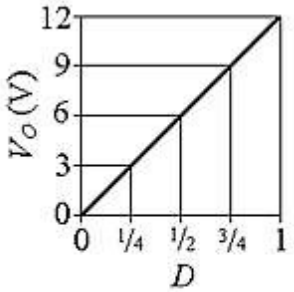
BY SERGIO FRANCO < HTTPS://WWW.EDN.COM/AUTHOR/SERGIO-FRANCO/>

Over the years I've run into a number of engineers who haven't had the chance to fully master the concept of slope compensation in dc-dc converters. I'll try to clarify [1] this concept using the buck converter as a vehicle. **Figure 1** exemplifies the buck conversion principle. The switch is toggled between the source V_I and ground at a frequency of f_S. The corresponding period is $T_S = 1/f_S$, and the portion of T_S during which the switch is in the *up* position is denoted as DT_S, where D is the *duty cycle* ($0 < D < 1$). A PSpice simulation of the circuit with $f_S = 100$ kHz and $D = 0.25$ yields the waveforms of **Figure 2**. Viewing the circuit as a *low-pass filter*, we note that after an initial transient, the circuit achieves a form of *steady state* during which V_O settles around 3 V, though with a small amount of ripple. If we raise D to 0.5, V_O will settle around 6 V, and if we raise D to 0.75, V_O will settle around 9 V.



(a)



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In fact, it is easily seen that V_O settles around the *average* of the square-wave denoted as v_{sw} in **Figure 1** , which is

$$V_O = DV_I \qquad (1)$$

Since $0 < D < 1$, it is apparent that the circuit acts as a form of *voltage divider* , with **Equation (1)** holding regardless of the current demanded by the load R_L . Initially, a good portion of the inductor current goes into charging up C , but once the circuit reaches its steady state, the capacitor current will average to zero, so the average current I_L supplied by the inductor will equal the average current I_O demanded by the load. In the above example, $I_L = I_O = V_O / R_L = 3$ A.

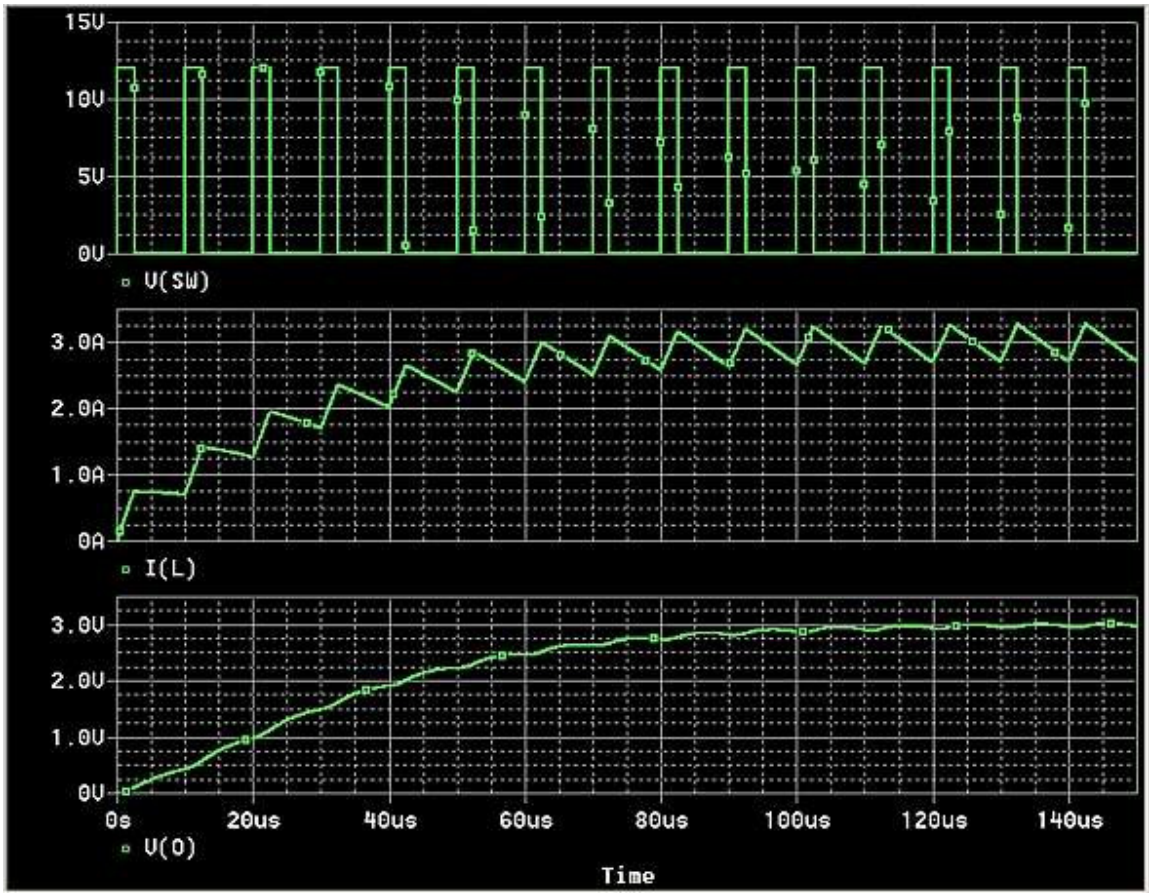

Figure 2 PSpice waveforms for the circuit of Figure 1 for the case $f_S = 100$ kHz and $D = 0.25$.

The most popular application of the buck converter is the regulation of V_O . To regulate, the circuit of **Figure 1** must include a *controller* to sense V_O and to continuously adjust D so as to maintain V_O at a prescribed value regardless of possible variations in V_I . Needless to say, the controller is a negative-feedback system. The *RLC* values of **Figure 1** were deliberately chosen for a *critically*

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How does the controller adjust D ? There are two classes of controllers, *voltage-mode* and *current-mode* controllers. The following discussion will address a popular subclass of the latter, namely, *peak-current-mode control* , or PCMC, an example of which is depicted in **Figure 3** . To sense the inductor current i_L , the circuit uses a small series resistor R_{sense} , whose voltage drop is then magnified by an amplifier having a gain of a_i . This amplifier converts i_L to the voltage $R_i\, i_L$, where

$$R_i = a_i \times R_{sense} \tag{2}$$

is the overall gain of the current-to-voltage conversion, in V/A, or ohms. To sense the output voltage V_O , the circuit uses the voltage divider $R_1 - R_2$ to generate the voltage $\beta\, V_O$, with

$$\beta = \frac{R_1}{R_1 + R_2} = \frac{1}{1 + R_2 / R_1} \tag{3}$$

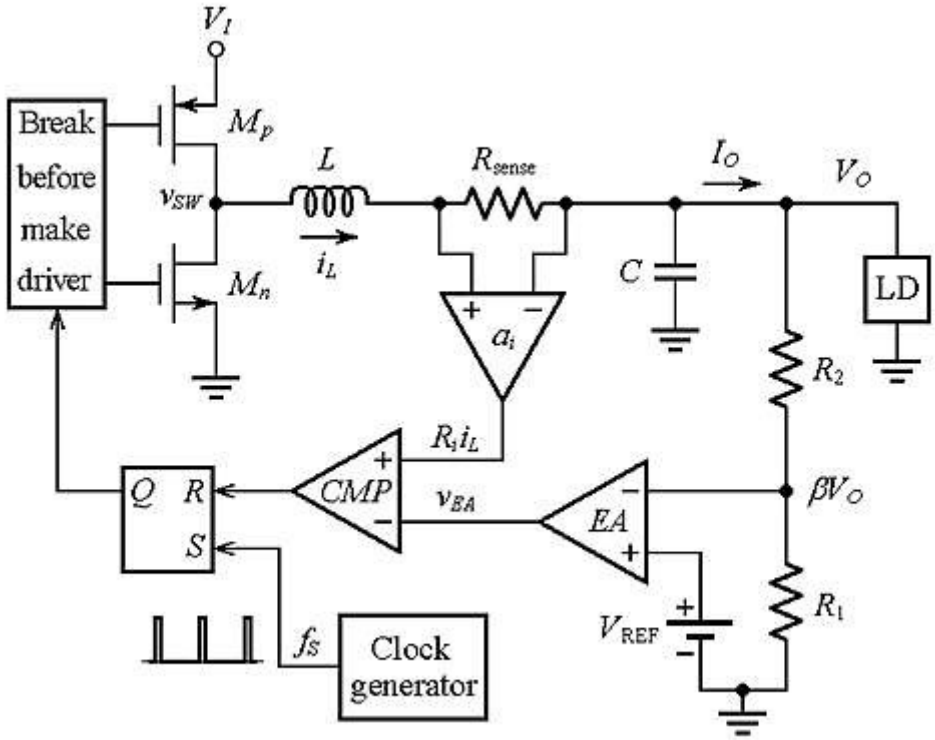

Figure 3 Circuit schematic of a PCMC buck converter without slope compensation.

Central to the system is the *error amplifier EA* , a high-gain amplifier that compares $\beta\, V_O$ against a

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$$V_O = \left(1 + \frac{R_2}{R_1}\right) V_{REF} \tag{4}$$

Once it reaches its steady state, the circuit operates as follows:

A cycle initiates when a clock pulse sets the flip-flop. This closes the M_p switch to make $v_{SW} = V_I$. During this portion of the cycle, denoted as DT_S in **Figure 4**, the inductor current i_L ramps up with a slope of S_n governed by the $i_L - v_L$ inductor law, or $S_n = di_L/dt = v_L/L$. During this time we have $v_L = V_I - V_O$, so

$$S_n = \frac{V_I - V_O}{L} \tag{5}$$

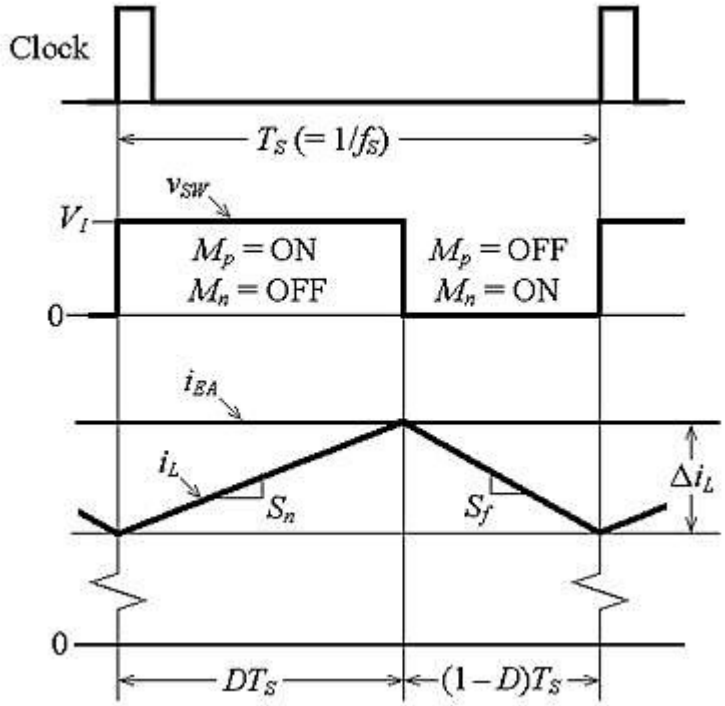

Figure 4 Steady-state waveforms in peak-current-mode control (PCMC).

Turning back to **Figure 3**, we observe that the *CMP* comparator continuously compares the voltage $R_i\, i_L$ against the voltage v_{EA}, and that as soon as $R_i\, i_L$ reaches v_{EA}, the *CMP* trips to reset the flip-flop. Dividing both sides by R_i, this is equivalent to saying that the *CMP* trips as soon as i_L reaches the value

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This allows us to visualize a cycleexclusively in terms of currents as in **Figure 4** . Now, resetting the flip-flop opens the M_p switch while closing the M_n switch to make $v_{SW} = 0$. During the remainder of the cycle, denoted as $(1 - D)T_S$, we have $v_L = 0 - V_O$, so i_L ramps down with a slope of S_f such that

$$S_f = \frac{-V_O}{L} \tag{7}$$

A new cycle begins with the arrival of the next clock pulse.

Two Flaws of Uncompensated PCMC

As is, the circuit of **Figure 3** suffers from two flaws. The first flaw is depicted in **Figure 5** for the case of a converter designed to regulate V_O at 3.0 V (for simplicity, a cycle is assumed to start at $t = 0$). **Figure 4*a*** shows the steady-state inductor current i_L and its average I_L for the case $V_I = 9$ V, corresponding to a duty cycle of $D = 3/9 = 1/3$. Suppose now V_I drops to 4.5 V, corresponding to a duty cycle of $D = 3/4.5 = 2/3$. Assuming v_{EA} hasn't had time to change appreciably, the average inductor current I_L will rise as in **Figure 5*b*** . This is so because while the down-slope S_f remains constant at $-3/L$, the up-slope S_n decreases from $(9 - 3)/L$ to $(4.5 - 3)/L$, that is, from $6/L$ to $1.5/L$. With an increased I_L , V_O will also tend to increase, indicating poor regulation.

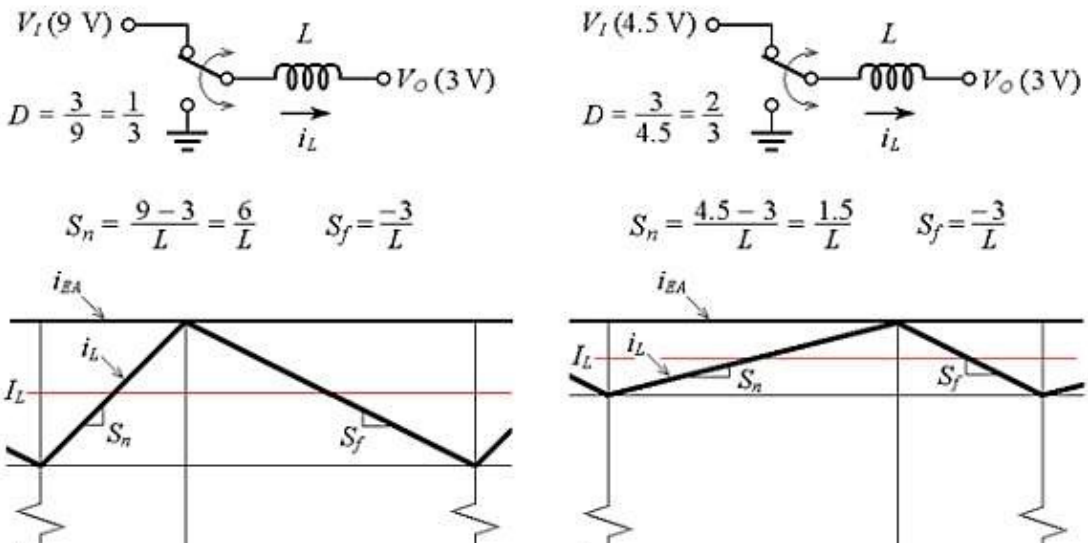

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Figure 5 The inductor current of the circuit of Figure 3 for two different duty cycles.

The second flaw is a form of instability known as *sub-harmonic oscillation* , which arises for $D >$ 0.5. **Figure 6** shows how an inductor current perturbation i_l (0) at the beginning of a cycle evolves into the perturbation i_l (T_S) at the end of the cycle. (A perturbation might be due, for instance, to a misfiring of the comparator in the course of the previous cycle.) Using simple geometry we can write i_l (0)/?$t = S_n$ and i_l (T_S)/?$t = S_f$. Eliminating ?t gives

$$\frac{i_l(T_S)}{i_l(0)} = \frac{S_f}{S_n} = \frac{-D}{1-D} \qquad (8)$$

indicating that (*a*) the polarity of i_l (T_S) is *opposite* to that of i_l (0), and (*b*) for $D <$ 0.5 its magnitude will decrease to die out after a sufficient number of cycles, but for $D >$ 0.5 it will tend to increase from one cycle to the next, leading to the aforementioned sub-harmonic instability.

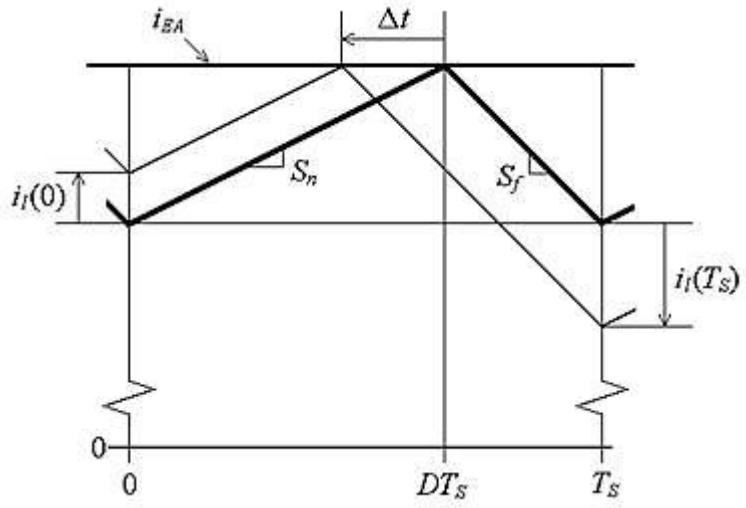

Figure 6 Illustrating sub-harmonic oscillation for $D >$ 0.5.

Slope Compensation

Looking back at **Figure 5** , we observe that if we want **Figure 5*b*** to retain the same I_L value as **Figure 5*a*** , we need to reduce the i_{EA} value of **Figure 5*b*** so as to “push down” the i_L waveform till the respective I_L s align. By how much do we need to reduce i_{EA} ? To answer, let us draw the desired i_L waveforms for three different values of D . As depicted in **Figure 7** , top, we start out by drawing the down-ramps for i_L , all vertically centered about identical I_L s, and all with the same

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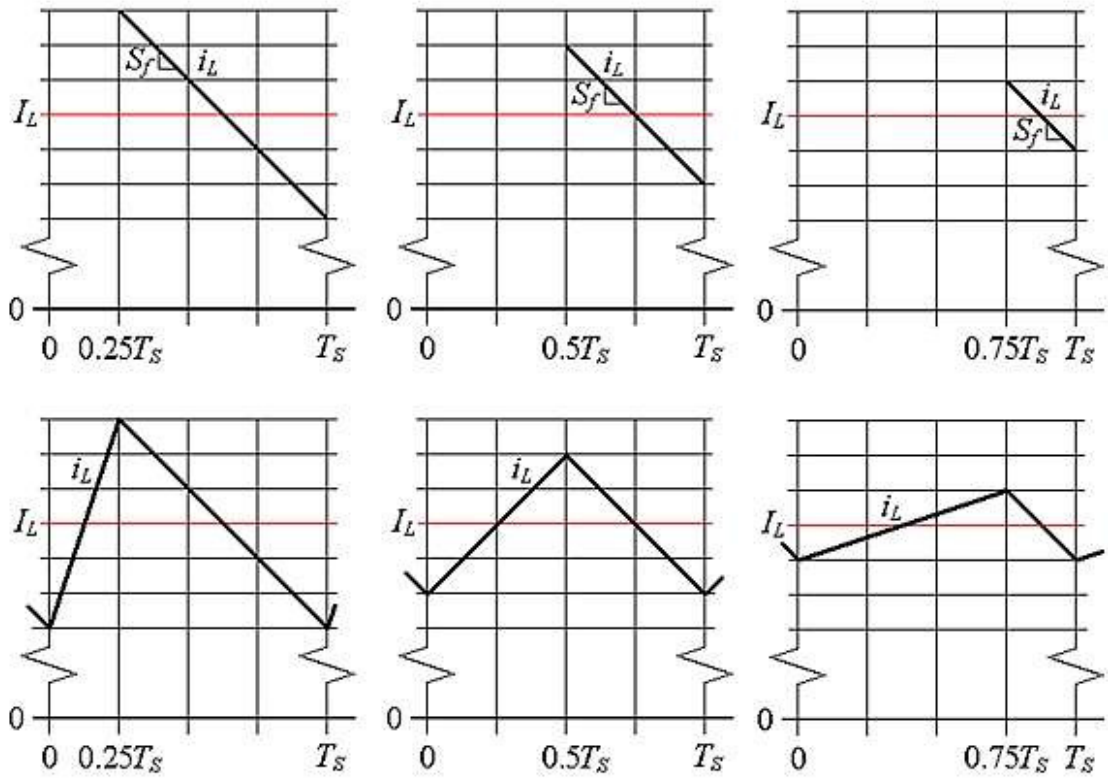

Figure 7 Constructing the compensated i_L waveforms for D = 0.25, 0.5, and 0.75.

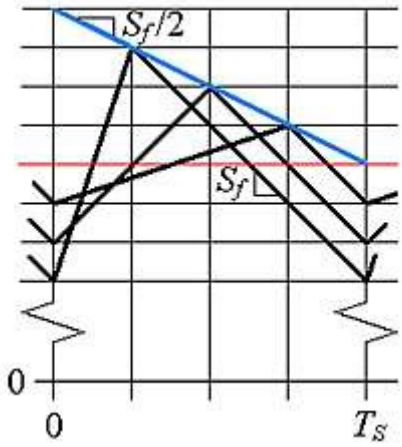

Figure 8 The locus of the peaks of Figure 7 is a ramp with a slope of S_f /2.

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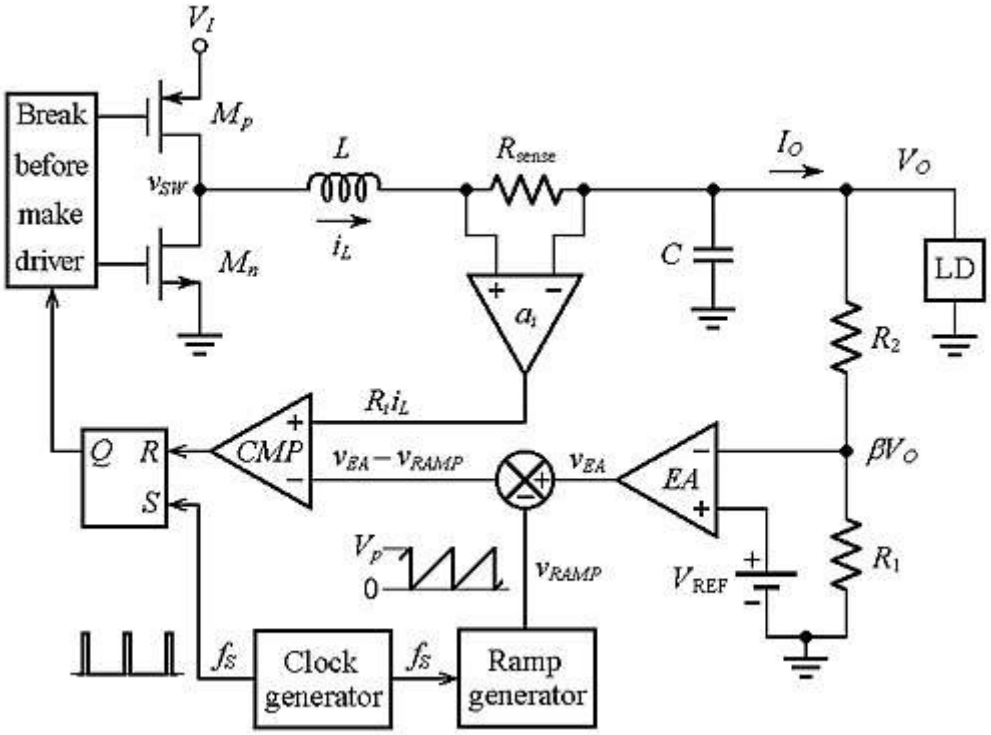

Figure 9 Incorporating slope compensation in the PCMC buck converter of Figure 3.

This shows precisely by how we must reduce i_{EA} , hence the designation *slope compensation* .

Figure 9 shows one way of modifying the circuit of **Figure 3** so as to achieve slope compensation. The circuit now includes a saw-tooth generator operating at a frequency of f_S , whose output v_{RAMP} is then subtracted from v_{EA} to produce the desired locus of peak values for i_L . With slope compensation, the waveforms of **Figure 5** change as depicted in **Figure 10** , where $i_{EA\ (comp)} = (v_{EA} - v_{RAMP})/R_i$.

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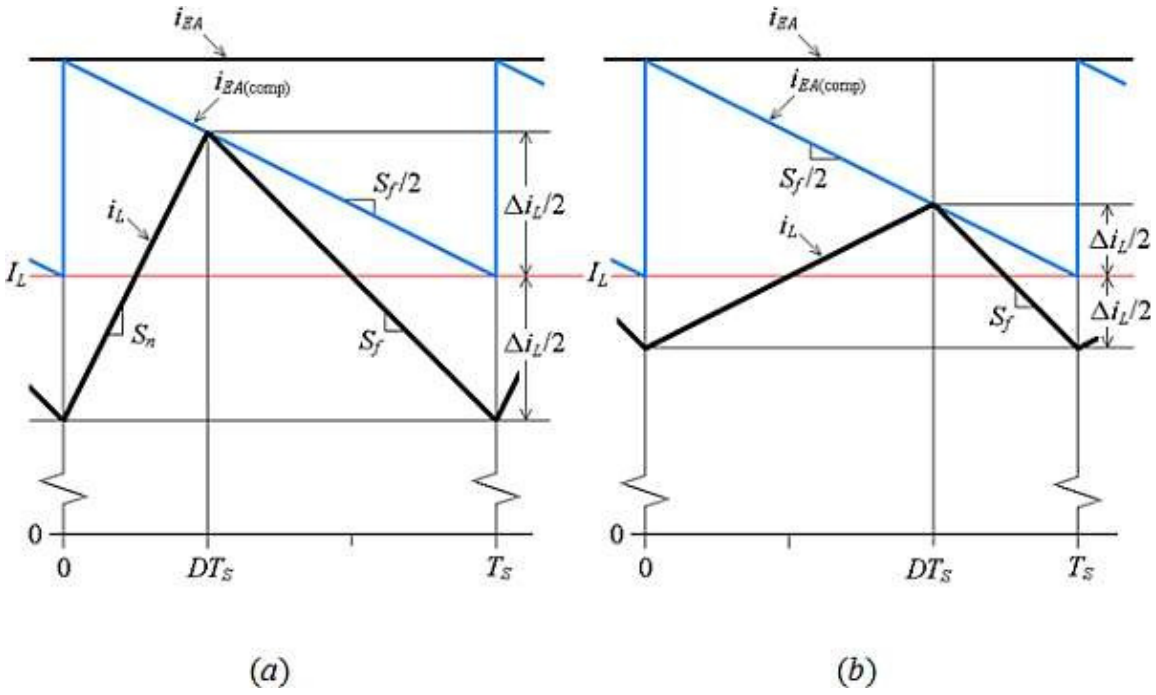

Figure 10 The inductor current of the circuit of Figure 9 for two different duty cycles.

As an added bonus, slope compensation also eliminates sub-harmonic oscillation, as depicted in **Figure 11** . Using graphical inspection, we observe that a beginning-of-cycle disturbance i_l (0) will result in an end-of-cycle disturbance i_l (T_s) of *lesser* magnitude, even though $D > 0.5$ (in fact, you can convince yourself that this holds for any value of D , $0 < D < 1$). It is the case to say that with slope compensation we are in effect killing two birds with one slope – ops stone.The error amplifier *EA* , shown in **Figure 9** as a mere triangle, serves two important functions: (*a*) to drive its inverting input voltage as close as necessary to the non-inverting one so as to approximate **Eq. (4)** , and (*b*) to provide a frequency profile suitable to ensure a prescribed phase margin for the whole system. Not at all an ordinary amplifier, which can easily form the body of a future blog on stability analysis and error-amplifier design.

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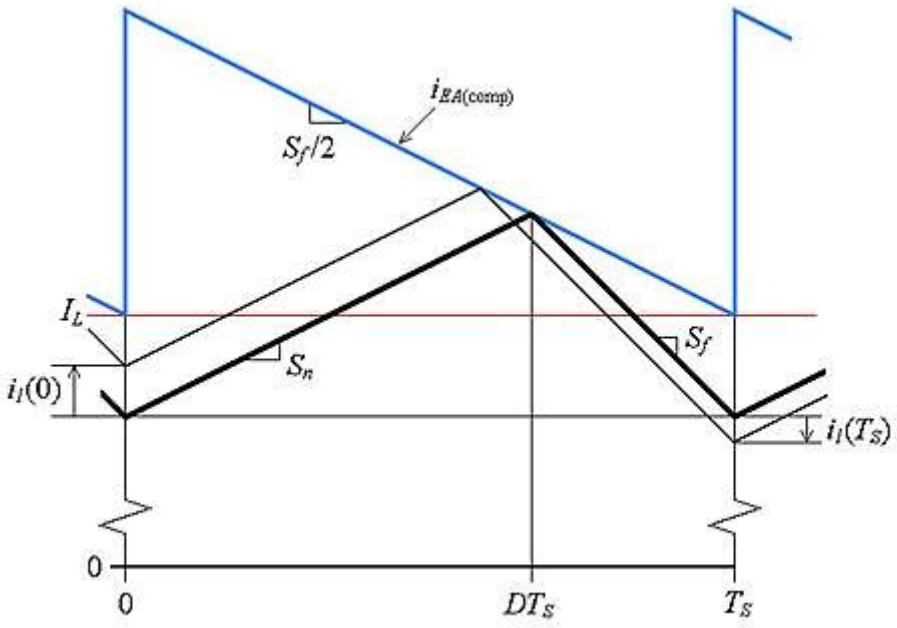

Figure 11 Slope compensation prevents sub-harmonic oscillation regardless of *D* .

References

[1] Design with Operational Amplifiers and Analog Integrated Circuits < http://online.sfsu.edu/sfranco/bookopamp/opampsjacket.pdf> , Sergio Franco

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rridley

March 26, 2015

"For a complete theoretical treatment of this current-mode system, you can download the free book from **http://www.ridleyengineering.com /books.htmlnnClick < http://www.ridleyengineering.com/books.htmlnnClick>** on the Current-Mode Control tab to see the download. "

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March 27, 2015

“Finally!!! That's all I have to say. :-)nnThank you for the nice article Mr. Franco.”

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D Feucht

March 28, 2015

“Back in the early '90s, Ray Ridley's sampled-loop (“continuous-time”) model of peak-current control was a major advancement over the low-frequency average model because it accurately predicted the subharmonic oscillation behavior. So start with Ridley's

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D Feucht

April 1, 2015

“Dr. Franco,nnI wanted to add that your article is clear and well-illustrated in showing how slope compensation affects stability for changes in input and output port voltages. It should be quite helpful to those new to peak current control.nnI know yo

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Sean McCommons

April 10, 2015

“This is wonderful information. thanks Dr. Franco and rridley.nnWhat I would like to know is how this relates to EM radiation. Meaning slope compensation is very fine to reduce instability. But I would really like to know about slope compensation for

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Sean McCommons

April 10, 2015

“Meaning It would be interesting to see a voltage slope vs efficiency treatment…”

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Petrica.Barbieru

September 26, 2015

“Very good and clear explanation!”

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"There are no images! Please help fix. Thank you"

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Raj Jay

May 31, 2017

"Hi Dr. Franco, nThe images are missing and it is difficult to correlate the explanation with out them. please repost it. Thanks."

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Sergio Franco

May 31, 2017

"I can see them alright. I just sent an email to Steve Taranovich to see if he can fix this problem.n"

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steve.taranovich

May 31, 2017

"@Raj Jay—It might have been a temporary glitch—I see all the figures—Please let me know if you still have problems. Maybe it is the browser you are using?"

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Raj Jay

June 2, 2017

"Hi Steve,n Thanks. I am able to see the pictures properly now. nBest Regards."

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Raj Jay

June 2, 2017

"Dr. Franco, Thanks for the great explanation on why sub harmonic oscillations happen. Best Regards."

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Sourire08

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Sergio Franco

January 12, 2018

"The combination of C and the error amplifier does axhibit some inertia in responding to the sudden change in VI, so assuming vEA hasn't had time to change yet, allows for an easier comparison between the cycle right before and the cycle right after the in

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