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Enter now Christophe Basso's 3rd book: "Designing Control Loops for Linear and Switching Power Supplies." (The other 2 books, particularly the "Switch Mode Power Supplies", are excellent also.) I'm sure you can find the table of contents

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online, so I won't repeat it here. There are 9 chapters that break the book up into basically 3 parts: 1.

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Designing Control Loops for Linear and Switching Power Supplies: A Tutorial Guide Christophe Basso October 2012 Last update March 3rd 2014 Corrections of typos, mistakes and errors found by readers or by the author himself. Special thanks go to Mr Tomas Gubek from Czech Republic who really scrutinized the text line by line and

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Designing Control Loops for Linear and Switching Power Supplies: A Tutorial Guide, 2012, 593 pages, Christophe Basso, 1608075575, 9781608075577, Artech House, 2012 Loop control is an essential area of electronics engineering that today's professionals

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In a purely linear feedback loop, f_c is limited by cumulative phase lags in various system elements. These phase lags inevitably increase with frequency in a manner that often varies unpredictably. Compensation becomes impossible, forcing the designer to set f_c at a frequency where the phase lags are still manageable.

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Designing Control Loops for Linear and Switching Power Supplies By A Tutorial Guide Basics of Loop Control Transfer Functions Stability Criteria of a Control System Compensation Operational

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Amplifiers-Based Compensators Operational Transconductance Amplifier-Based Compensators TL431-Based Compensators Shunt Regulator-Based Compensators Measurements and Design Example

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Designing control loops for linear and switching power supplies: a tutorial guide October 04, 2012 // By Julien Happich Christophe Basso's new book on loop control is now available on booksellers shelves. Packed with more than 1500 equations and more than 400 figures, the book offers a refreshing approach on a complex subject, loop control.

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Nevertheless, the controller used is of a high degree of complexity with two control loops: a sliding mode controller is used for the motion control whilst, for the pneumatic force control, a nonlinear state feedback controller is used. Models of friction force and servo-valves are used to cope with the systems nonlinearities.

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Conclusion. ; Measurements and Design Examples - Measuring the Control System Transfer Function. Design Example 1: A Forward dc-dc Converter. Design Example 2: A Linear Regulator. Design Example 3: A CCM Voltage-Mode Boost Converter. Design Example 4: A Primary-Regulated Flyback Converter. Design Example 5: Input Filter Compensation. Conclusion.

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