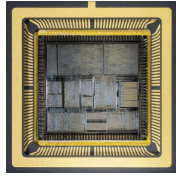


Lecture 4: SPICE

CSCOE 6651 Advanced VLSI Systems

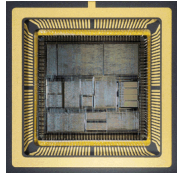
Instructor: Saraju P. Mohanty, Ph. D.

NOTE: The figures, text etc included in slides are borrowed from various books, websites, authors pages, and other sources for academic purpose only. The instructor does not claim any originality.



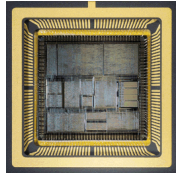
Lecture Outlines

- About SPICE
- Supported analysis by SPICE
- Circuit Simulation
- Methods for solving linear and non linear equations



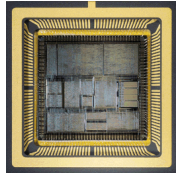
About SPICE

- SPICE –Simulation Program with Integrated Circuit Emphasis
- SPICE is a general-purpose circuit simulation program for nonlinear dc, nonlinear transient, and linear ac analyses
- Circuits may contain:
 - resistors, capacitors, inductors, mutual inductors, independent voltage and current sources
 - four types of dependent sources
 - lossless and lossy transmission lines (two separate implementations), switches, uniform distributed RC lines
 - common semiconductor devices: diode, BJT, FET



SPICE History

- 1969-70: Prof. Roher and a class project
 - CANCER: Computer Analysis of Nonlinear Circuits, Excluding Radiation
- 1970-72: Prof. Roher and Nagel
 - Develop CANCER into a truly public-domain, general-purpose circuit simulator
- 1972: SPICE I released as public domain
 - SPICE: Simulation Program with Integrated Circuit Emphasis
- 1975: Cohen following Nagel research
 - SPICE 2A released as public domain
- 1976 SPICE 2D New MOS Models
- 1979 SPICE 2E Device Levels (R. Newton appears)
- 1980 SPICE 2G Pivoting (ASV appears)



SPICE History ...

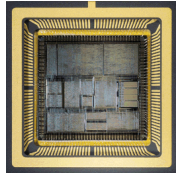
Free Tools

- SPICE from Berkeley
- WinSpice
- NgSpice
- TclSpice
- LTSpice
- XSpice
- KSpice

Commercial Tools

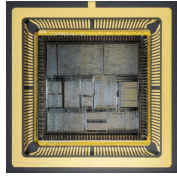
- Spectre
- PSpice
- HSpice
- TopSpice
- B2-Spice

Some of them run in Unix and some of them in Windows.



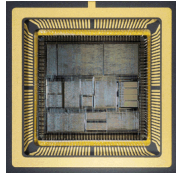
SPICE History ...

- **Simulation Program with Integrated Circuit Emphasis**
 - Developed in 1970's at Berkeley
 - Many commercial versions are available
 - HSPICE is a robust industry standard
 - Has many enhancements that we will use
- The circuits elements are called **cards**, and complete description is called a **SPICE deck**.
- The file contains a netlist consisting of components and nodes, simulation options, analysis options, and device models.



Writing Spice Decks

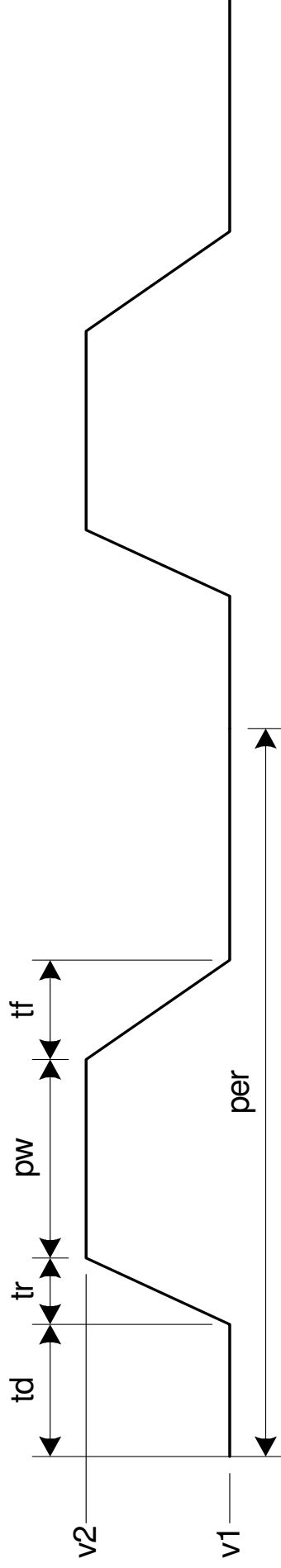
- Writing a SPICE deck is like writing a good program
 - Plan: sketch schematic on paper or in editor
 - Modify existing decks whenever possible
 - Code: strive for clarity
 - Start with name, email, date, purpose
 - Generously comment
 - Test:
 - Predict what results should be
 - Compare with actual
 - *Garbage In, Garbage Out!*

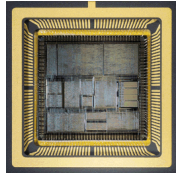


SPICE Sources

- DC Source
Vdd vdd gnd 2.5
- Piecewise Linear Source
Vin in gnd pwl 0ps 0 100ps 0 150ps 1.8 800ps 1.8
- Pulsed Source
Vclk clk gnd PULSE 0 1.8 0ps 100ps 100ps 300ps 800ps

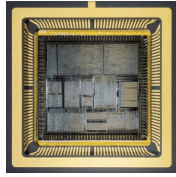
PULSE v1 v2 td tr tf pw per





SPICE Elements

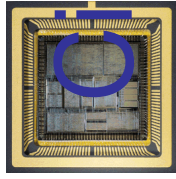
Letter	Element
R	Resistor
C	Capacitor
L	Inductor
K	Mutual Inductor
V	Independent voltage source
I	Independent current source
M	MOSFET
D	Diode
Q	Bipolar transistor
W	Lossy transmission line
X	Subcircuit
E	Voltage-controlled voltage source
G	Voltage-controlled current source
H	Current-controlled voltage source
F	Current-controlled current source



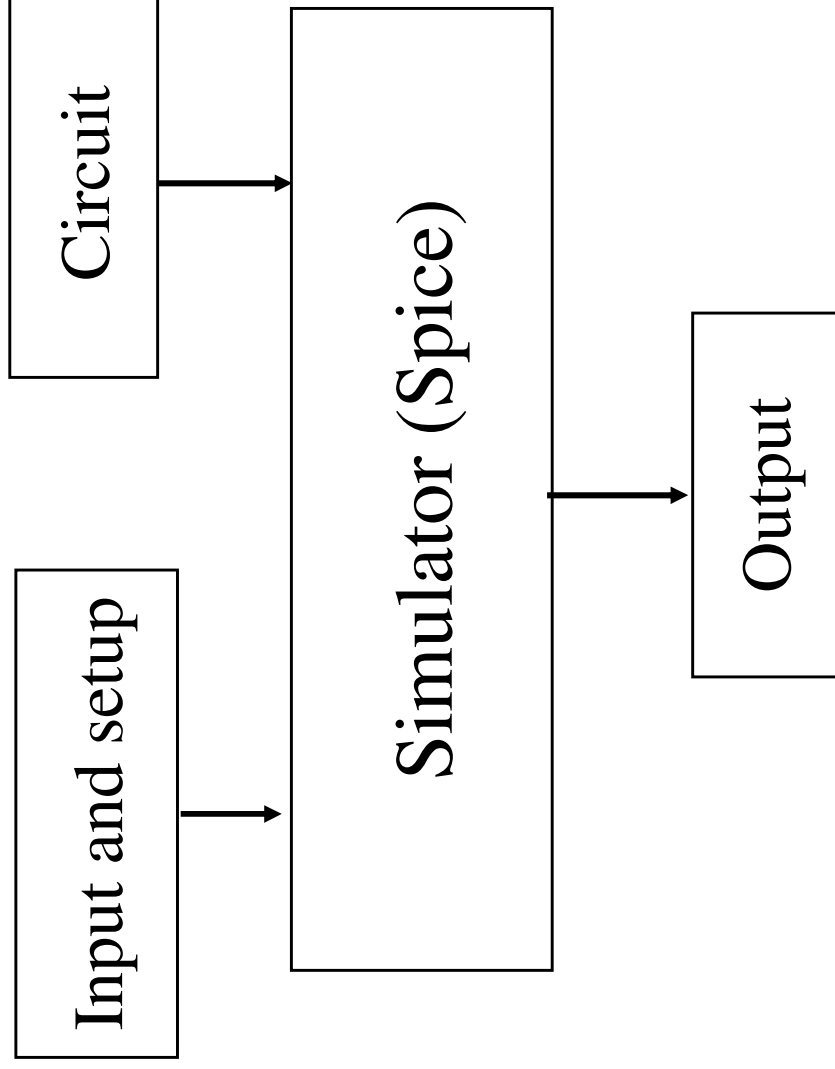
SPICE Units

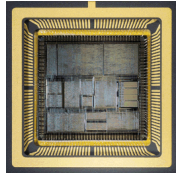
Letter	Unit	Magnitude
a	atto	10^{-18}
f	femto	10^{-15}
p	pico	10^{-12}
n	nano	10^{-9}
u	micro	10^{-6}
m	mili	10^{-3}
k	kilo	10^3
x	mega	10^6
g	giga	10^9

Ex: 100 femptofarad capacitor = 100fF, 100f, 100e-15



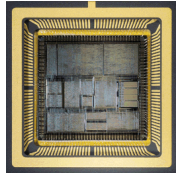
Circuit Simulation: User's Perspective





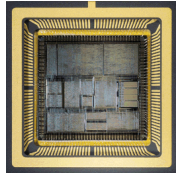
Simulators at Different Levels

- Simulators at different levels of abstraction :
 - Process
 - Circuit
 - Logic
- **Process Simulator:** Time and temperature effect on physical and electrical characteristics.
- **Circuit Simulator:** Use device model and netlist to predict current, voltage, and performance.
- **Logic Simulator:** Functional prediction of digital circuits for logical correctness.



Device Models

- SPICE uses wide variety of transistor models with different trade-offs between complexity and accuracy.
- Different models:
 - Level 1 (simple)
 - Level 2 (simple)
 - Level 3 (simple)
 - BSIM 1 (Berkley Short-Channel Insulated-Gate-FET Model)
 - BSIM 2 (very elaborate)
 - BSIM 3 (very elaborate)
 - BSIM 4 (current, most elaborate)

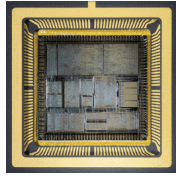


Device Models : Level 1

- Closely related to the Shockley model
- Enhanced with channel length modulation and the body effect.
- The parameters from the SPICE model are in CAPS.
- The threshold voltage is modulation by the source-to-body voltage (V_{sb}) due to body effect is taken into account.
- Gate capacitance is calculated from the oxide thickness TOX.

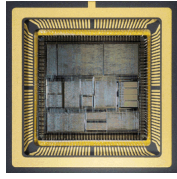
```
.model NMOS NMOS (LEVEL=1 TOX=40e-10 KP=155E-6 LAMBDA=0.2  
+  
+ VTO=0.4 PHI=0.93 GAMMA=0.6  
+ CJ=9.8E-5 PB=0.72 MJ=0.36  
+ CJSW=2.2E-10 PHP=7.5 MJSW=0.1)
```

Sample Level 1 MODEL card



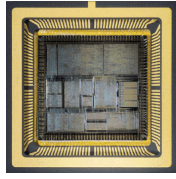
Device Models : Level 2 and Level 3

- Account effects of :
 - Velocity Saturation
 - Mobility Degradation
 - Subthreshold Conduction
 - Drain-Induced Barrier Lowering
- Still not good enough to mimic the characteristics of the modern devices.



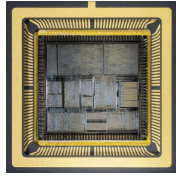
Device Models : BSIM

- Features of version 3v3:
 - Continuous and differentiable I-V characteristics for different regions of operation for good convergence.
 - Sensitivity of V_{th} etc to length and width
 - V_{th} model include body effect and DIBL.
 - Velocity saturation, mobility degradation, etc.
 - Multiple gate capacitance
 - Diffusion capacitance and resistance models
- Features of version 4:
 - Tunneling current
 - High-K dielectric



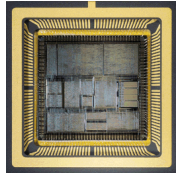
Supported Analysis by SPICE

- Types of Analysis
 - DC Analysis
 - AC Small-Signal Analysis
 - Transient Analysis
 - Pole-Zero Analysis
 - Small-Signal Distortion Analysis
 - Sensitivity Analysis
 - Noise Analysis



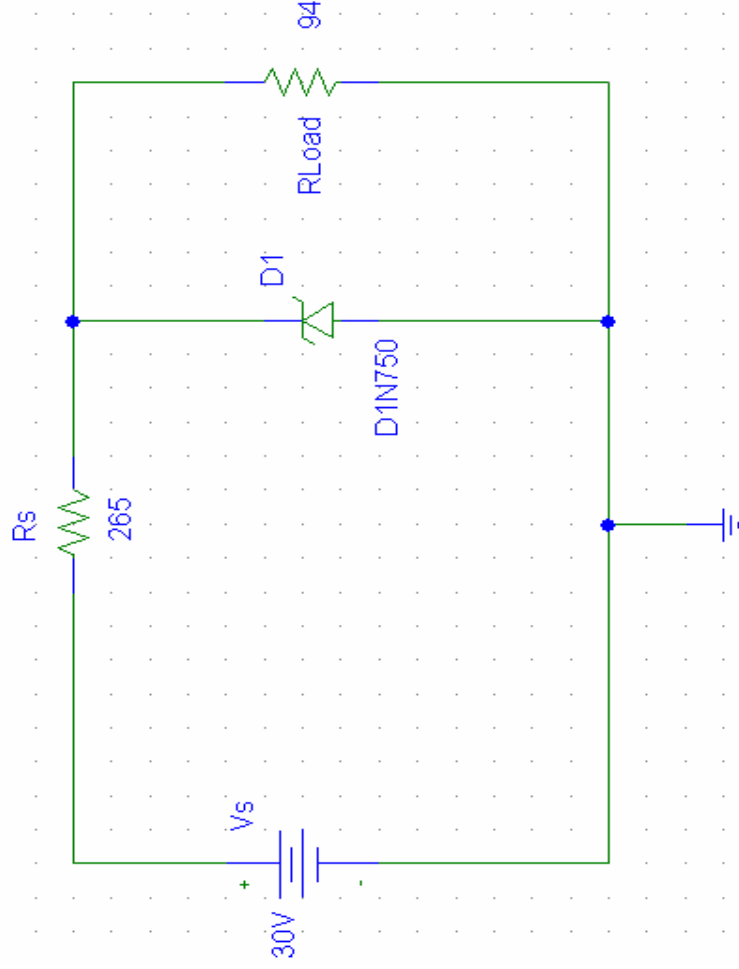
Analysis : DC

- The dc analysis portion of SPICE determines the dc operating point of the circuit with inductors shorted and capacitors opened.
- The dc analysis options are specified on the .DC, .TF, and .OP control lines.
- A dc analysis is automatically performed prior to a transient analysis to determine the transient initial conditions, and prior to an ac small-signal analysis to determine the linearized, small-signal models for nonlinear devices.



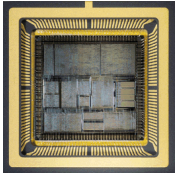
Analysis: DC, Example

Question: Voltage across RLoad as V_s varies from 20V to 30V.

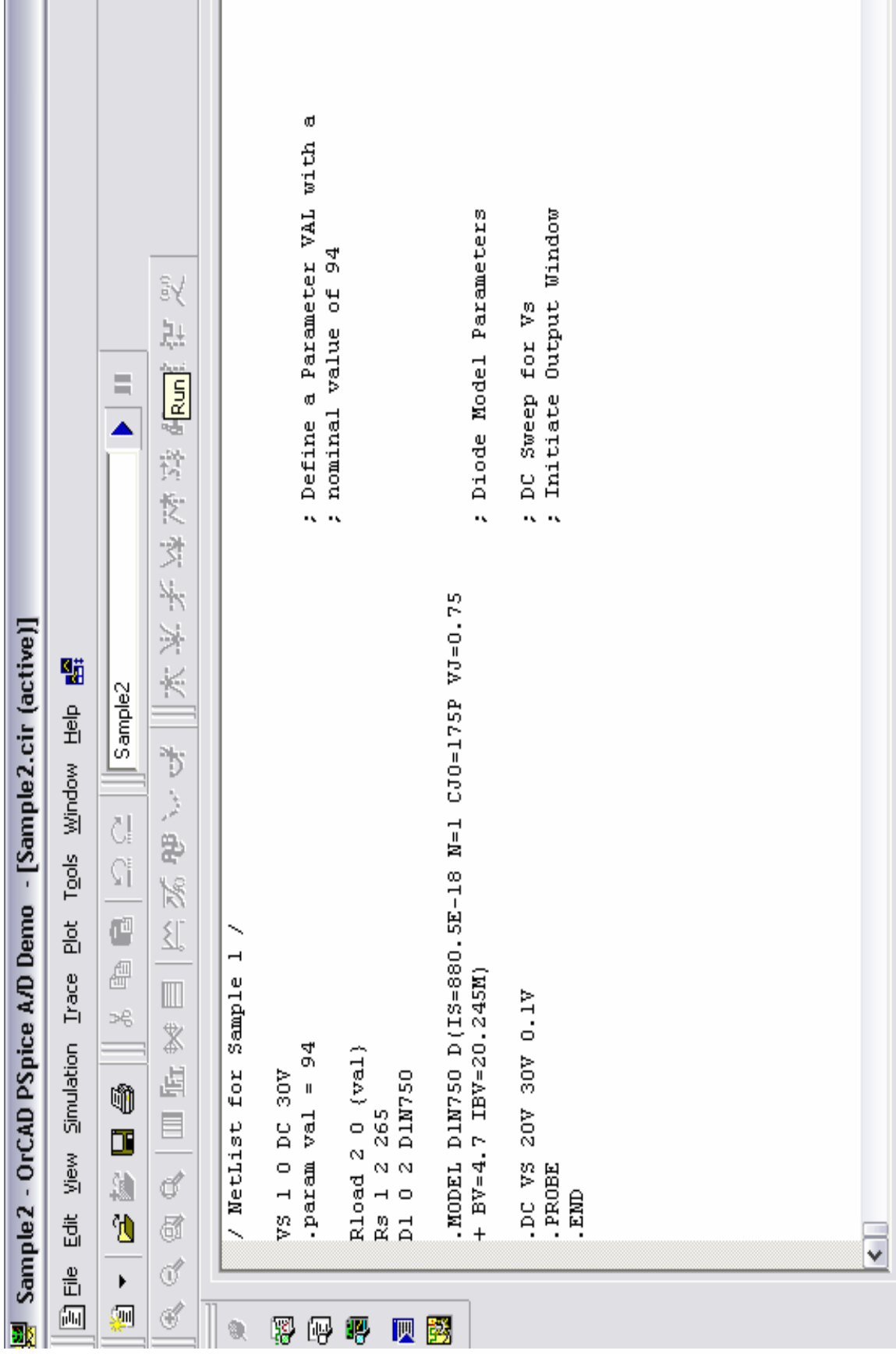


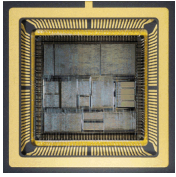
What is the voltage across RLoad as V_s varies from 20V to 30V?

This circuit can be analyzed using Schematic and Net list [Manual Coding].

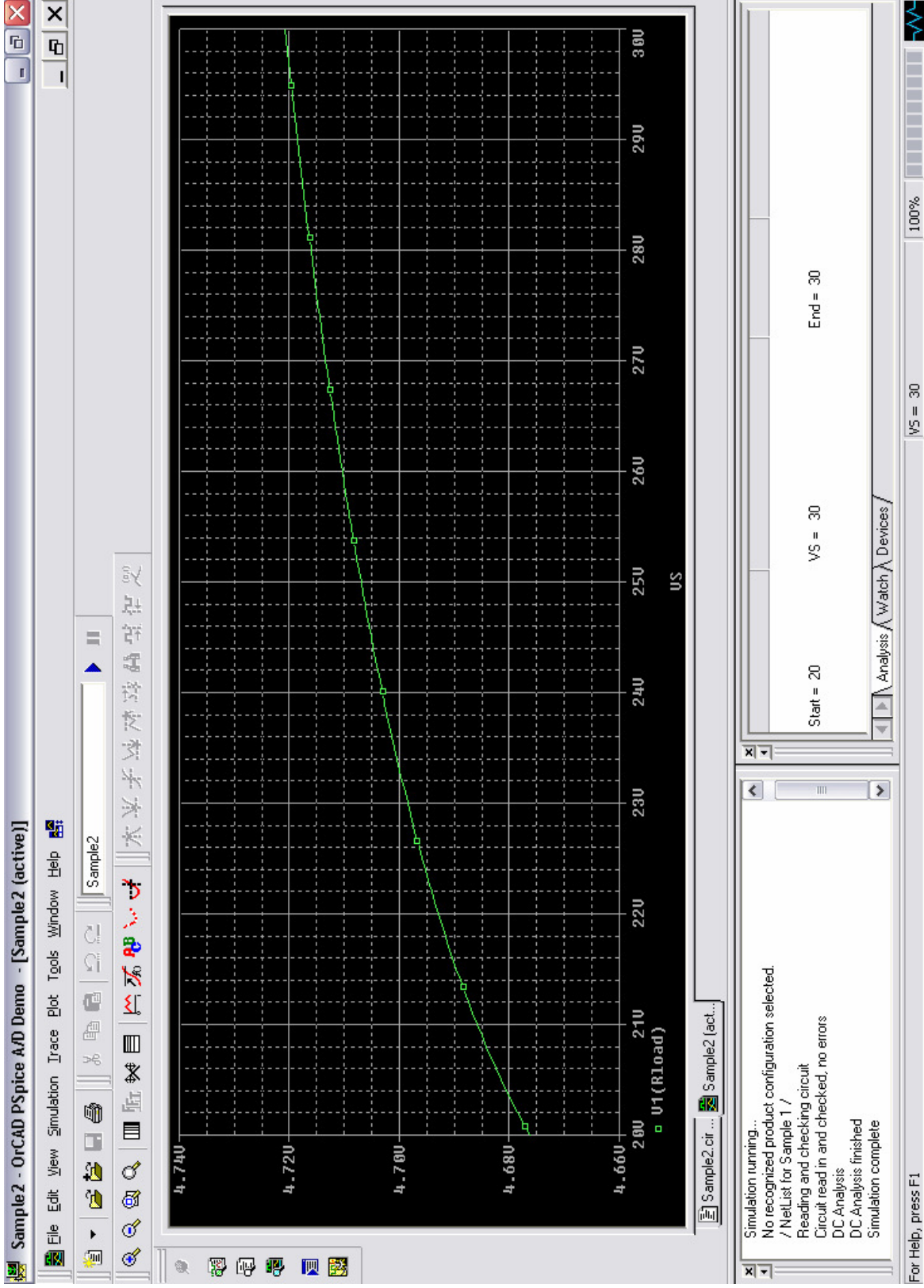


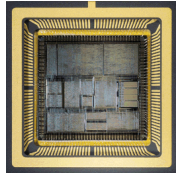
Analysis: DC, Example ...





Analysis: DC, Example ...



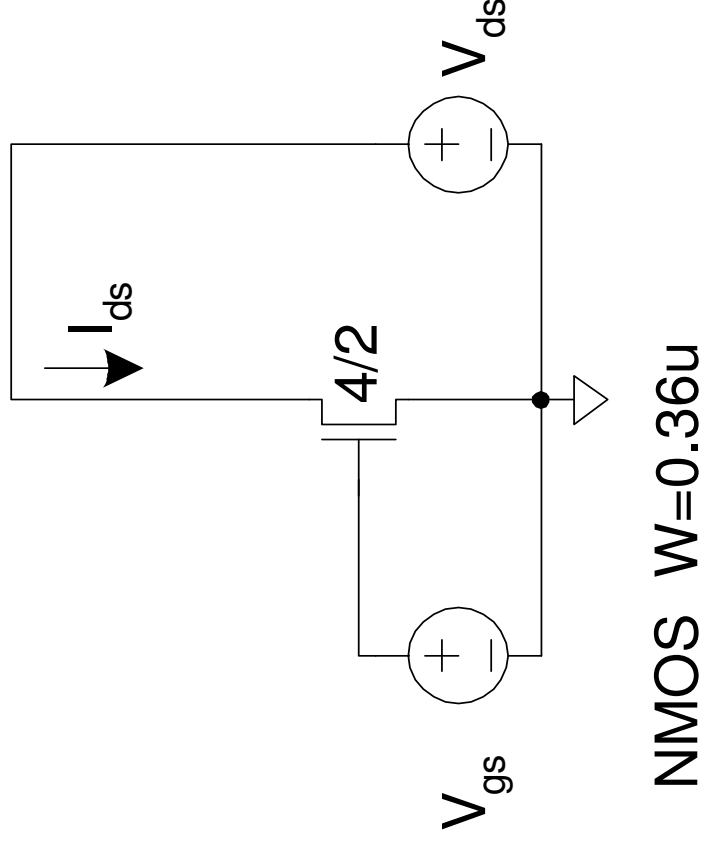


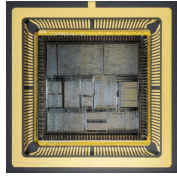
Transistor DC Analysis

```

* mosiv.sp
* -----
* Parameters and models
* -----
.include '../models/tsmc180/models.sp'
.temp 70
.option post
* -----
* Simulation netlist
* -----
*nmos
Vgs g gnd 0
Vds d gnd 0
M1 d g L=0.18u NMOS W=0.36u
* -----
* Stimulus
* -----
.dc Vds 0 1.8 0.05 SWEEP Vgs 0 1.8 0.3
.end

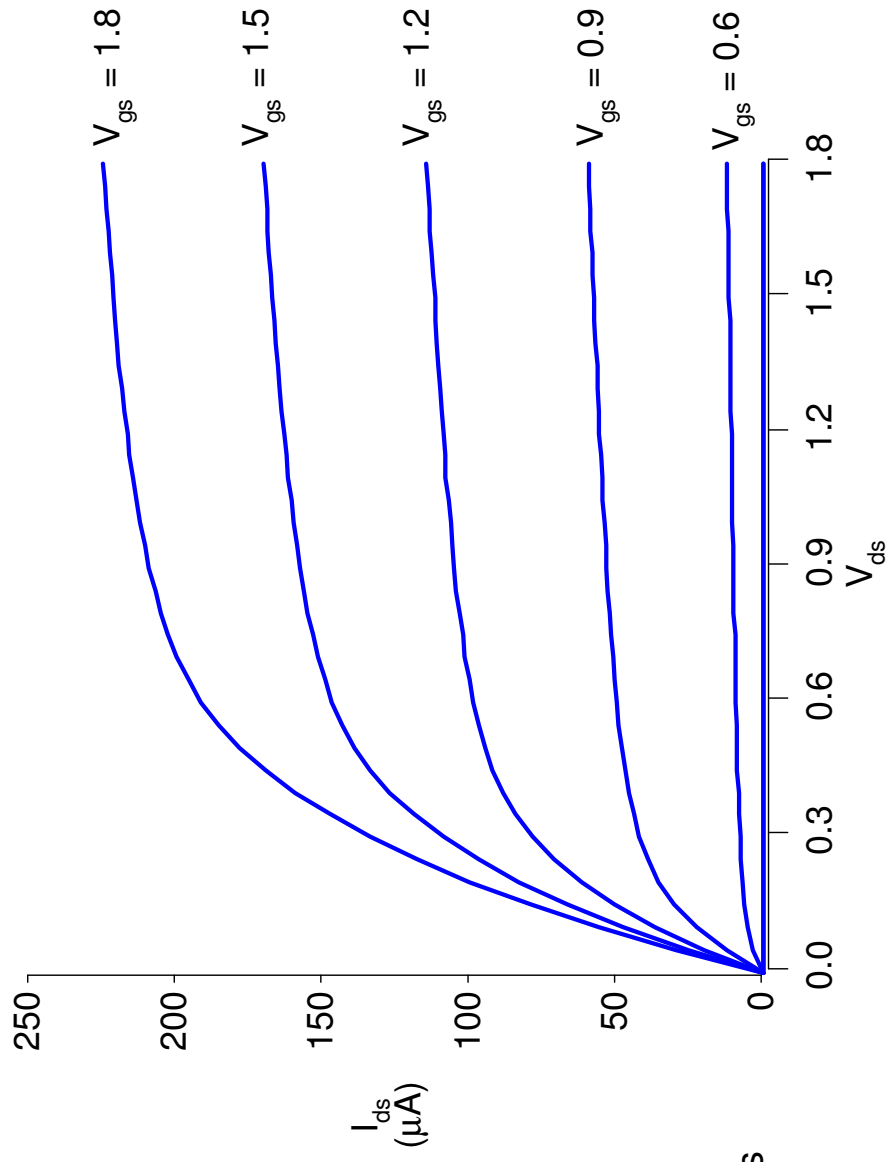
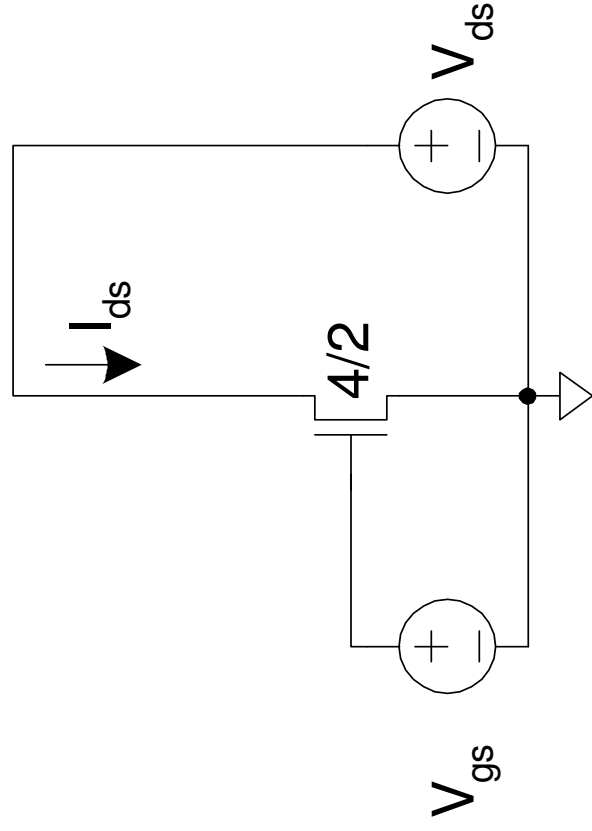
```



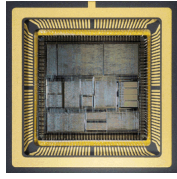


Transistor DC Analysis

- NMOS I-V
 - V_{gs} dependence
 - Saturation

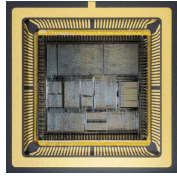


I-V characteristics



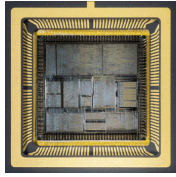
Analysis: AC Small Signal

- The ac small-signal portion of SPICE computes the ac output variables as a function of frequency.
- The ac analysis options are specified on the .AC control lines.
- The program first computes the dc operating point of the circuit and determines linearized, small-signal models for all of the nonlinear devices in the circuit.



Analysis: Transient

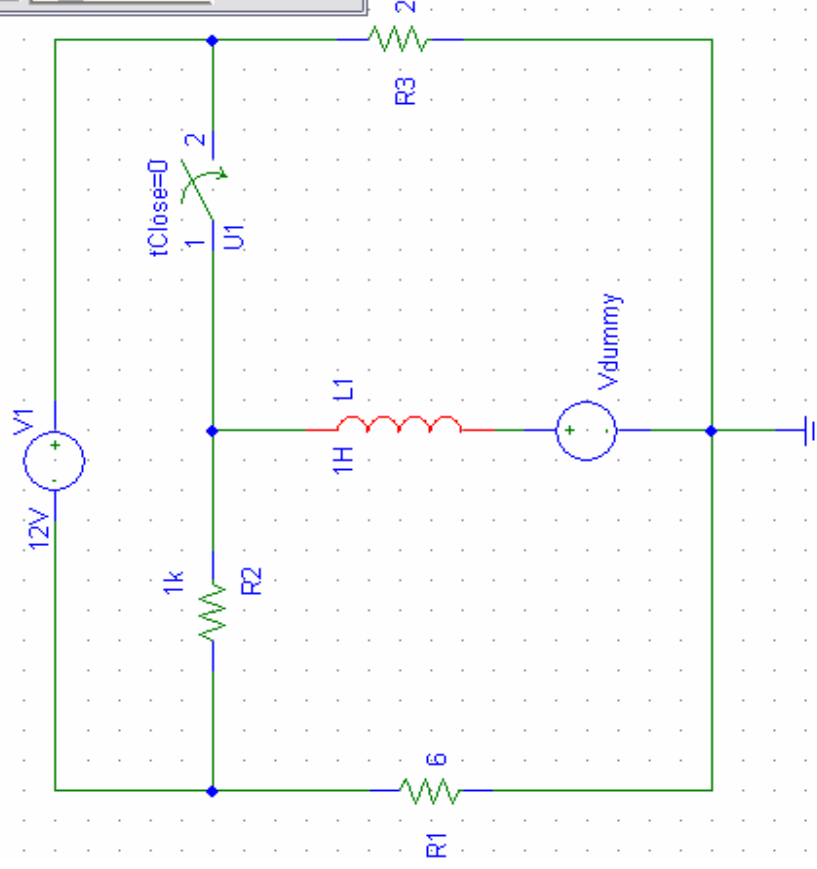
- The transient analysis portion of SPICE computes the transient output variables as a function of time over a user-specified time interval.
- The transient time interval is specified on a .TRAN control line.
- The initial conditions are automatically determined by a dc analysis.



Analysis: Transient, Example

Question: Find V_{out} at $t > 0$

Do Hand Calculation for current through Inductor at $t < 0$

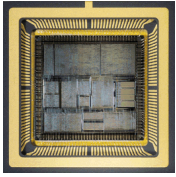


L1 PartName: L

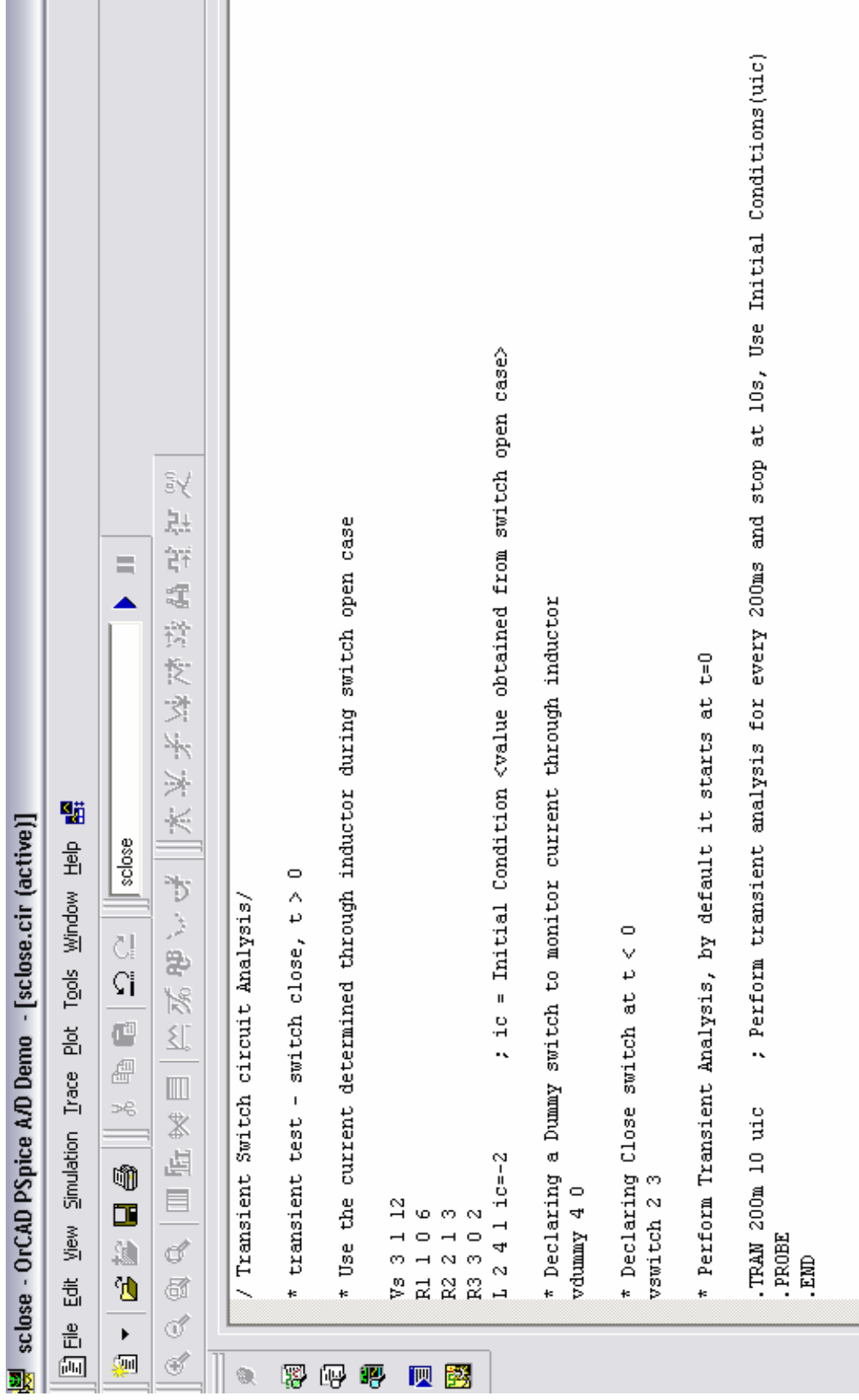
Name	Value
IC	= -2
VALUE	= 1H
IC	= -2
REFDES	= L1
TEMPLATE	= L^@REFDES %1 %2 ?TOLERANCEIL^@REFDES
PART	= L
TOLERANCE	=
PKGTYPE	= L2012C

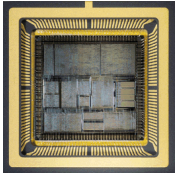
☒ Include Non-changeable Attributes
☒ Include System-defined Attributes

OK Cancel

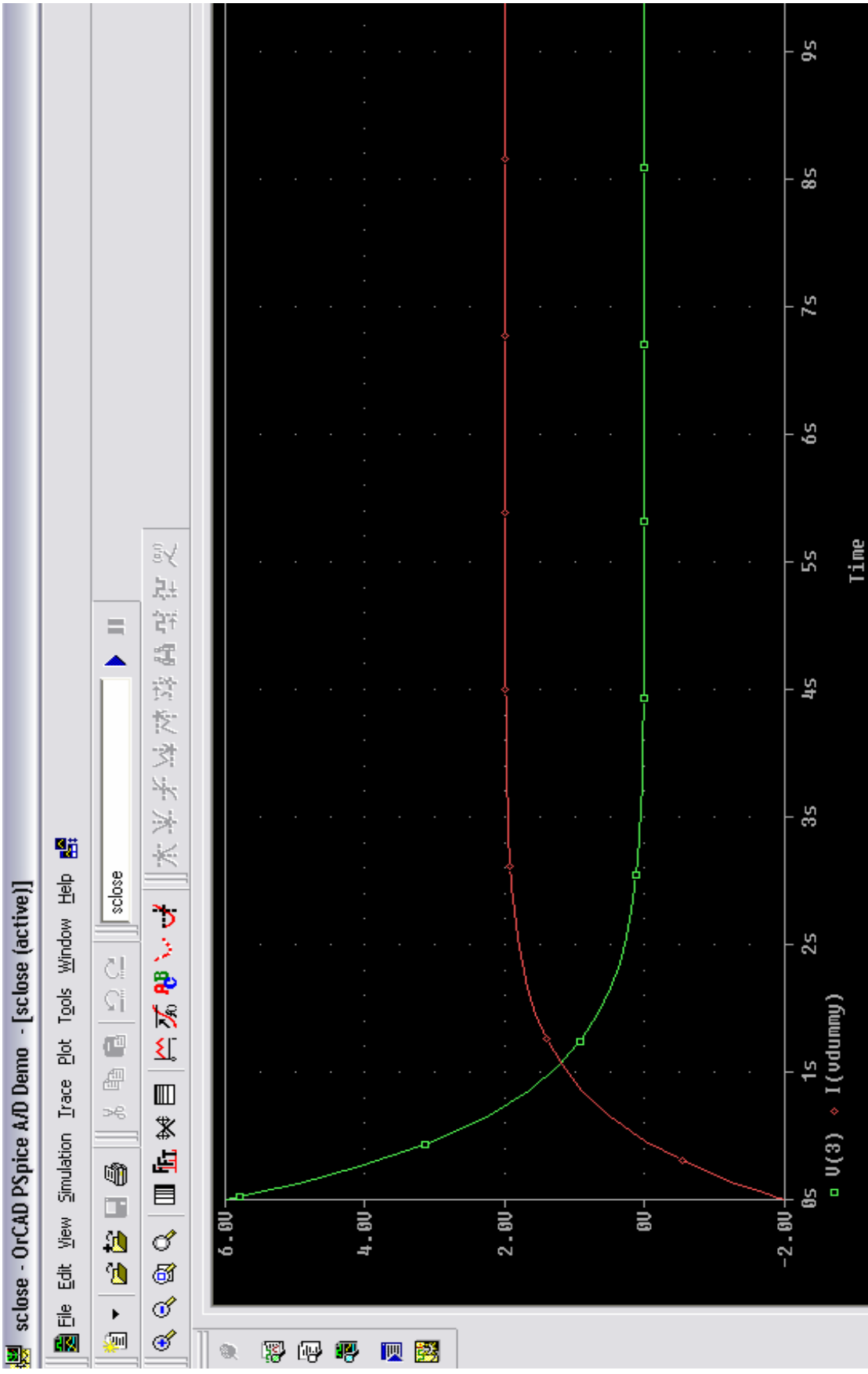


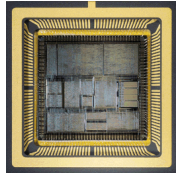
Analysis: Transient, Example





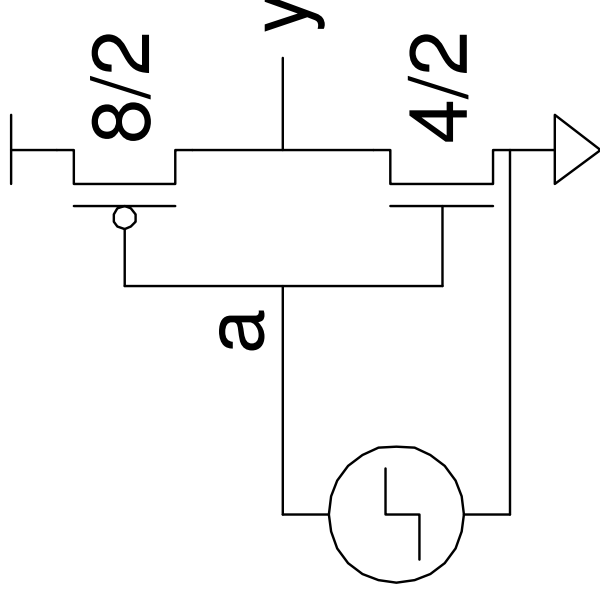
Analysis: Transient, Example

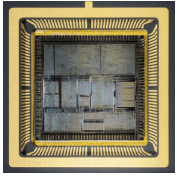




Inverter Transient Analysis

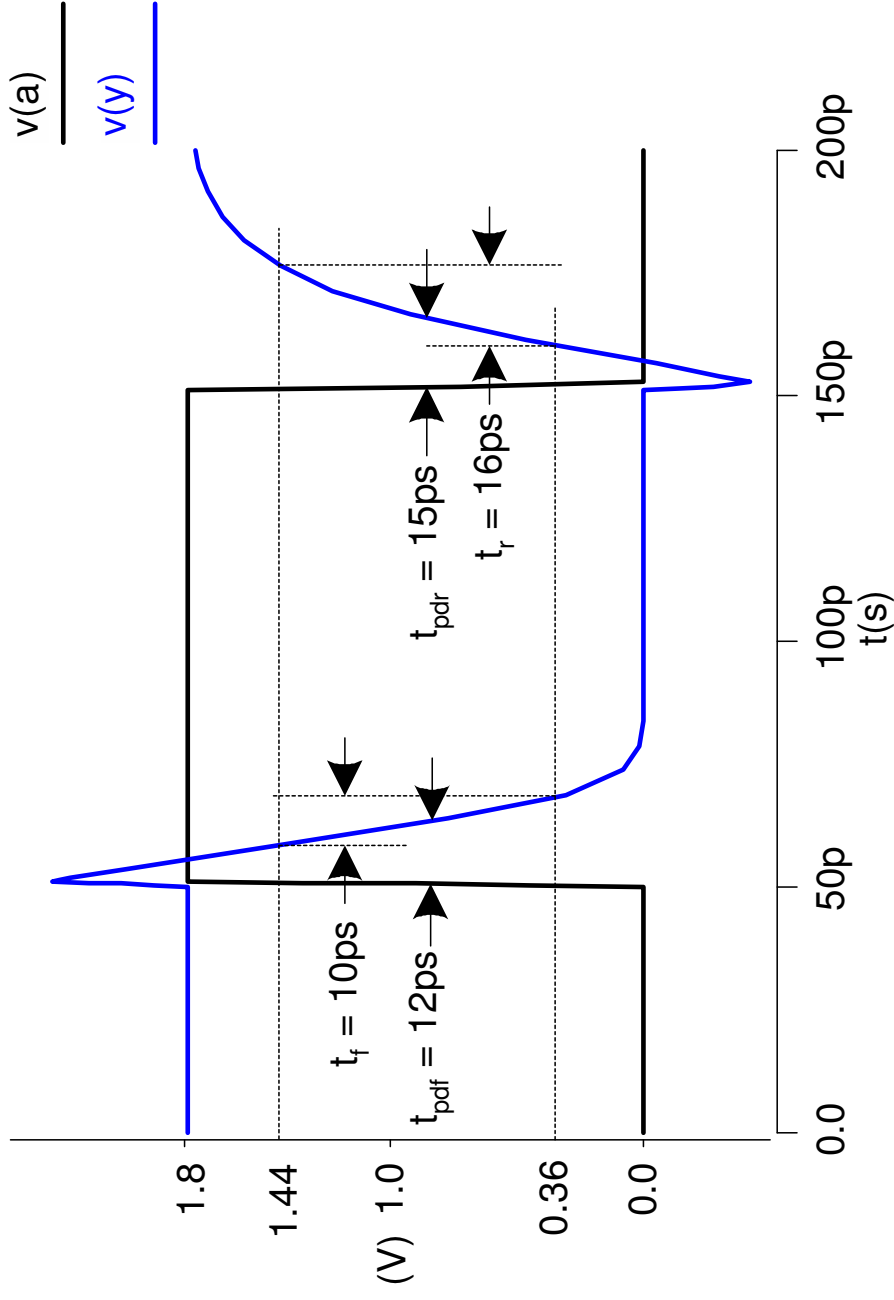
```
* inv.sp
* Parameters and models
* -----
.param SUPPLY=1.8
.option scale=90n
.include './models/tsmc180/models.sp'
.temp 70
.option post
* Simulation netlist
* -----
Vdd vdd gnd 'SUPPLY'
Vin a gnd PULSE 0 'SUPPLY' 50ps 0ps 100ps 200ps
M1 y a gnd gnd NMOS W=4 L=2
+ AS=20 PS=18 AD=20 PD=18
M2 y a vdd vdd PMOS W=8 L=2
+ AS=40 PS=26 AD=40 PD=26
* Stimulus
* -----
.tran 1ps 200ps
.end
```

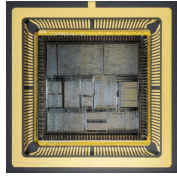




Inverter Transient Analysis

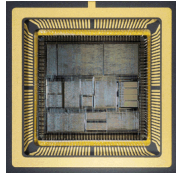
- Unloaded inverter
 - Overshoot
 - Very fast edges





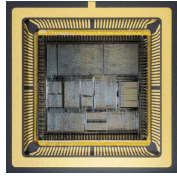
Analysis: Pole-Zero

- The pole-zero analysis portion of SPICE computes the poles and/or zeros in the small-signal ac transfer function.
- The program first computes the dc operating point and then determines the linearized, small-signal models for all the nonlinear devices in the circuit.
- Two types of transfer functions are allowed : one of the form $(\text{output voltage})/(\text{input voltage})$ and the other of the form $(\text{output voltage})/(\text{input current})$.



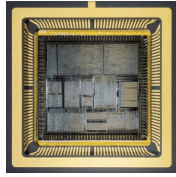
Analysis: Small-Signal Distortion

- The distortion analysis portion of SPICE computes steady-state harmonic and inter-modulation products for small input signal magnitudes.
- Distortion analysis is supported for the following nonlinear devices: diodes (DIO), BJT, JFET, MOSFETs (levels 1, 2, 3, 4/BSIM1, 5/BSIM2, and 6) and MESFETs.
- All linear devices are automatically supported by distortion analysis.

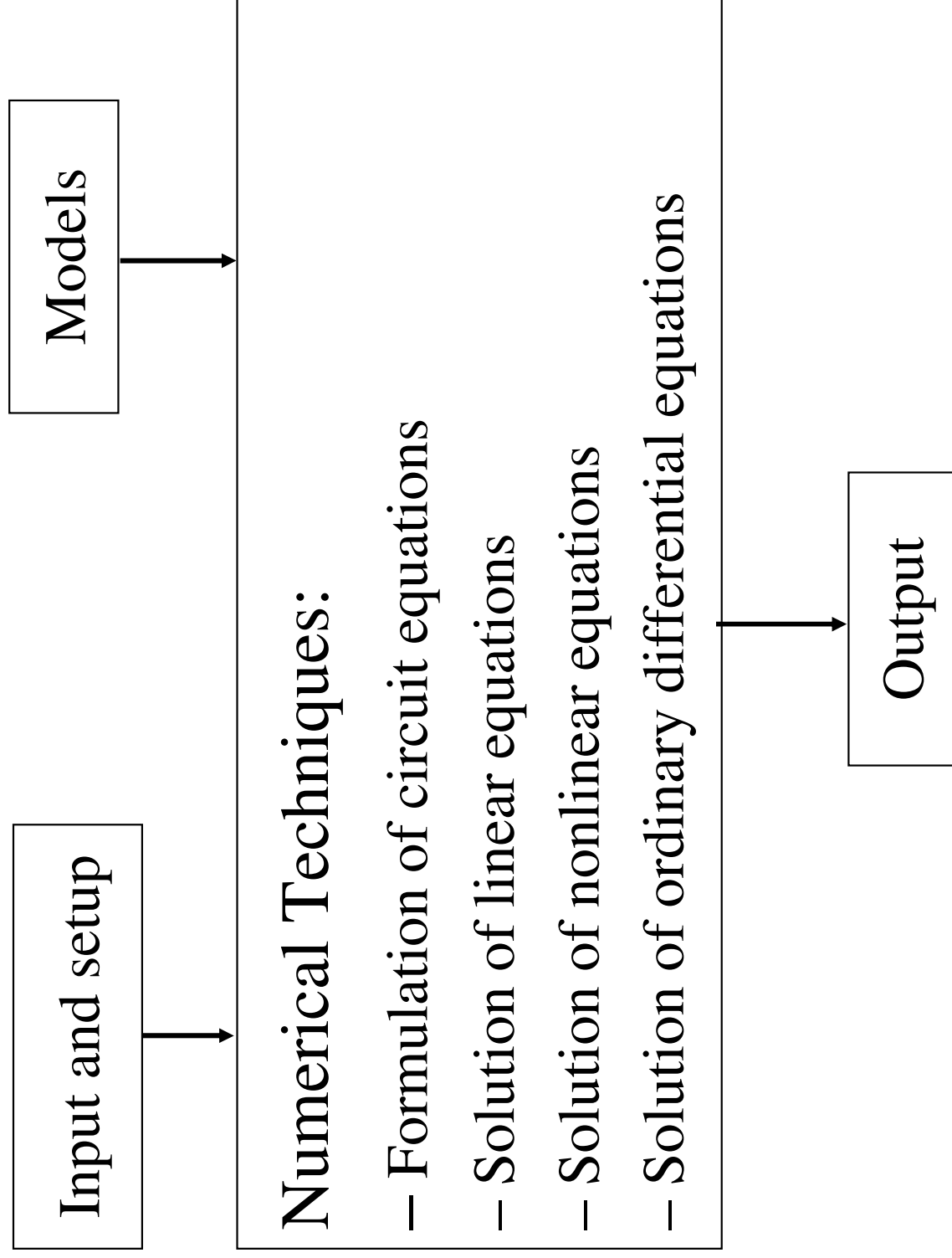


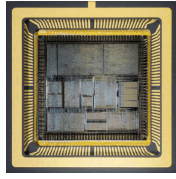
Noise Analysis

- The noise analysis portion of SPICE does analysis device-generated noise for the given circuit.
- When provided with an input source and an output port, the analysis calculates the noise contributions of each device (and each noise generator within the device) to the output port voltage.
- It also calculates the input noise to the circuit, equivalent to the output noise referred to the specified input source.

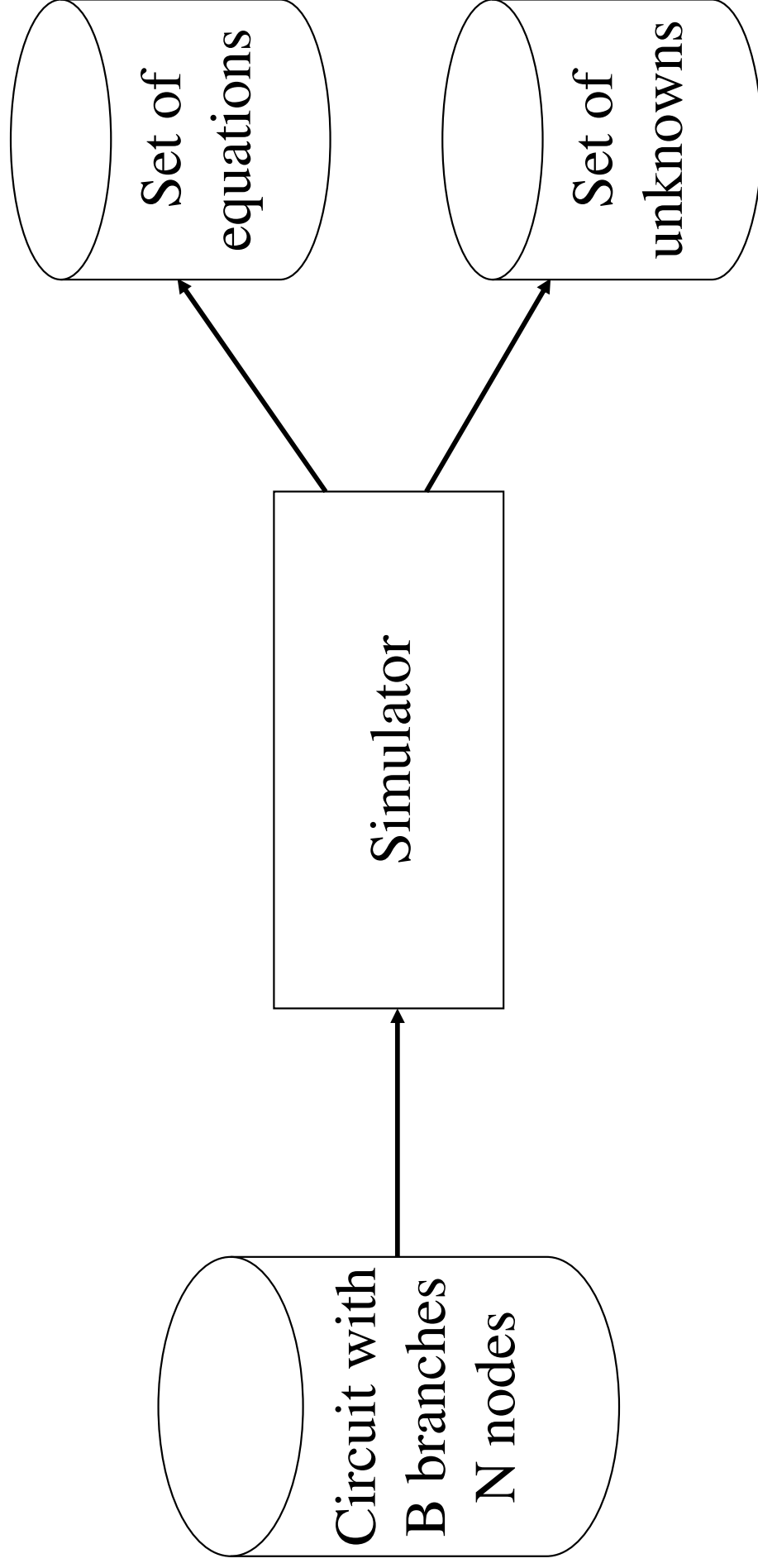


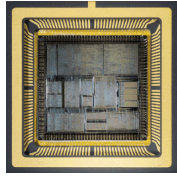
Program Structure (a closer look)





Formulation of Circuit Equations





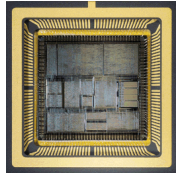
Formulation of Circuit Equations

- **Unknowns**

- B branch currents (i)
- $3636N$ node voltages (e)
- B branch voltages (v)

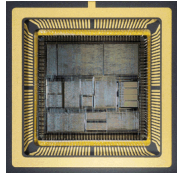
- **Equations**

- $N+B$ Conservation Laws
- B Constitutive Equations



Conservation Laws

- Determined by the topology of the circuit
 - Kirchhoff's Voltage Law (KVL): Every circuit node has a unique voltage with respect to the reference node. The voltage across a branch e_b is equal to the difference between the positive and negative referenced voltages of the nodes on which it is incident.
 - Kirchhoff's Current Law (KCL): The algebraic sum of all the currents flowing out of (or into) any circuit node is zero.

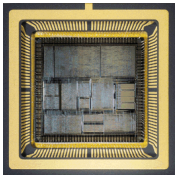


SPICE: Simplistic View

- Really, it's just all about solving KCL and KVL equations:

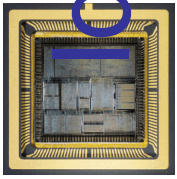
$$\sum I_k = 0, \quad \sum V_k = 0$$

- Generally, it's a nonlinear differential equation (e.g. transistors).
- Bunch of numerical algebra



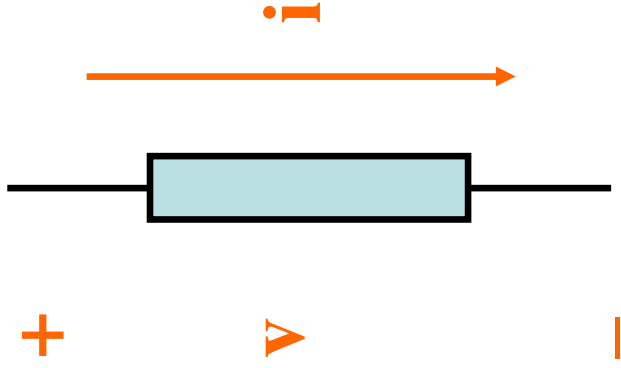
Branch Constitutive Equations (BCE)

- Determined by the mathematical model of the electrical behavior of a component
 - Example: $V=R \cdot I$
- In most of circuit simulators this mathematical model is expressed in terms of ideal elements

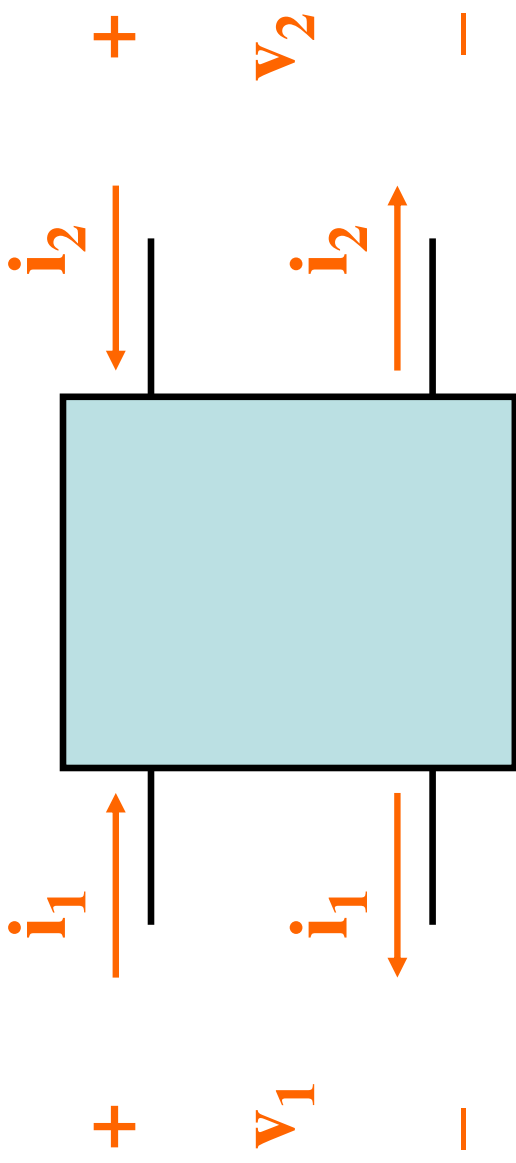


Ideal Elements: Reference Direction

Two-terminal

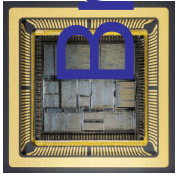


Two-port



Branch voltages and currents are measured according to the associated reference directions

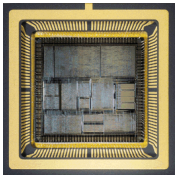
—Also define a reference node (ground)



Branch Constitutive Equations (BCE)

Ideal elements

Element	Branch Eqn
Resistor	$v = R \cdot i$
Capacitor	$i = C \cdot dv/dt$
Inductor	$v = L \cdot di/dt$
Voltage Source	$v = v_s, i = ?$
Current Source	$i = i_s, v = ?$
VCVS	$v_s = A_V \cdot v_c, i = ?$
VCCS	$i_s = G_T \cdot v_c, v = ?$
CCVS	$v_s = R_T \cdot i_c, i = ?$
CCCS	$i_s = A_I \cdot i_c, v = ?$



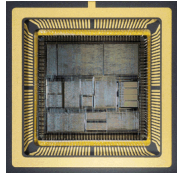
Analysis: AC Small Signal, Theory

We compute the tiny small signal current DI by using a Taylor series expansion about the bias point i.e.

$$I = f(v)$$

so

$$I_{dc} + DI = f(V_{dc}) + f'(V_{dc})DV$$

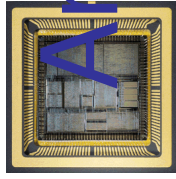


Analysis: AC Small Signal, Theory ...

- The problem is split into two parts
- A nonlinear dc part where there is no time variation, $I_{dc} = f(V_{dc})$
- A linear time-varying part

$$DI = f'(V_{dc})DV$$

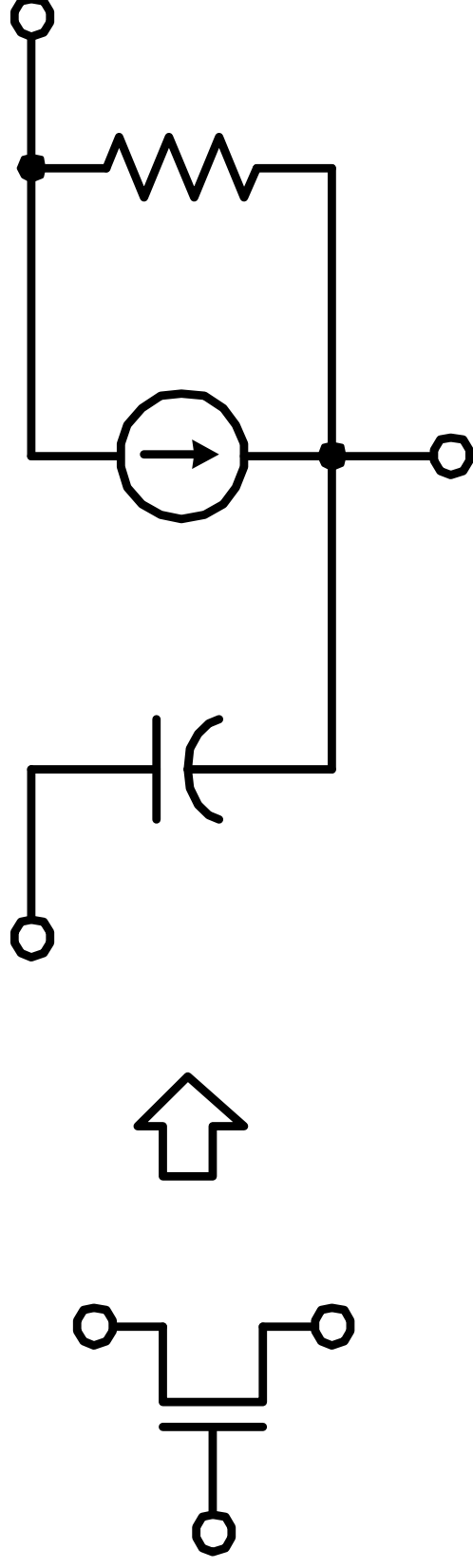
- The derivative is represented by a conductance or resistance in a small-signal equivalent circuit.

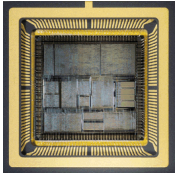


Analysis: AC Small Signal, Theory ...

First, Linearize it

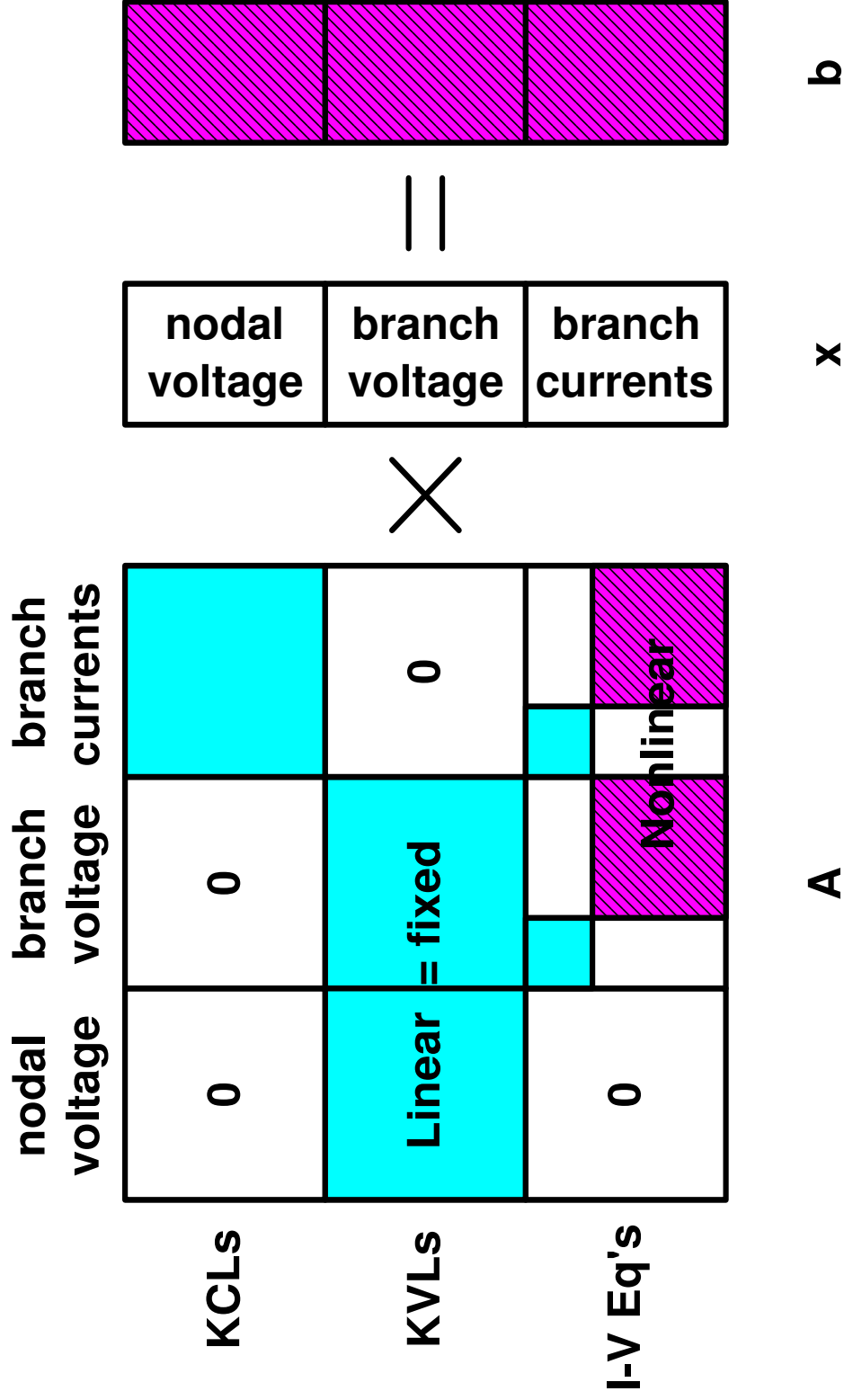
At each time step, SPICE builds a small-signal model (i.e. linear model) at the operating point:

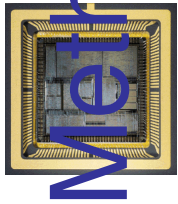




Matrix Equation

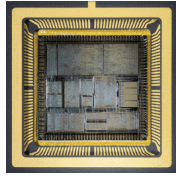
Construct a matrix equation : $Ax=b$





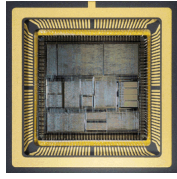
Methods for Linear & Non-Linear Systems

- Systems of linear equations
 - Existence and uniqueness review
 - Gaussian Elimination basics
 - LU factorization
 - Pivoting
- Nonlinear problems
- Iterative Methods
- Newton's Method
 - Derivation of Newton
 - Quadratic Convergence
 - Examples



Systems of Linear Equations

- Problem to solve: $Mx = b$
- Given $Mx = b$:
 - Is there a solution?
 - Is the solution unique?



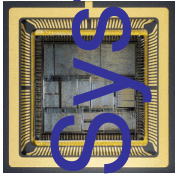
Systems of Linear Equations ...

$$\begin{array}{c} \uparrow \quad \quad \uparrow \quad \quad \uparrow \\ \vec{M}_1 \quad \quad \dots \quad \quad \vec{M}_N \\ \downarrow \quad \quad \downarrow \quad \quad \downarrow \end{array} \begin{bmatrix} x_1 \\ x_2 \\ \vdots \\ x_N \end{bmatrix} = \begin{bmatrix} b_1 \\ b_2 \\ \vdots \\ b_N \end{bmatrix}$$

→

$$x_1 \vec{M}_1 + x_2 \vec{M}_2 + \dots + x_N \vec{M}_N = b$$

Find a set of weights x so that the weighted sum of the columns of the matrix M is equal to the right hand side b



Systems of Linear Equations - Existence

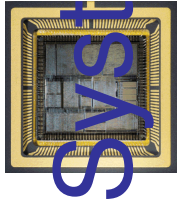
A solution exists if:

There exist weights, x_1, \dots, x_N , such that:

$$\vec{x_1 M_1} + \vec{x_2 M_2} + \dots + \vec{x_N M_N} = \vec{b}$$



A solution exists when \vec{b} is in the span of the columns of M



Systems of Linear Equations - Uniqueness

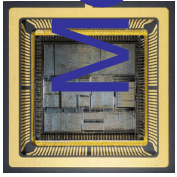
Suppose there exist weights, y_1, \dots, y_N , not all zero, such that:

$$y_1 \vec{M}_1 + y_2 \vec{M}_2 + \dots + y_N \vec{M}_N = \vec{0}$$

$$\text{Then: } Mx = b \rightarrow Mx + My = b \rightarrow M(x+y) = b$$

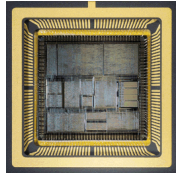


A solution is unique only if the columns of M are linearly independent.



Methods for Solving Linear Equations

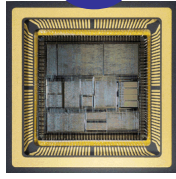
- **Direct methods:** find the exact solution in a finite number of steps
- **Iterative methods:** produce a sequence of approximate solutions hopefully converging to the exact solution



Gaussian Elimination Basics

Gaussian Elimination Method for Solving $M \times b$

- A “Direct” Method Finite Termination for exact result (ignoring round-off)
- Produces accurate results for a broad range of matrices
- Computationally Expensive



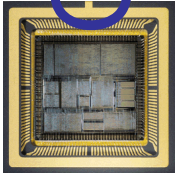
Gaussian Elimination (GE) Basics

Reminder by 3x3 example

$$\begin{bmatrix} M_{11} & M_{12} & M_{13} \\ M_{21} & M_{22} & M_{23} \\ M_{31} & M_{32} & M_{33} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} b_1 \\ b_2 \\ b_3 \end{bmatrix}$$



$$\begin{aligned} M_{11}x_1 + M_{12}x_2 + M_{13}x_3 &= b_1 \\ M_{21}x_1 + M_{22}x_2 + M_{23}x_3 &= b_2 \\ M_{31}x_1 + M_{32}x_2 + M_{33}x_3 &= b_3 \end{aligned}$$



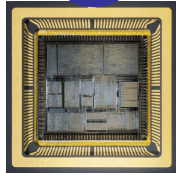
GE Basics – Key idea in the matrix

Remove x_1 from eqn 2 and eqn 3

Pivot M_{11}

MULTIPLIERS

$$\begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix} \begin{bmatrix} M_{11} \\ M_{12} \\ M_{13} \end{bmatrix} \begin{bmatrix} \left(M_{22} - \left(\frac{M_{21}}{M_{11}} \right) M_{12} \right) \\ \left(M_{32} - \left(\frac{M_{31}}{M_{11}} \right) M_{12} \right) \\ \left(M_{23} - \left(\frac{M_{21}}{M_{11}} \right) M_{13} \right) \\ \left(M_{33} - \left(\frac{M_{31}}{M_{11}} \right) M_{13} \right) \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} b_1 \\ b_2 - \left(\frac{M_{21}}{M_{11}} \right) b_1 \\ b_3 - \left(\frac{M_{31}}{M_{11}} \right) b_1 \end{bmatrix}$$

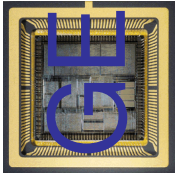


GE Basics – Simplify the Notation

Remove x2 from eqn 3

$$\begin{bmatrix} M_{11} & M_{12} & M_{13} \\ 0 & \tilde{M}_{22} & \tilde{M}_{23} \\ 0 & 0 & \tilde{M}_{33} - \frac{\tilde{M}_{32} \tilde{M}_{23}}{\tilde{M}_{22}} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} b_1 \\ \tilde{b}_2 \\ \tilde{b}_3 - \frac{\tilde{M}_{32} \tilde{b}_2}{\tilde{M}_{22}} \end{bmatrix}$$

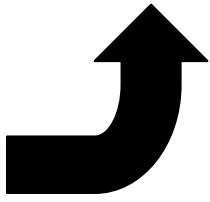
Pivot (points to \tilde{M}_{22}) Multiplier (points to $\frac{\tilde{M}_{32} \tilde{M}_{23}}{\tilde{M}_{22}}$)



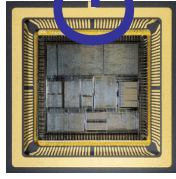
Basics – Yielding Triangular System

$$\begin{bmatrix} M_{11} & M_{12} & M_{13} \\ 0 & \tilde{M}_{22} & \tilde{M}_{23} \\ 0 & 0 & \tilde{M}_{33} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} b_1 \\ \tilde{b}_2 \\ \tilde{b}_3 \end{bmatrix}$$

Altered During GE

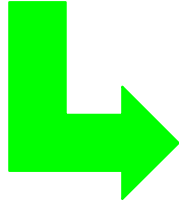


$$\begin{bmatrix} U_{11} & U_{12} & U_{13} \\ 0 & U_{22} & U_{23} \\ 0 & 0 & U_{33} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} y_1 \\ y_2 \\ y_3 \end{bmatrix}$$



GE Basics – Backward Substitution

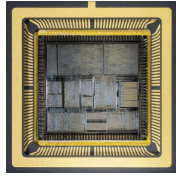
$$\begin{bmatrix} U_{11} & U_{12} & U_{13} \\ 0 & U_{22} & U_{23} \\ 0 & 0 & U_{33} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} y_1 \\ y_2 \\ y_3 \end{bmatrix}$$



$$x_3 = \frac{y_3}{U_{33}}$$

$$x_2 = \frac{y_2 - U_{23}x_3}{U_{22}}$$

$$x_1 = \frac{y_1 - U_{12}x_2 - U_{13}x_3}{U_{11}}$$



GE Basics: Summary

(1) $Mx = b$
GE
 $Ux = y$

Equivalent system

U : upper trg

$$Ly = b$$

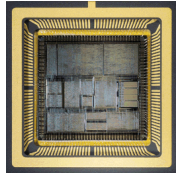
L : unit lower trg

(2) Noticed that:

(3) $Ux = y$

$$LUx = b \rightarrow Mx = b$$

\Rightarrow Efficient way of implementing GE: LU factorization



Gaussian Elimination Basics

Solve $Mx = b$

Step 1

$$M = LU$$

$$\square = \begin{array}{c} \square \\ \square \end{array} \circ \begin{array}{c} \square \\ \square \end{array}$$

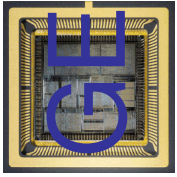
Step 2 Forward Elimination

Solve $Ly = b$

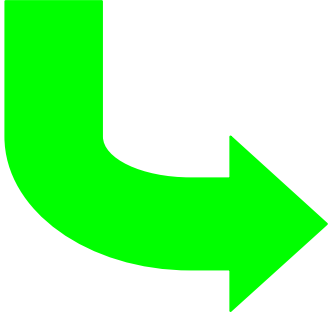
Step 3 Backward Substitution

Solve $Ux = y$

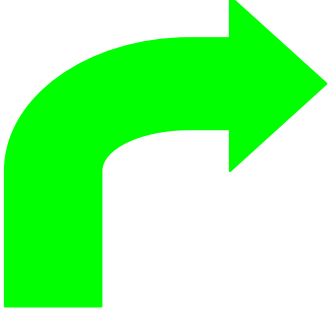
Note: Changing RHS does not imply to recompute LU factorization



Basics – Fitting the Pieces Together

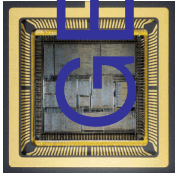


$$\begin{bmatrix} M_{11} & M_{12} & M_{13} \\ M_{21} & M_{22} & M_{23} \\ M_{31} & M_{32} & M_{33} \end{bmatrix}$$



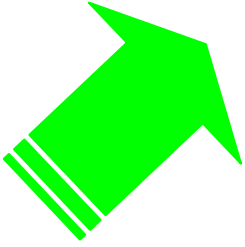
$$L = \begin{bmatrix} 1 & 0 & 0 & 1 \\ \frac{M_{21}}{M_{11}} & 1 & 0 & \\ \frac{M_{31}}{M_{11}} & \frac{M_{32}}{M_{11}} & 1 & \\ \frac{M_{21}}{M_{11}} & \frac{M_{32}}{M_{11}} & \frac{M_{23}}{M_{11}} & \frac{M_{33}}{M_{11}} \end{bmatrix}$$

$$U = \begin{bmatrix} M_{11} & M_{12} & M_{13} \\ 0 & M_{22} & M_{23} \\ 0 & 0 & M_{33} \end{bmatrix}$$



Basics – Fitting the Pieces Together

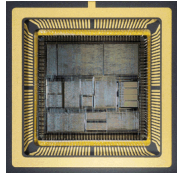
$$L = \begin{bmatrix} 1 & 0 & 0 \\ \frac{M_{21}}{M_{11}} & 1 & 0 \\ \frac{M_{31}}{M_{11}} & \frac{M_{32}}{M_{11}} & 1 \end{bmatrix}$$



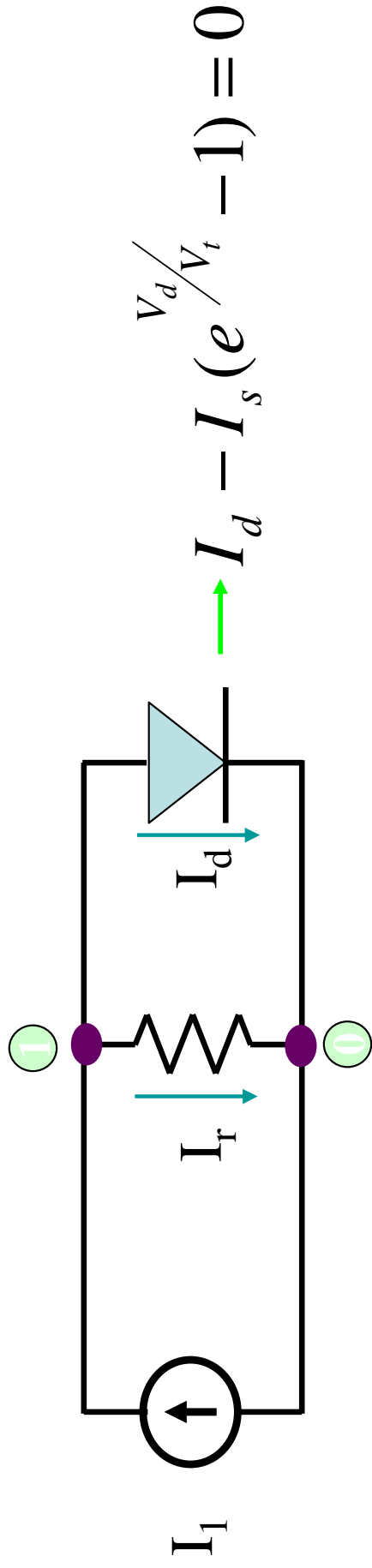
$$U = \begin{bmatrix} M_{11} & M_{12} & M_{13} \\ 0 & \tilde{M}_{22} & \tilde{M}_{23} \\ 0 & 0 & \approx M_{33} \end{bmatrix}$$



$$\begin{bmatrix} M_{11} & M_{21} & M_{31} \\ \frac{M_{21}}{M_{11}} & \tilde{M}_{22} & \tilde{M}_{23} \\ \frac{M_{31}}{M_{11}} & \frac{M_{32}}{M_{11}} & \approx M_{33} \end{bmatrix}$$



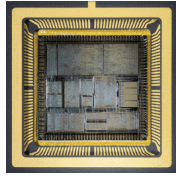
Nonlinear Problems - Example



Need to Solve

$$\boxed{I_r + I_d - I_1 = 0}$$

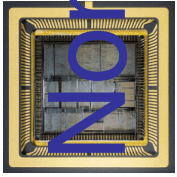
$$\frac{1}{R}e_1 + I_s(e^{e_1 \frac{V_t}{V_t}} - 1) - I_1 = 0 \quad \xrightarrow{\text{green arrow}} \quad g(e_1) = I_1$$



Nonlinear Equations

- Given $g(V)=I$
 - It can be expressed as: $f(V)=g(V)-I$
- \Rightarrow Solve $g(V)=I$ equivalent to solve $f(V)=0$
- Hard to find analytical solution for $f(x)=0$

Solve iteratively

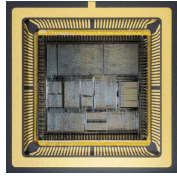


Nonlinear Equations – Iterative Methods

- Start from an initial value x^0
- Generate a sequence of iterate x^{n-1}, x^n, x^{n+1} which hopefully converges to the solution x^*
- Iterates are generated according to an iteration function $F: x^{n+1} = F(x^n)$

Ask

- When does it converge to correct solution ?
- What is the convergence rate ?



Newton-Raphson (NR) Method

Consists of linearizing the system.

Want to solve $f(x)=0 \rightarrow$ Replace $f(x)$ with its linearized version and solve.

$$f(x) = f(x^*) + \frac{df}{dx}(x^*)(x - x^*)$$

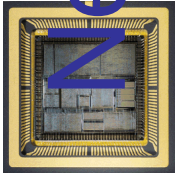
Taylor Series

$$f(x^{k+1}) = f(x^k) + \frac{df}{dx}(x^k)(x^{k+1} - x^k)$$

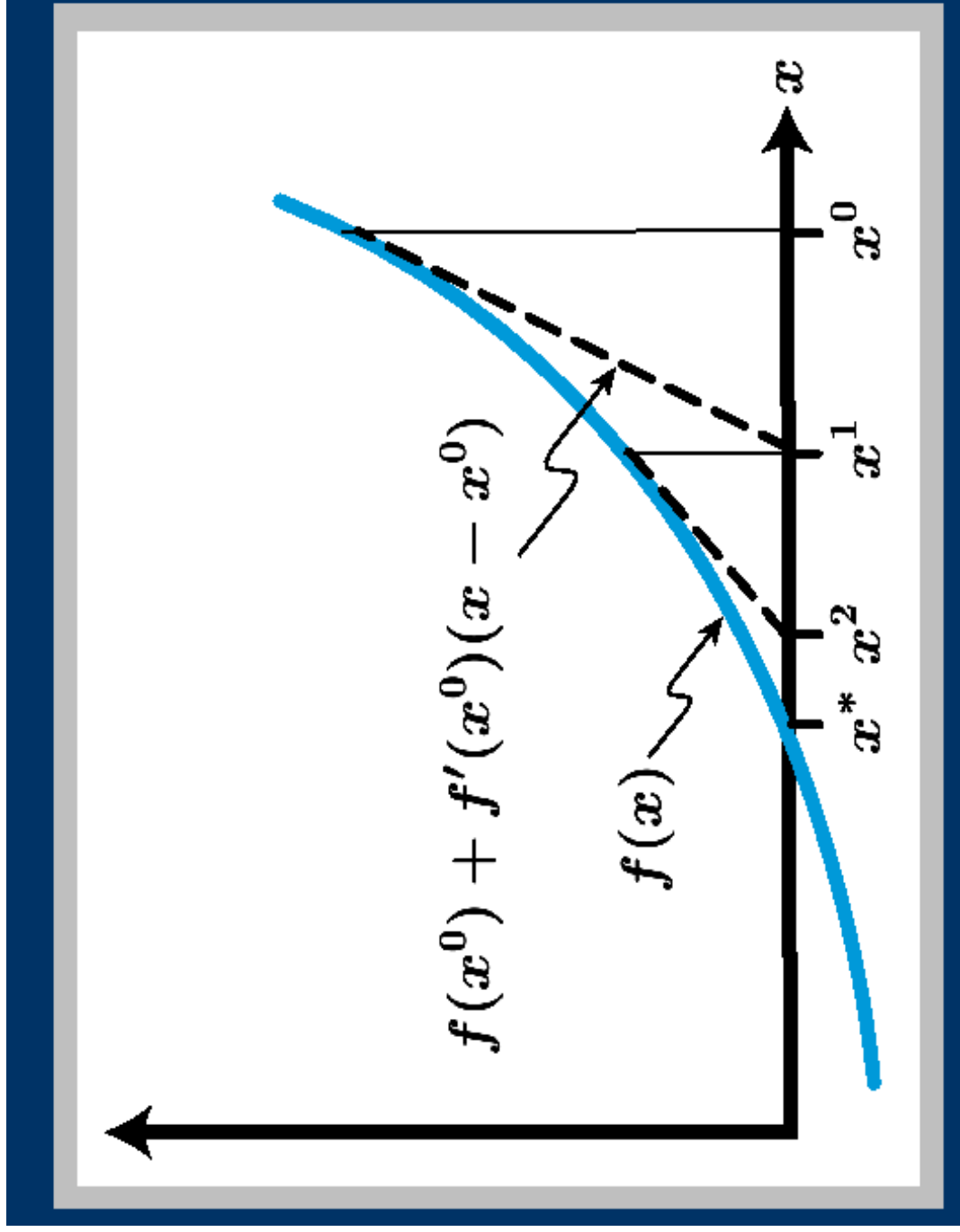
$$\Rightarrow x^{k+1} = x^k - \left[\frac{df}{dx}(x^k) \right]^{-1} f(x^k)$$

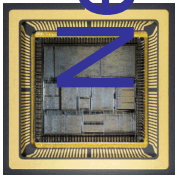
Iteration function

Note: at each step need to evaluate f and f'



Newton-Raphson Method – Graphical





Newton-Raphson Method – Algorithm

Define iteration

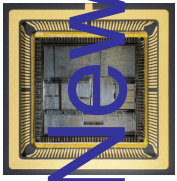
Do $k = 0$ to

$$x^{k+1} = x^k - \left[\frac{df}{dx}(x^k) \right]^{-1} f(x^k)$$

until convergence

- How about convergence?
- An iteration $\{x^{(k)}\}$ is said to converge with order q if there exists a vector norm such that for each $k \geq N$:

$$\|x^{k+1} - \hat{x}\| \leq \|x^k - \hat{x}\|^q$$



Newton-Raphson Method – Convergence

Local Convergence Theorem

If

a) $\frac{df}{dx}$

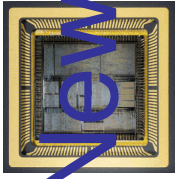
bounded away from zero

b) $\frac{d^2f}{dx^2}$

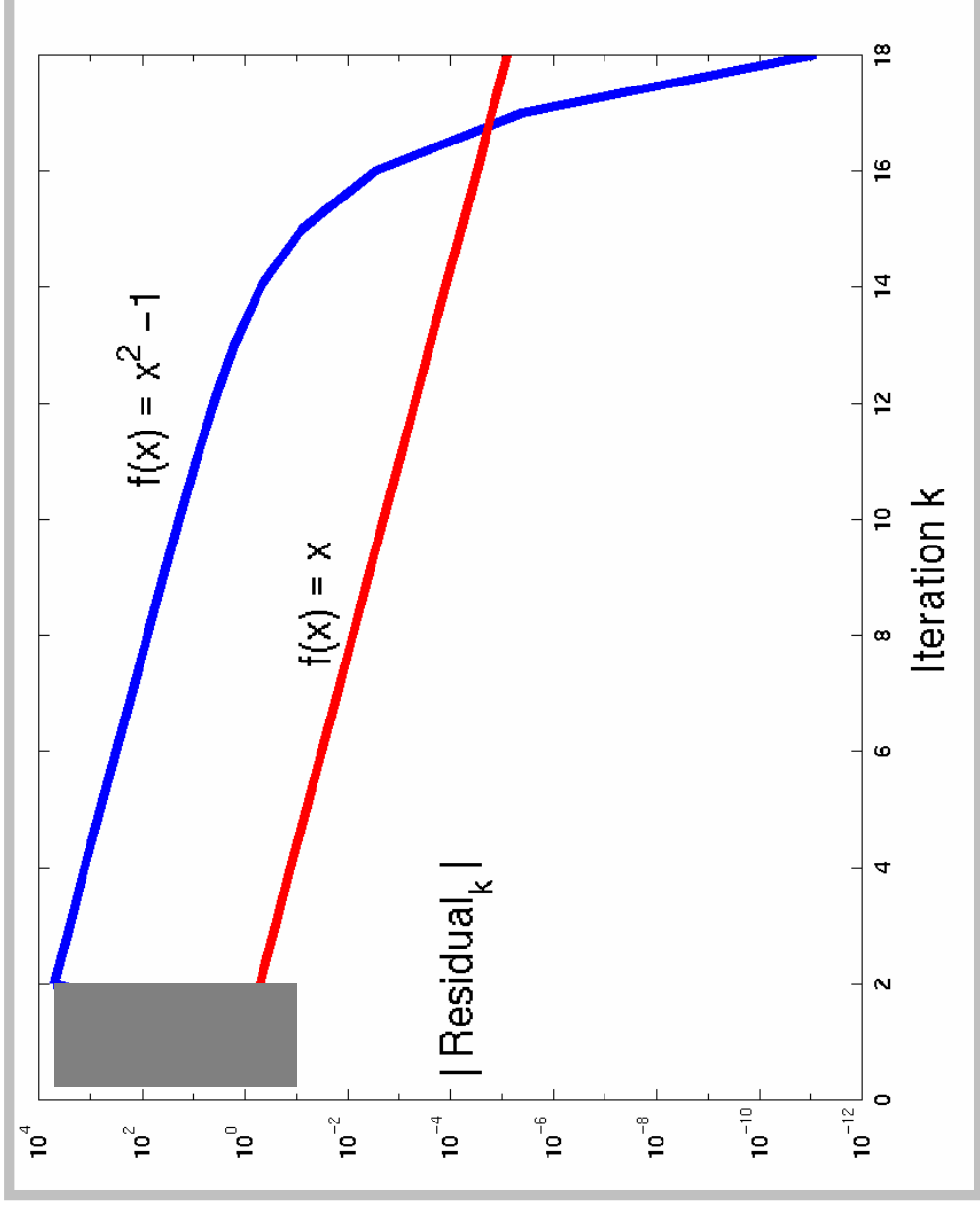
bounded

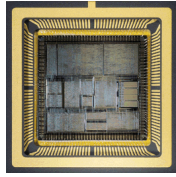
K is bounded

Then Newton's method converges given a sufficiently close initial guess (and convergence is quadratic)



Newton-Raphson Method – Convergence





Reference

- http://bwrc.eecs.berkeley.edu/Classes/lcBook/SPICE/UserGuide/overview_fr.html
- http://bear.ces.cwru.edu/eecs_cad/cad_spice.html
- http://mos.stanford.edu/papers/jk_fspice.ppt
- <http://www.ecircuitcenter.com/AboutSPICE.htm>
- <http://www-cad.eecs.berkeley.edu/~nardi/EE219A/lectures/0Tuto.ppt>
- <http://www.ieee.uta.edu/Tutorials/pspice/Basic%20Tuto.ppt>