Translinear Circuits

Bradley A. Minch

Mixed Analog-Digital VLSI Circuits and Systems Lab
Franklin W. Olin College of Engineering
Needham, MA 02492–1200

bradley.minch@olin.edu

April 2, 2009

Translinear Circuits: What's in a Name?

In 1975, Barrie Gilbert coined the term *translinear* to describe a class of circuits whose large-signal behavior hinges both on the precise exponential I/V relationship of the bipolar transistor and on the intimate thermal contact and close matching of monolithically integrated devices.

Translinear Circuits: What's in a Name?

In 1975, Barrie Gilbert coined the term *translinear* to describe a class of circuits whose large-signal behavior hinges both on the precise exponential I/V relationship of the bipolar transistor and on the intimate thermal contact and close matching of monolithically integrated devices.

The word translinear refers to the exponential I/V characteristic of the bipolar transistor—its transconductance is linear in its collector current:

$$I_{\mathrm{C}} = I_{\mathrm{s}} e^{V_{\mathrm{BE}}/U_{\mathrm{T}}} \quad \Longrightarrow \quad g_{\mathrm{m}} = \frac{\partial I_{\mathrm{C}}}{\partial V_{\mathrm{B}}} = \underbrace{I_{\mathrm{s}} e^{V_{\mathrm{BE}}/U_{\mathrm{T}}}}_{I_{\mathrm{C}}} \cdot \frac{1}{U_{\mathrm{T}}} = \frac{I_{\mathrm{C}}}{U_{\mathrm{T}}}.$$

Translinear Circuits: What's in a Name?

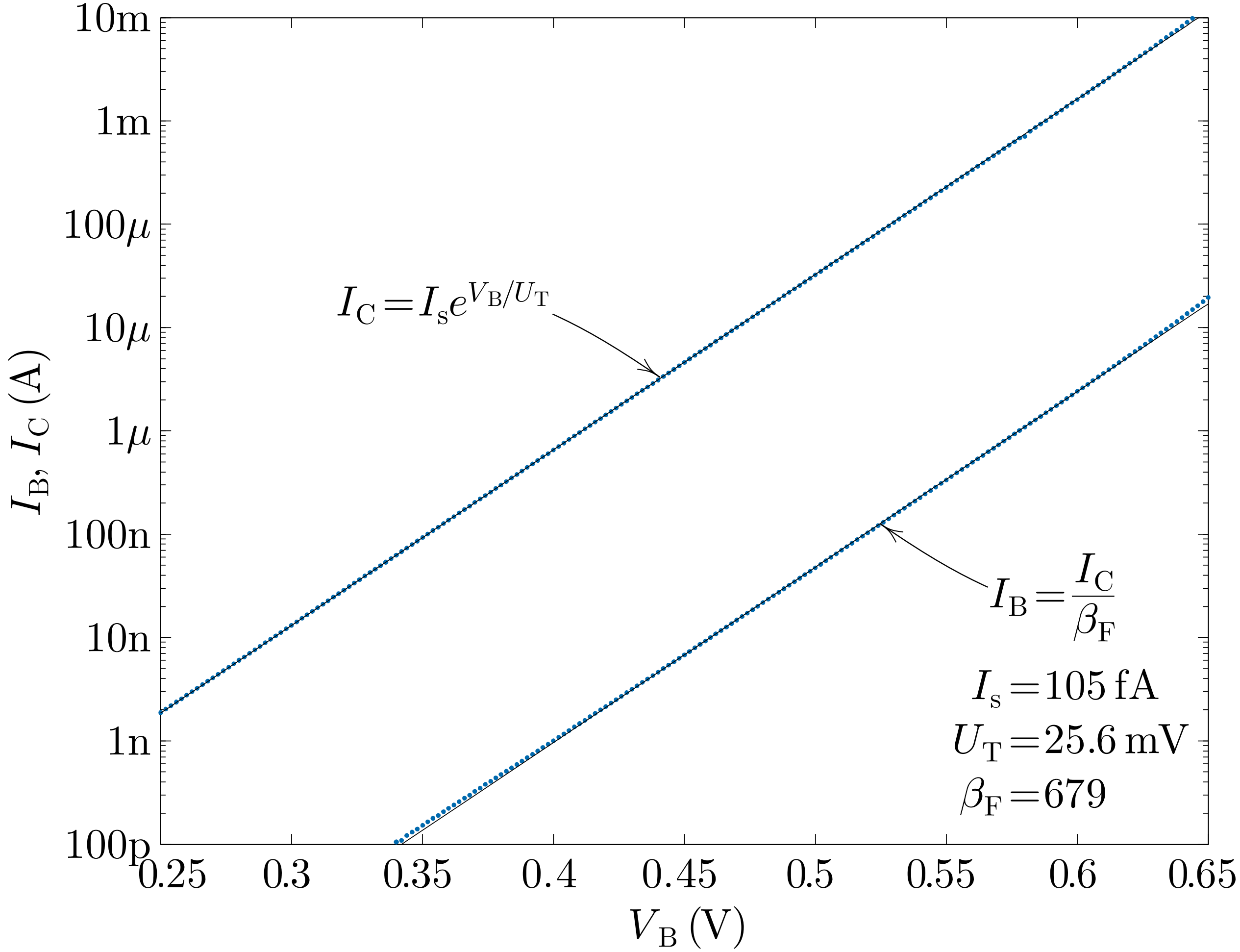
In 1975, Barrie Gilbert coined the term *translinear* to describe a class of circuits whose large-signal behavior hinges both on the precise exponential I/V relationship of the bipolar transistor and on the intimate thermal contact and close matching of monolithically integrated devices.

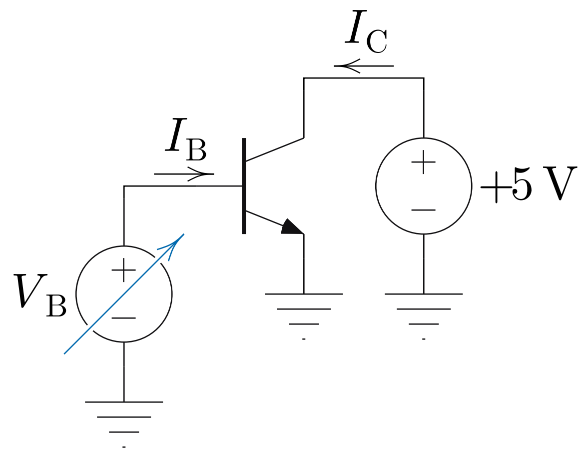
The word translinear refers to the exponential I/V characteristic of the bipolar transistor—its transconductance is linear in its collector current:

$$I_{\mathrm{C}} = I_{\mathrm{s}} e^{V_{\mathrm{BE}}/U_{\mathrm{T}}} \quad \Longrightarrow \quad g_{\mathrm{m}} = \frac{\partial I_{\mathrm{C}}}{\partial V_{\mathrm{B}}} = \underbrace{I_{\mathrm{s}} e^{V_{\mathrm{BE}}/U_{\mathrm{T}}}}_{I_{\mathrm{C}}} \cdot \frac{1}{U_{\mathrm{T}}} = \frac{I_{\mathrm{C}}}{U_{\mathrm{T}}}.$$

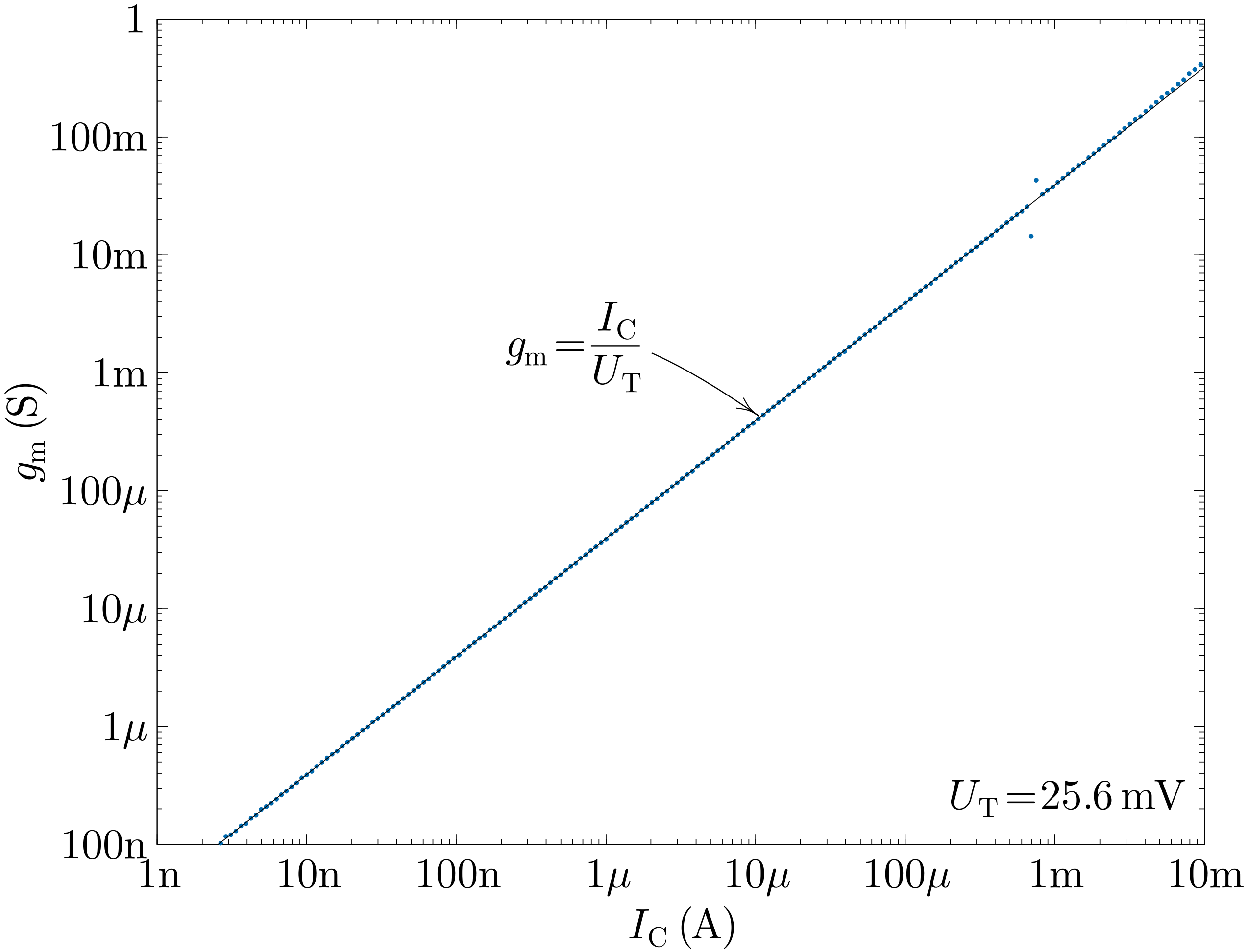
Gilbert also meant the word translinear to refer to circuit analysis and design principles that bridge the gap between the familiar territory of linear circuits and the uncharted domain of nonlinear circuits.

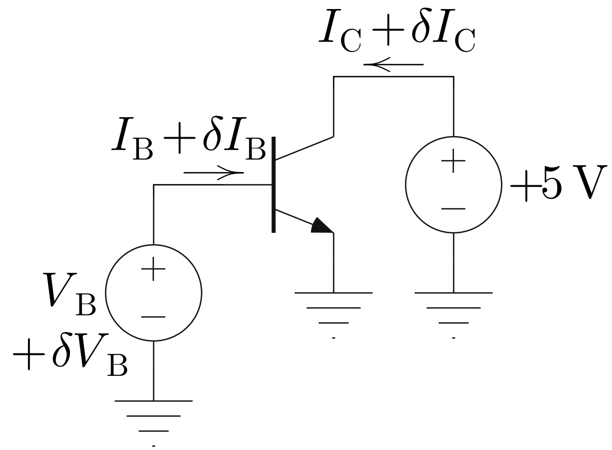
Gummel Plot of a Forward-Active Bipolar Transistor





Translinearity of the Forward-Active Bipolar Transistor





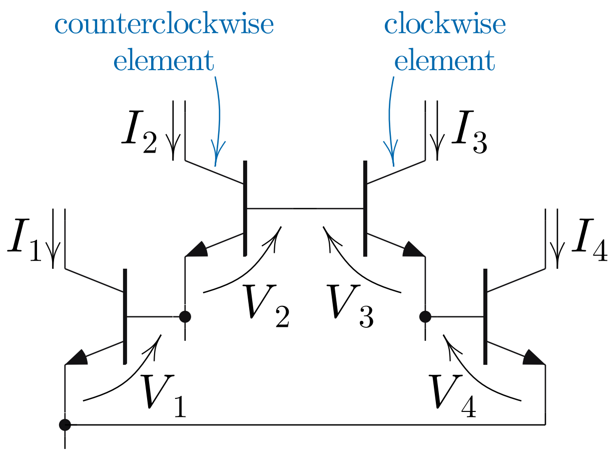
$$g_{\mathrm{m}} = \frac{\partial I_{\mathrm{C}}}{\partial V_{\mathrm{B}}} = \frac{I_{\mathrm{C}}}{U_{\mathrm{T}}}$$

$$\delta I_{\mathrm{C}} \approx g_{\mathrm{m}} \delta V_{\mathrm{B}}$$

The Translinear Principle

Consider a closed loop of base-emitter junctions of four closely matched *npn* bipolar transistors biased in the forward-active region and operating at the same temperature. Kirchhoff's voltage law (KVL) implies that

$$\begin{aligned} V_1 + V_2 &= V_3 + V_4 \\ U_\mathrm{T} \log \frac{I_1}{I_\mathrm{s}} + U_\mathrm{T} \log \frac{I_2}{I_\mathrm{s}} &= U_\mathrm{T} \log \frac{I_3}{I_\mathrm{s}} + U_\mathrm{T} \log \frac{I_4}{I_\mathrm{s}} \\ \log \frac{I_1 I_2}{I_\mathrm{s}^2} &= \log \frac{I_3 I_4}{I_\mathrm{s}^2} \\ \underbrace{I_1 I_2}_{\text{CCW}} &= \underbrace{I_3 I_4}_{\text{CW}}. \end{aligned}$$

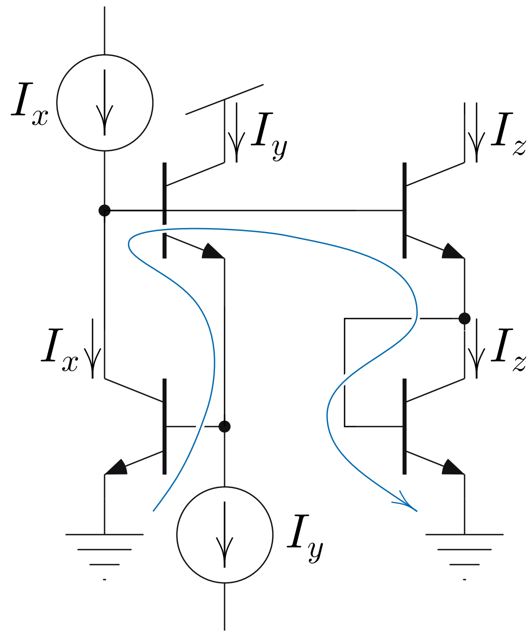


This result is a particular case of Gilbert's *translinear principle* (TLP): The product of the clockwise currents is equal to the product of the counterclockwise currents.

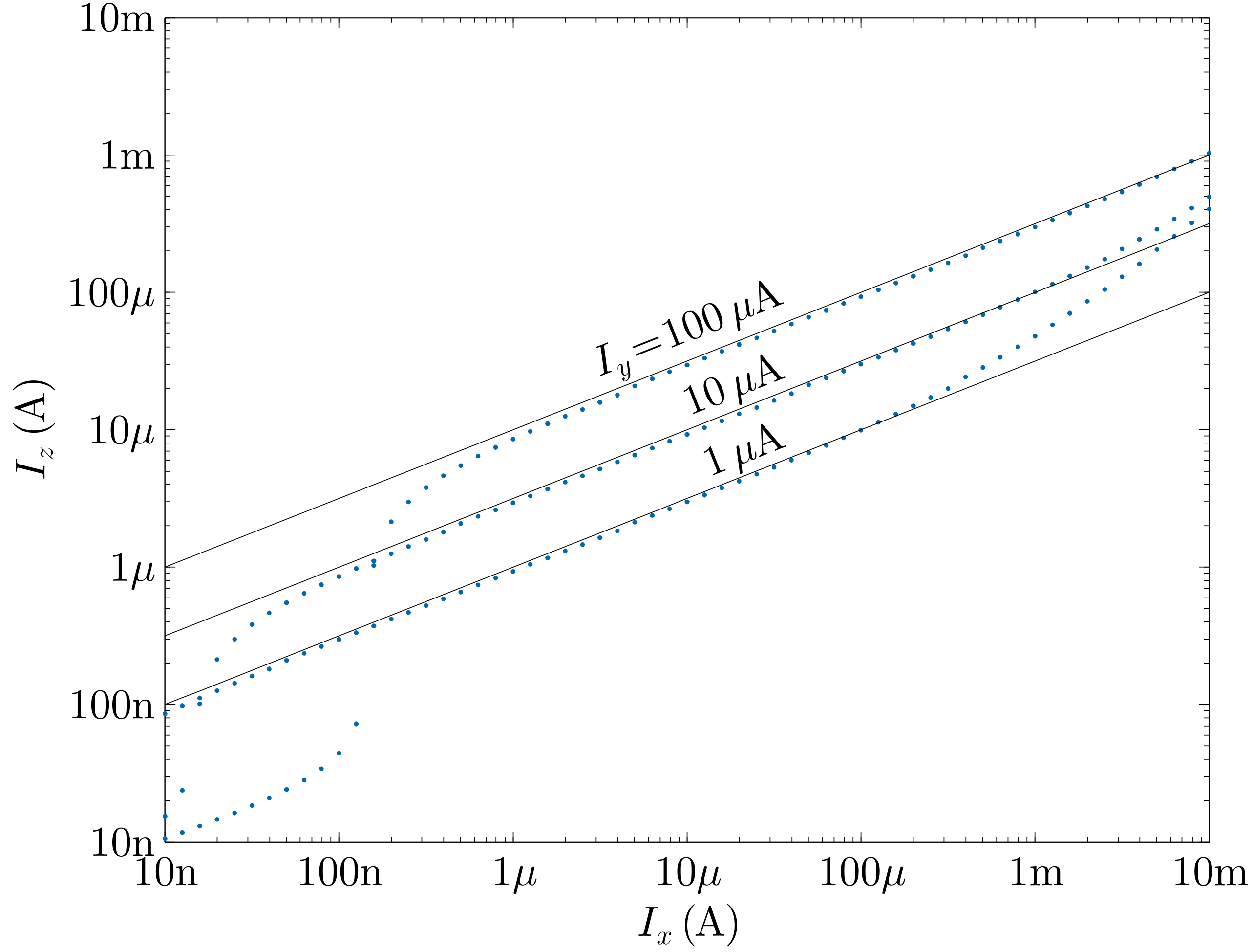
Static Translinear Circuits: Geometric Mean

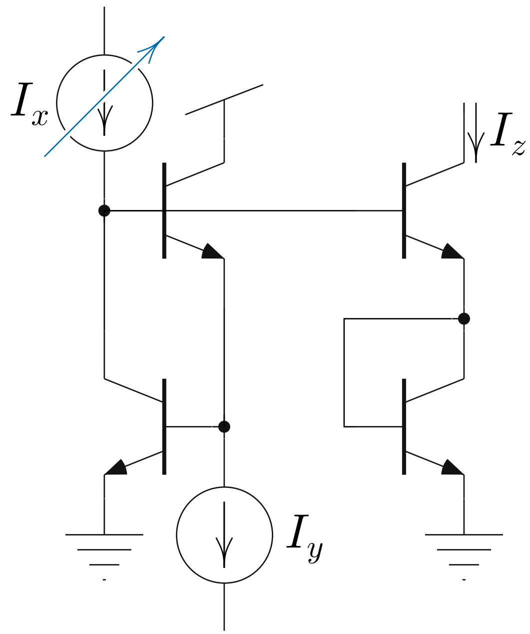
We neglect both base currents (i.e., $\beta_{\mathrm{F}} = \infty$) and the Early effect, and we assume that all transistors operate in their forward-active regions. Then, we have that

$$\text{TLP} \implies I_x I_y = I_z^2 \implies I_z = \sqrt{I_x I_y}.$$



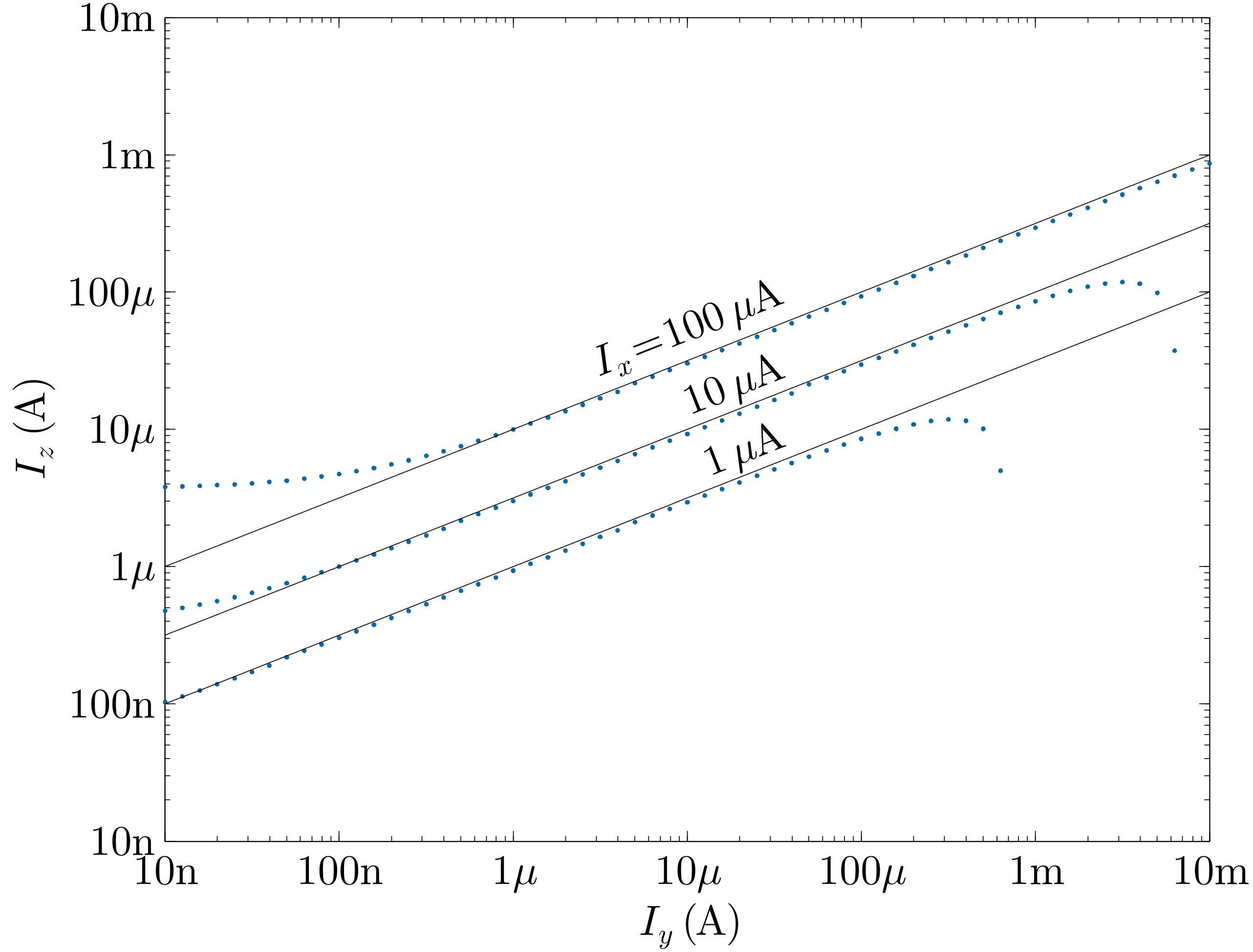
Static Translinear Circuits: Geometric Mean

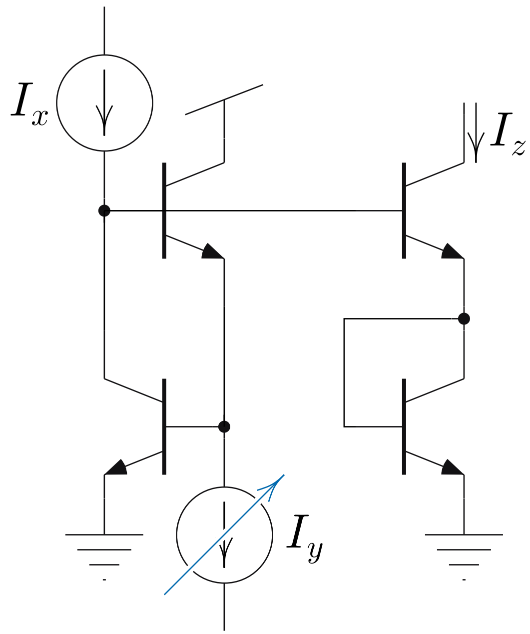




$$I_z = \sqrt{I_x I_y}$$

Static Translinear Circuits: Geometric Mean



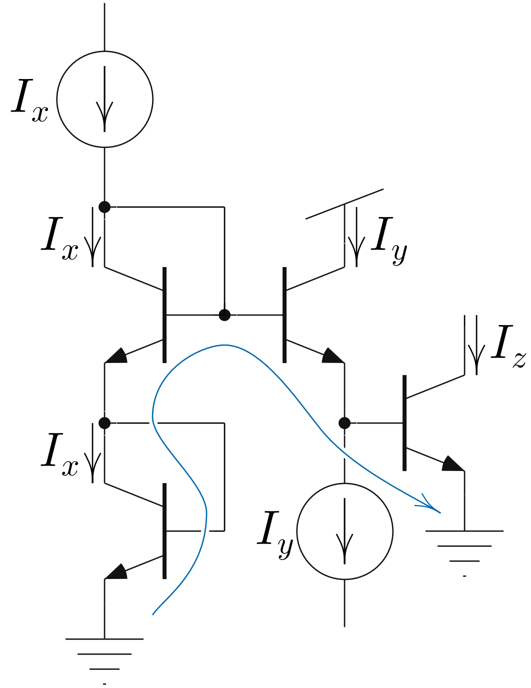


$$I_z = \sqrt{I_x I_y}$$

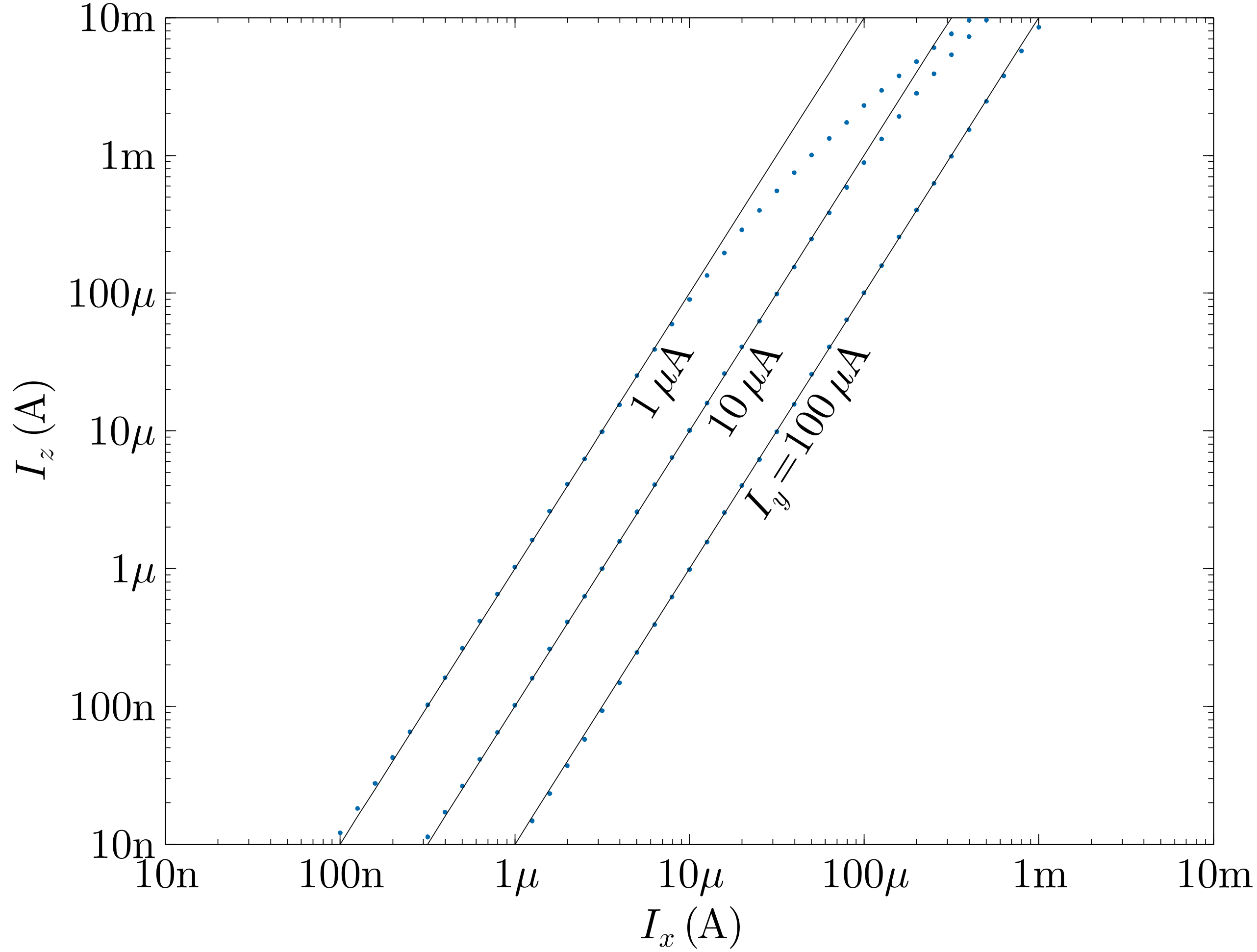
Static Translinear Circuits: Squaring/Reciprocal

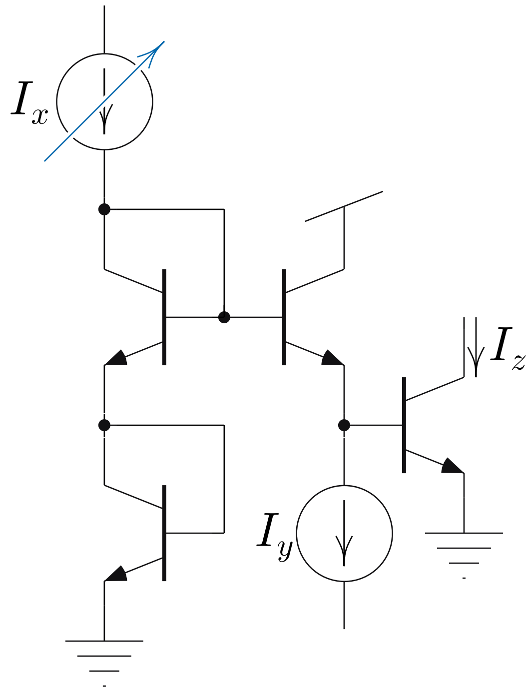
Again, we neglect both base currents (i.e., $\beta_F = \infty$) and the Early effect, and we assume that all transistors operate in their forward-active regions. Then, we have that

$$\text{TLP} \implies I_x^2 = I_y I_z \implies I_z = \frac{I_x^2}{I_y}.$$



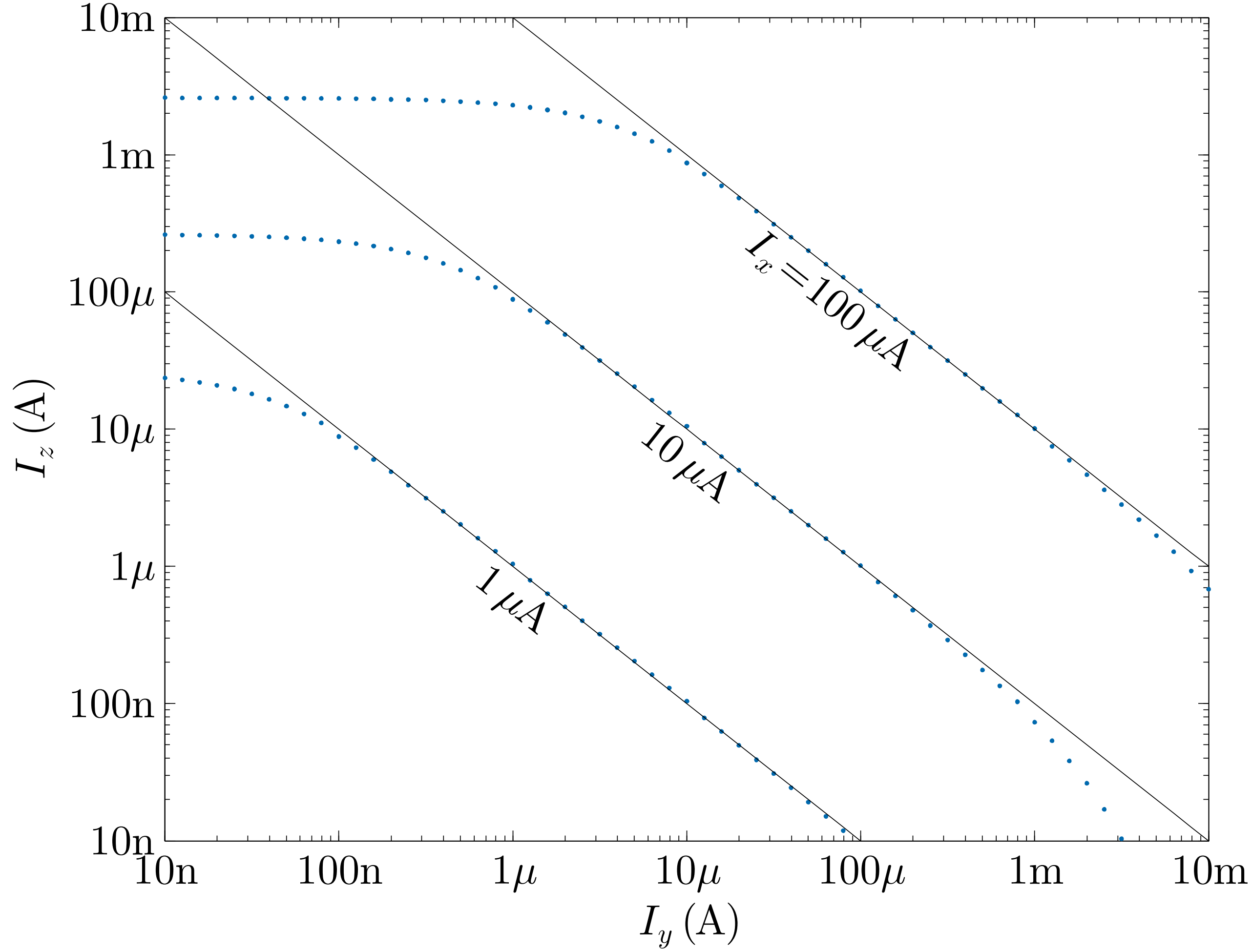
Static Translinear Circuits: Squaring/Reciprocal

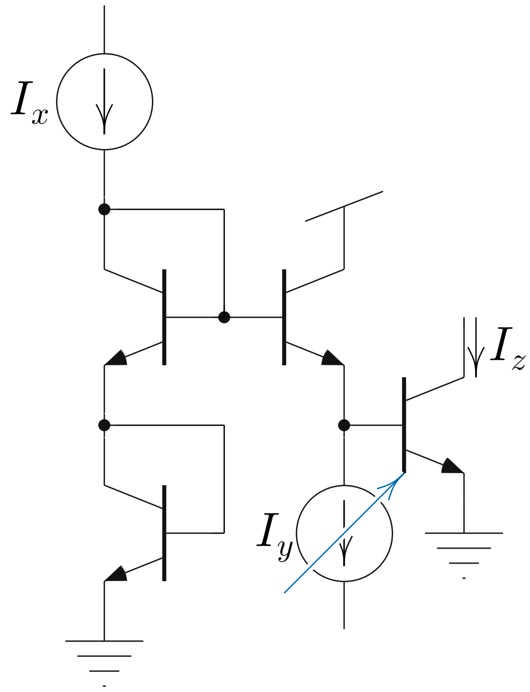




$$I_z = \frac{I_x^2}{I_y}$$

Static Translinear Circuits: Squaring/Reciprocal





$$I_z = \frac{I_x^2}{I_y}$$

Static Translinear Circuits: Pythagorator

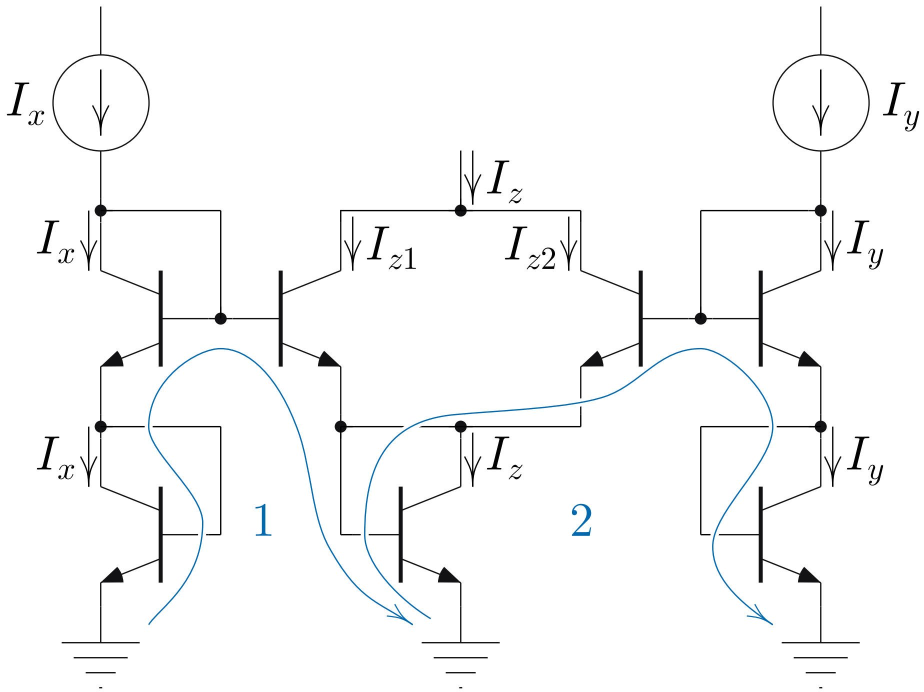
Again, we neglect both base currents and the Early effect, and we assume that all transistors operate in their forward-active regions. Then, we have that

$$\text{TLP 1} \implies I_x^2 = I_{z1} I_z \implies I_{z1} = \frac{I_x^2}{I_z}$$

$$\text{TLP 2} \implies I_y^2 = I_{z2} I_z \implies I_{z2} = \frac{I_y^2}{I_z}$$

$$\text{KCL} \implies I_z = I_{z1} + I_{z2} = \frac{I_x^2}{I_z} + \frac{I_y^2}{I_z}$$

$$\implies I_z^2 = I_x^2 + I_y^2 \implies I_z = \sqrt{I_x^2 + I_y^2}.$$



This circuit is called the pythagorator.

Dynamic Translinear Circuits: First-Order Low-Pass Filter

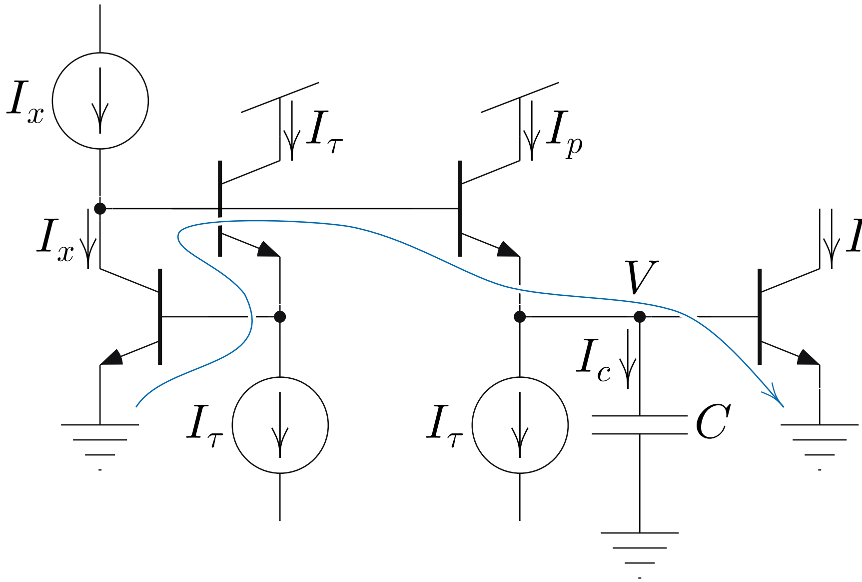
Next, consider the *dynamic* translinear circuit shown below, comprising a translinear loop and a capacitor. We shall again neglect base currents and the Early effect. We also assume that all transistors operate in the forward-active region. Then, we have that

$$\text{TLP} \implies I_\tau I_x = I_p I_y \implies I_p = \frac{I_\tau I_x}{I_y}$$

$$I_\mathrm{c} = C\frac{dV}{dt} = C\frac{d}{dt}\left(U_\mathrm{T}\log\frac{I_y}{I_\mathrm{s}}\right) = \frac{CU_\mathrm{T}}{I_y}\frac{dI_y}{dt}$$

$$\text{KCL} \implies I_\mathrm{c}+I_\tau = I_p \implies \frac{CU_\mathrm{T}}{I_y}\frac{dI_y}{dt}+I_\tau = \frac{I_\tau I_x}{I_y}$$

$$\implies \underbrace{\frac{CU_\mathrm{T}}{I_\tau}}_{\tau}\frac{dI_y}{dt} + I_y = I_x \implies \tau\frac{dI_y}{dt} + I_y = I_x.$$



This circuit is a first-order log-domain filter.

Dynamic Translinear Circuits: RMS-to-DC Converter

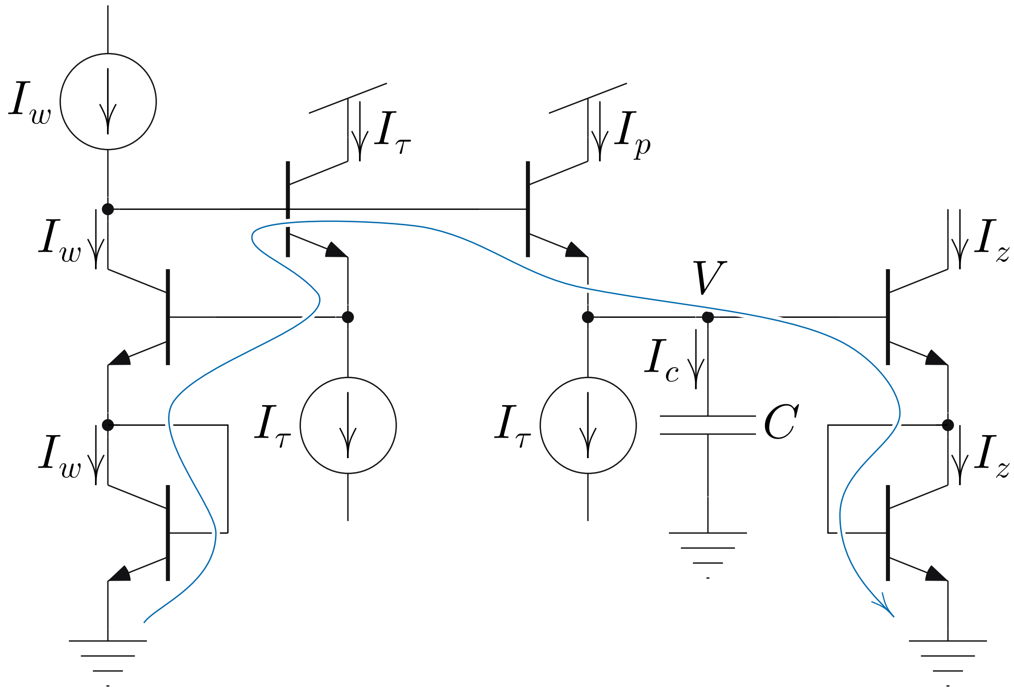
$$\text{TLP} \implies I_w^2 I_\tau = I_p I_z^2 \implies I_p = \frac{I_\tau I_w^2}{I_z^2}$$

$$I_\mathrm{c} = C\frac{d}{dt}\left(2U_\mathrm{T}\log\frac{I_z}{I_\mathrm{s}}\right) = 2\frac{CU_\mathrm{T}}{I_z}\frac{dI_z}{dt}$$

$$\text{KCL} \implies I_\mathrm{c} + I_\tau = I_p$$

$$\implies \frac{2CU_\mathrm{T}}{I_z}\frac{dI_z}{dt} + I_\tau = \frac{I_\tau I_w^2}{I_z^2}$$

$$\implies \underbrace{\frac{CU_\mathrm{T}}{I_\tau}}_{\tau} 2\,I_z\frac{dI_z}{dt} + I_z^2 = I_w^2$$



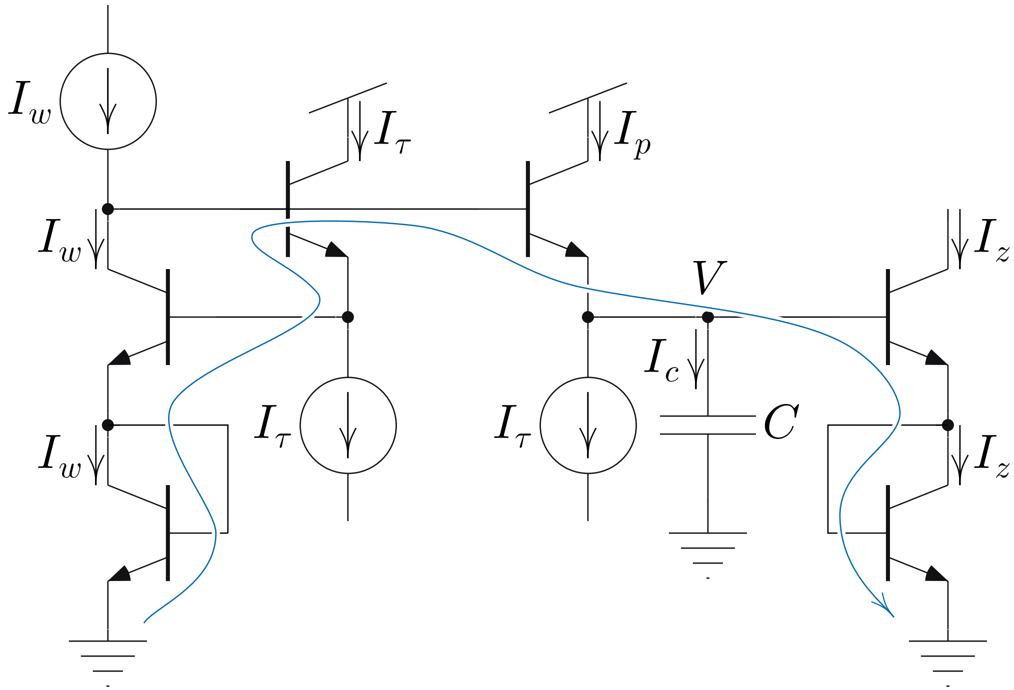
Dynamic Translinear Circuits: RMS-to-DC Converter

$$\Longrightarrow \quad \tau\left(2\,I_z\frac{dI_z}{dt}\right) + I_z^2 \quad = \quad I_w^2$$

$$\Longrightarrow \quad \tau\frac{d}{dt}\left(I_z^2\right) + I_z^2 \quad = \quad I_w^2$$

$$\Longrightarrow \quad \tau\frac{d}{dt}\left(\underbrace{\frac{I_z^2}{I_1}}_{I_y}\right) + \underbrace{\frac{I_z^2}{I_1}}_{I_y} \quad = \quad \underbrace{\frac{I_w^2}{I_1}}_{I_x}$$

$$\underbrace{I_z = \sqrt{I_1 I_y}}_{\text{root}} \qquad \underbrace{\tau\frac{dI_y}{dt} + I_y = I_x}_{\text{mean}} \qquad \underbrace{I_x = \frac{I_w^2}{I_1}}_{\text{square}}$$



Why Translinear Circuits?

Why Translinear Circuits?

- Translinear circuits are *universal*. Conjecture: In principle, we can realize any system whose description we can write down as a nonlinear ODE with time as its independent variable as a dynamic translinear circuit.

Why Translinear Circuits?

- Translinear circuits are *universal*. Conjecture: In principle, we can realize any system whose description we can write down as a nonlinear ODE with time as its independent variable as a dynamic translinear circuit.

- Translinear circuits are *synthesizable* via highly structured methods. They should be very amenable to the development both of CAD tools and of reconfigurable FPAA architectures for rapid prototyping and deployment of translinear analog signal processing systems.

Why Translinear Circuits?

- Translinear circuits are *universal*. Conjecture: In principle, we can realize any system whose description we can write down as a nonlinear ODE with time as its independent variable as a dynamic translinear circuit.

- Translinear circuits are *synthesizable* via highly structured methods. They should be very amenable to the development both of CAD tools and of reconfigurable FPAA architectures for rapid prototyping and deployment of translinear analog signal processing systems.

- Translinear circuits are fundamentally *large-signal* circuits. Linear dynamic translinear circuits are linear because of device nonlinearities rather than in spite of them.

Why Translinear Circuits?

- Translinear circuits are *universal*. Conjecture: In principle, we can realize any system whose description we can write down as a nonlinear ODE with time as its independent variable as a dynamic translinear circuit.

- Translinear circuits are *synthesizable* via highly structured methods. They should be very amenable to the development both of CAD tools and of reconfigurable FPAA architectures for rapid prototyping and deployment of translinear analog signal processing systems.

- Translinear circuits are fundamentally *large-signal* circuits. Linear dynamic translinear circuits are linear because of device nonlinearities rather than in spite of them.

- Translinear circuits are *tunable* electronically over a wide dynamic range of parameters (e.g., gains, corner frequencies, quality factors).

Why Translinear Circuits?

- Translinear circuits are *universal*. Conjecture: In principle, we can realize any system whose description we can write down as a nonlinear ODE with time as its independent variable as a dynamic translinear circuit.

- Translinear circuits are *synthesizable* via highly structured methods. They should be very amenable to the development both of CAD tools and of reconfigurable FPAA architectures for rapid prototyping and deployment of translinear analog signal processing systems.

- Translinear circuits are fundamentally *large-signal* circuits. Linear dynamic translinear circuits are linear because of device nonlinearities rather than in spite of them.

- Translinear circuits are *tunable* electronically over a wide dynamic range of parameters (e.g., gains, corner frequencies, quality factors).

- Translinear circuits are *robust*. Carefully designed translinear circuits are temperature insensitive and do not depend on device or technology parameters.

Simple EKV Model of the Saturated nMOS Transistor

We model the saturation current of an nMOS transistor by

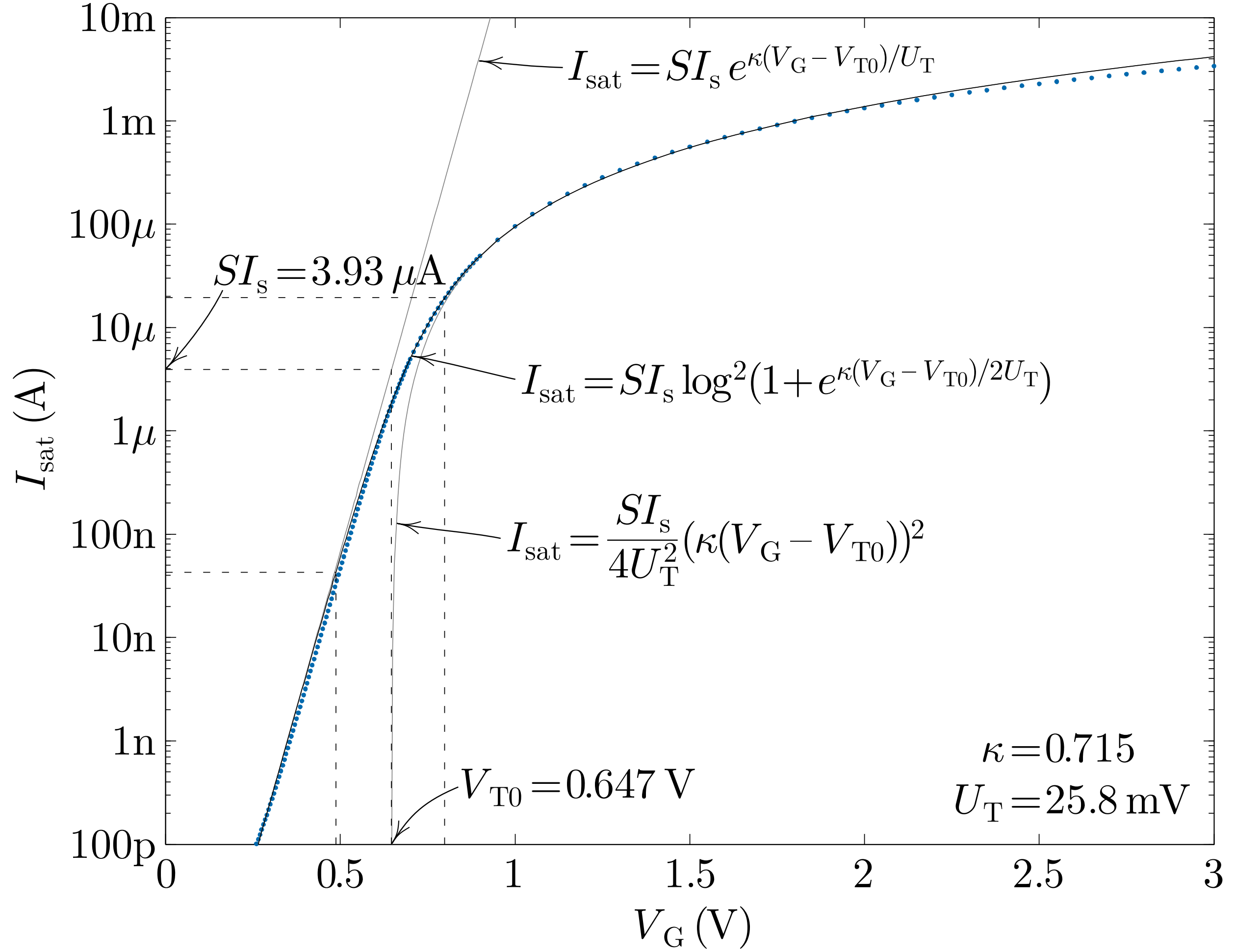
$$I_{\text{sat}} = SI_{\text{s}} \log^2\left(1 + e^{(\kappa(V_{\text{G}}-V_{\text{T0}})-V_{\text{S}})/2U_{\text{T}}}\right)$$
$$\approx \begin{cases} SI_{\text{s}} e^{(\kappa(V_{\text{G}}-V_{\text{T0}})-V_{\text{S}})/U_{\text{T}}}, & \kappa\left(V_{\text{G}}-V_{\text{T0}}\right)-V_{\text{S}} < 0 \\ \dfrac{SI_{\text{s}}}{4U_{\text{T}}^2}\left(\kappa\left(V_{\text{G}}-V_{\text{T0}}\right)-V_{\text{S}}\right)^2, & \kappa\left(V_{\text{G}}-V_{\text{T0}}\right)-V_{\text{S}} > 0, \end{cases}$$

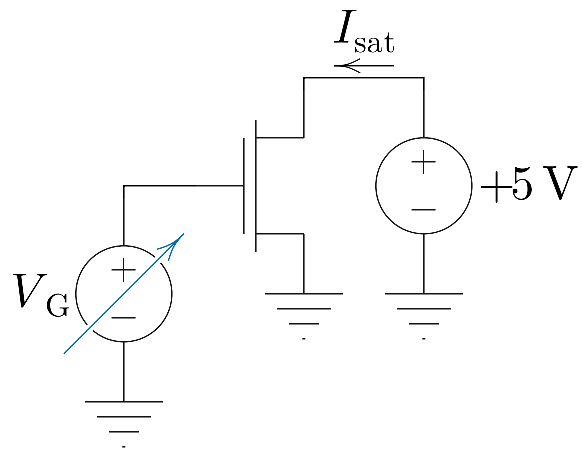
where

$$U_{\text{T}} = \frac{kT}{q}, \quad S = \frac{W}{L}, \quad I_{\text{s}} = \frac{2\mu C_{\text{ox}} U_{\text{T}}^2}{\kappa}, \quad \text{and} \quad \kappa = \frac{C_{\text{ox}}}{C_{\text{ox}} + C_{\text{dep}}}.$$

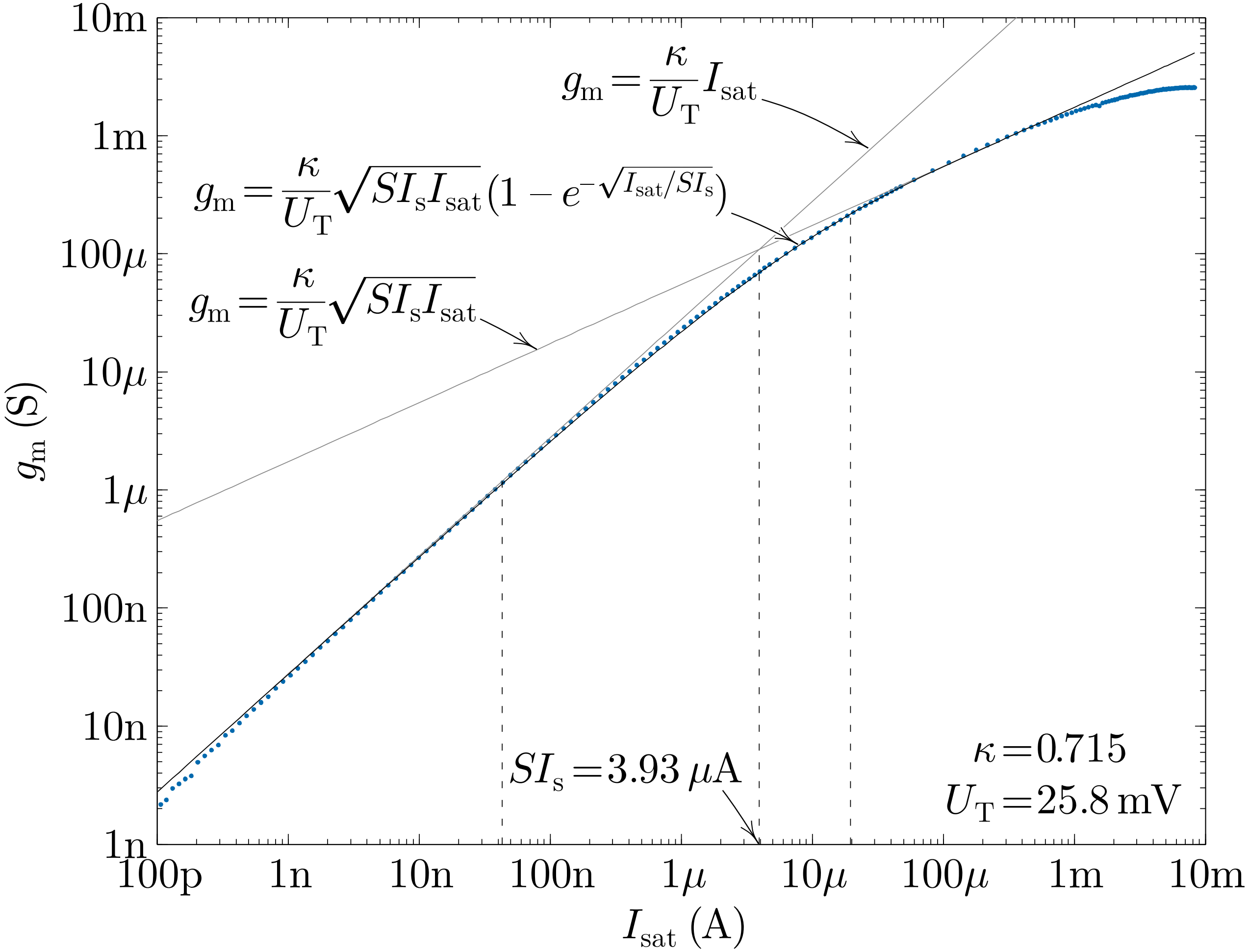
Weak inversion operation corresponds to $I_{\text{sat}} \ll SI_{\text{s}}$, moderate inversion operation corresponds to $I_{\text{sat}} \approx SI_{\text{s}}$, and strong inversion operation to $I_{\text{sat}} \gg SI_{\text{s}}$. Note that SI_{s} is approximately twice the saturation current at threshold.

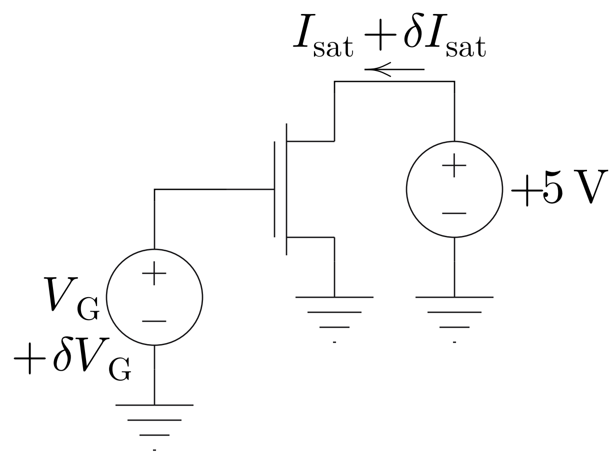
Saturation Current of an nMOS Transistor





Translinearity of the Saturated nMOS Transistor

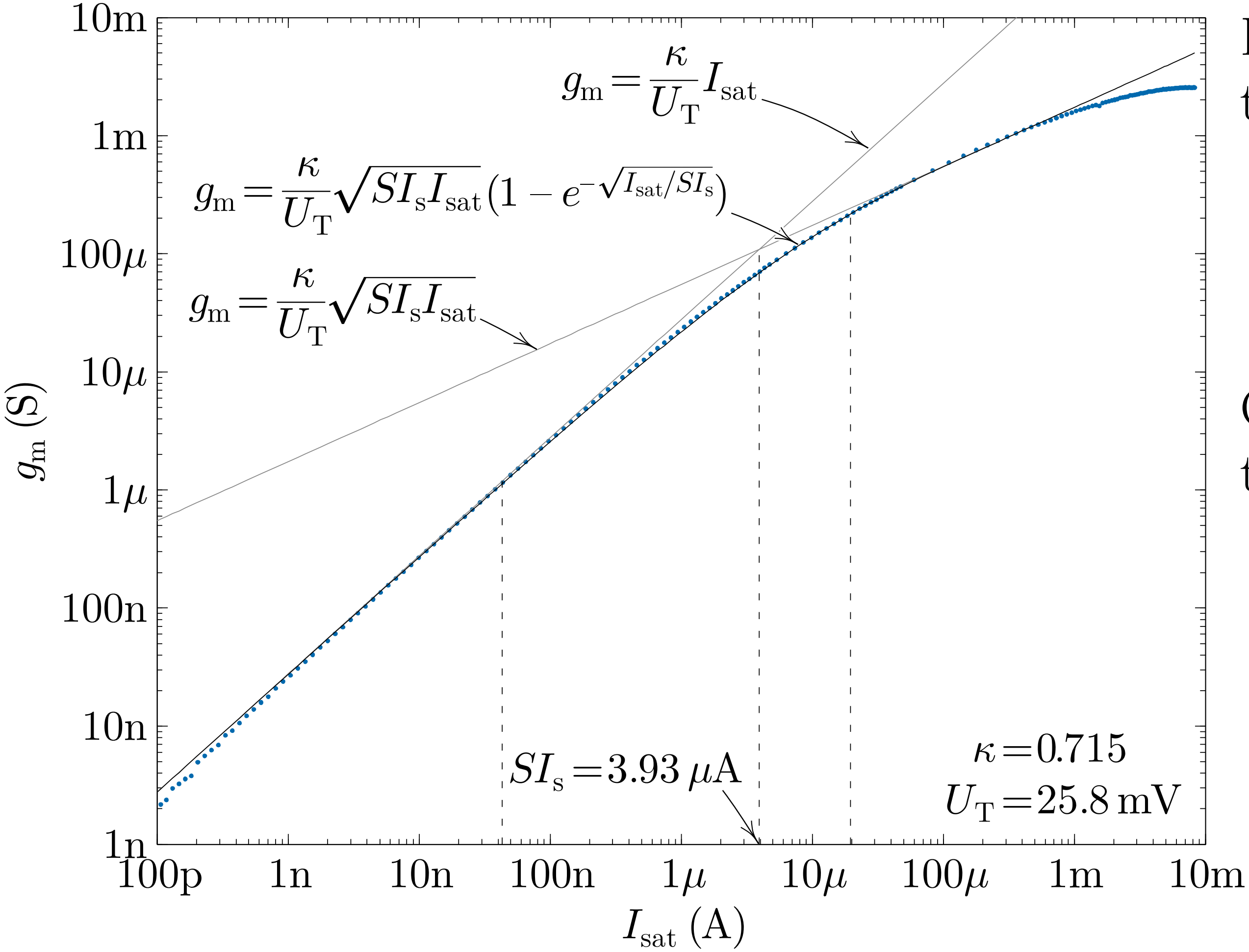




$$g_m = \frac{\partial I_{sat}}{\partial V_G} = \frac{\kappa I_{sat}}{U_T}, I_{sat} \ll SI_s$$

$$\delta I_{sat} \approx g_m \delta V_G$$

Weak Inversion is Suited to Audio Signal Processing

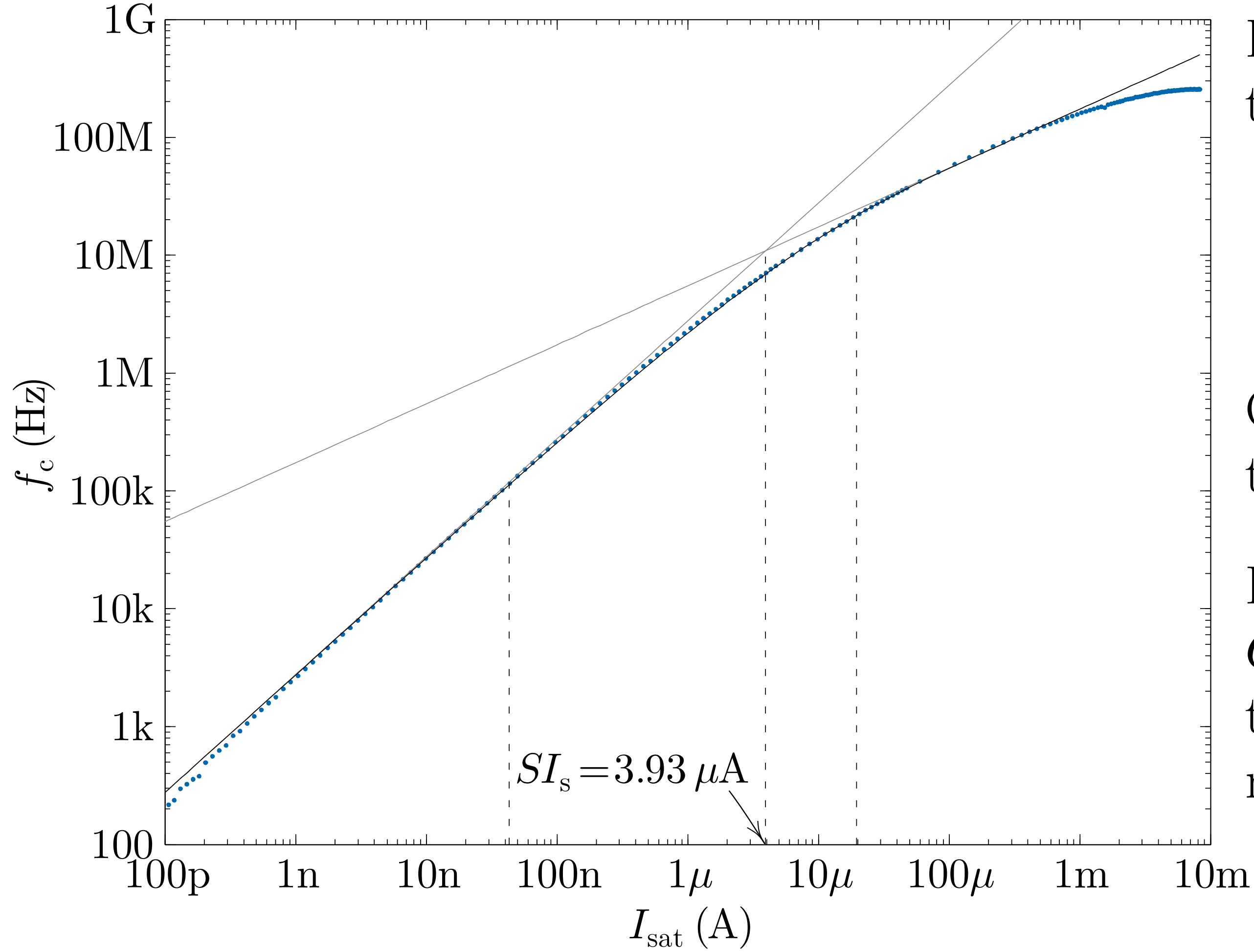


For integrated continous-time filters, typically

$$f_\mathrm{c} = \frac{g_\mathrm{m}}{2\pi C}.$$

On-chip capacitors are typically on the order of 1 pF or of 10 pF.

Weak Inversion is Suited to Audio Signal Processing



For integrated continous-time filters, typically

$$f_c = \frac{g_m}{2\pi C}.$$

On-chip capacitors are typically on the order of 1 pF or of 10 pF.

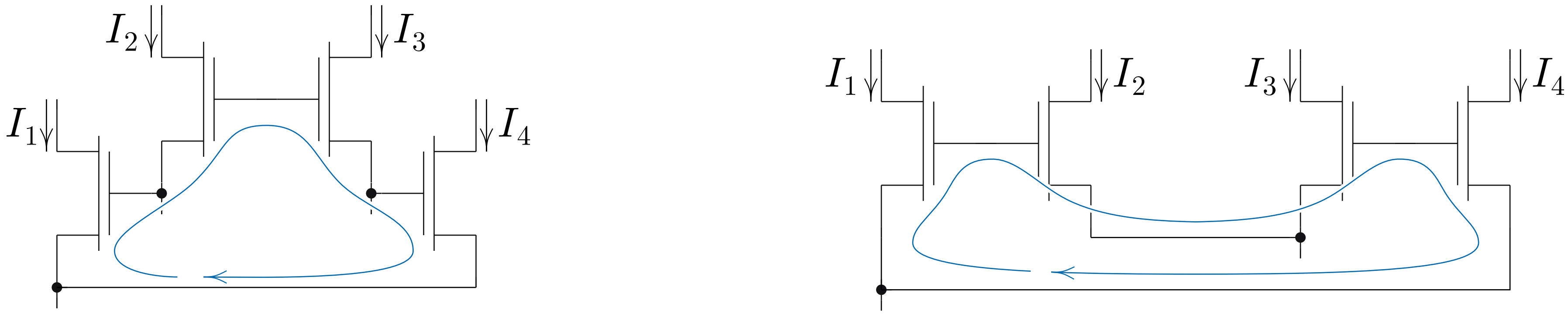
If we choose a reasonable value for C, say $C = 5/\pi\,\mathrm{pF} \approx 1.59\,\mathrm{pF}$, then we find that weak inversion maps onto the audio band.

Weak-Inversion MOS Translinear Principle

When designing weak-inversion MOS translinear circuits, if we restrict ourselves to using translinear loops that alternate between clockwise and counterclockwise elements, we obtain Gilbert's original TLP, with no dependence on the body effect (i.e., κ).

stacked loop

alternating loop



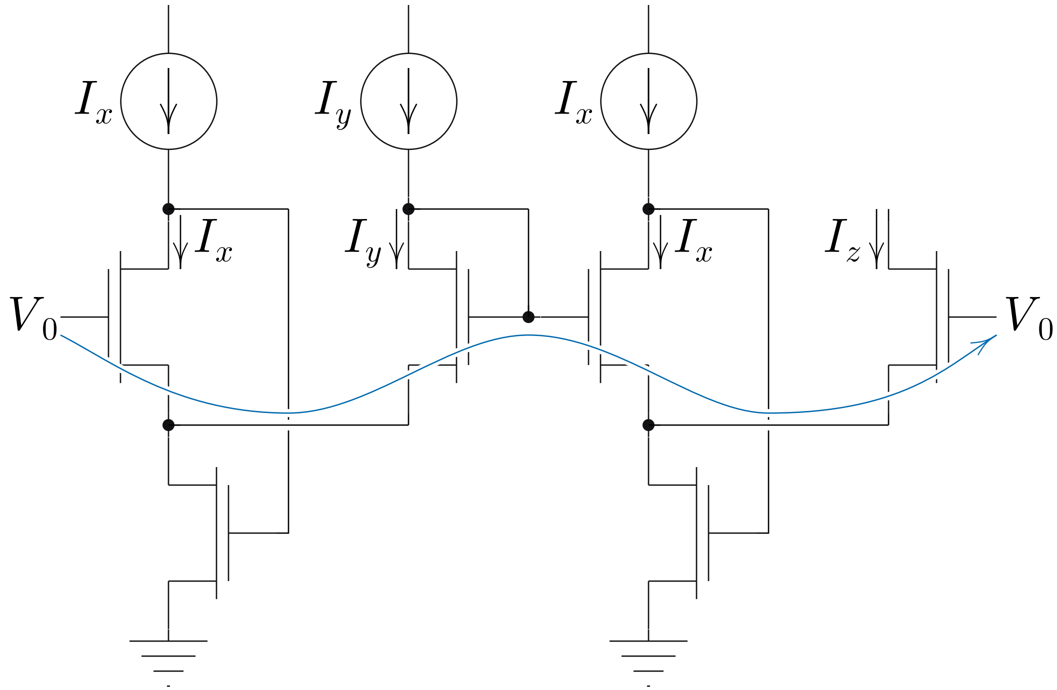
TLP: $I_1 I_2^{\kappa} = I_3^{\kappa} I_4$

TLP: $I_1 I_3 = I_2 I_4$

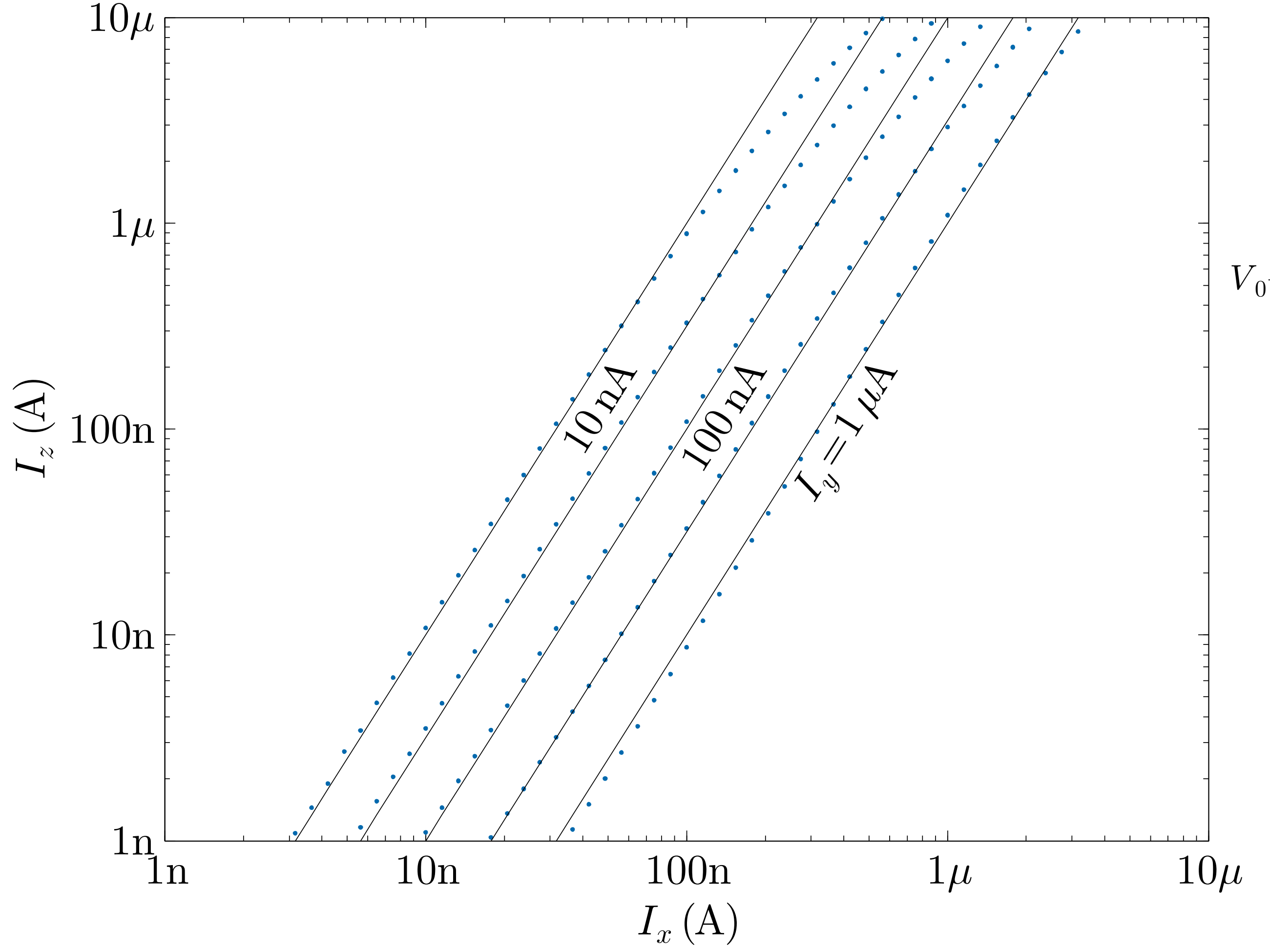
This restriction does not limit the class of systems that we can implement. However, designs based on alternating loops generally consume more current but operate on a lower power supply voltage than do designs based on stacked loops.

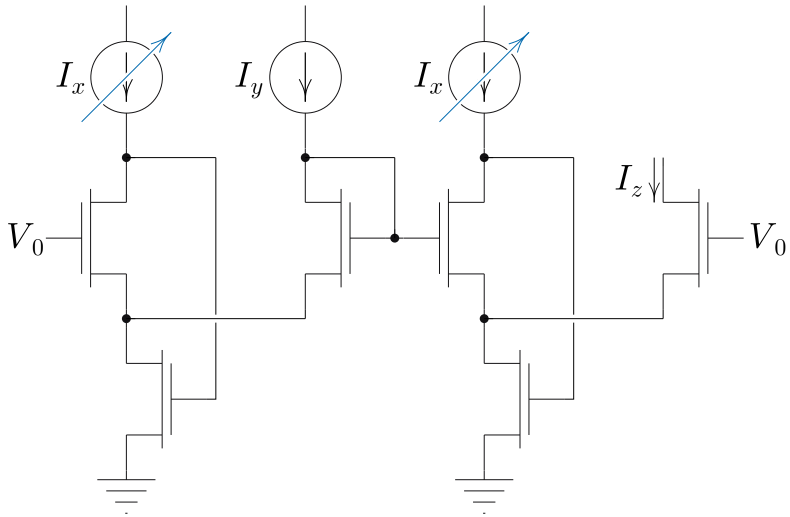
Static Translinear Circuits: Squaring/Reciprocal

$$\text{TLP} \implies I_x^2 = I_y I_z \implies I_z = \frac{I_x^2}{I_y}$$



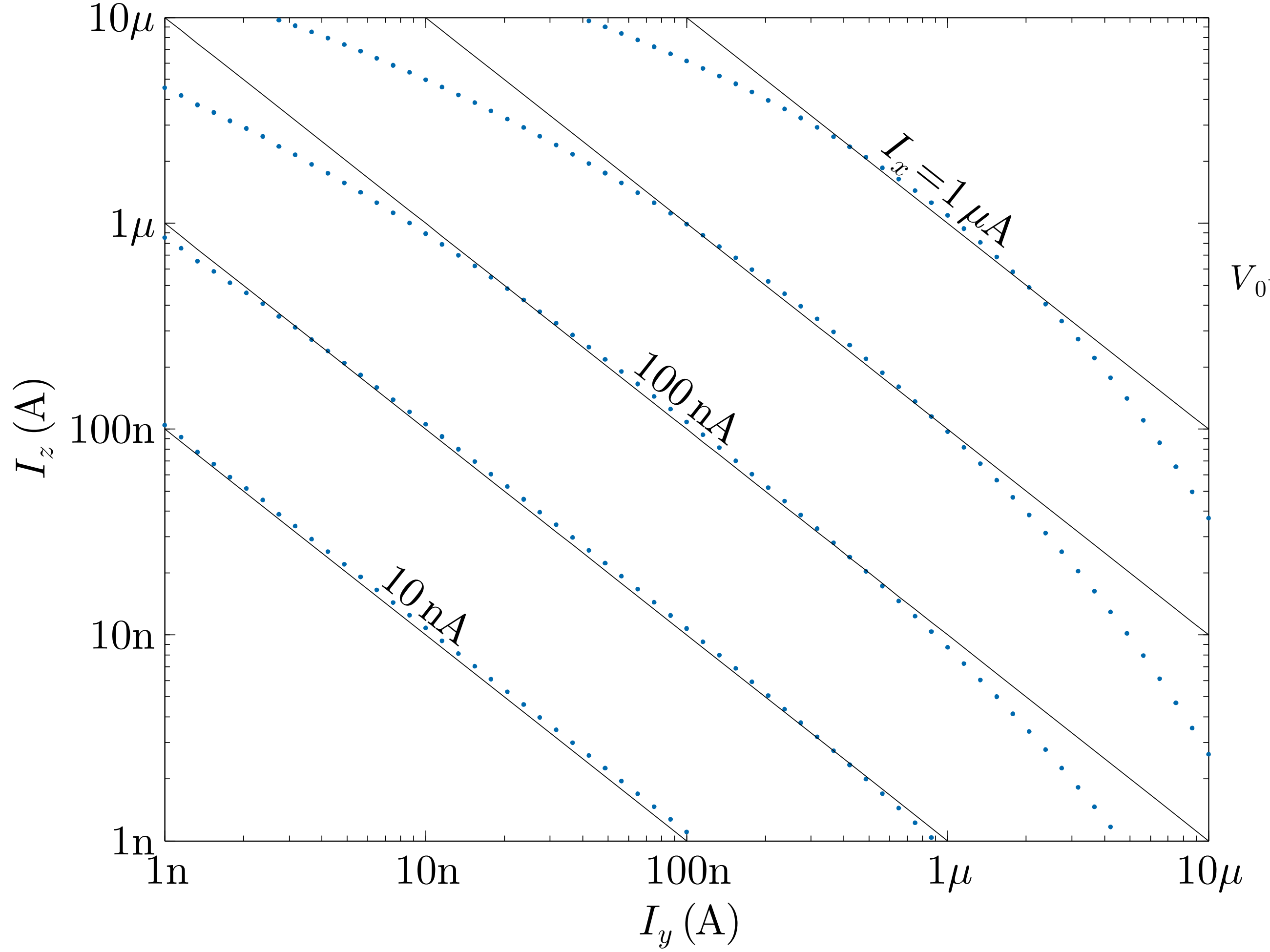
Static Translinear Circuits: Squaring/Reciprocal

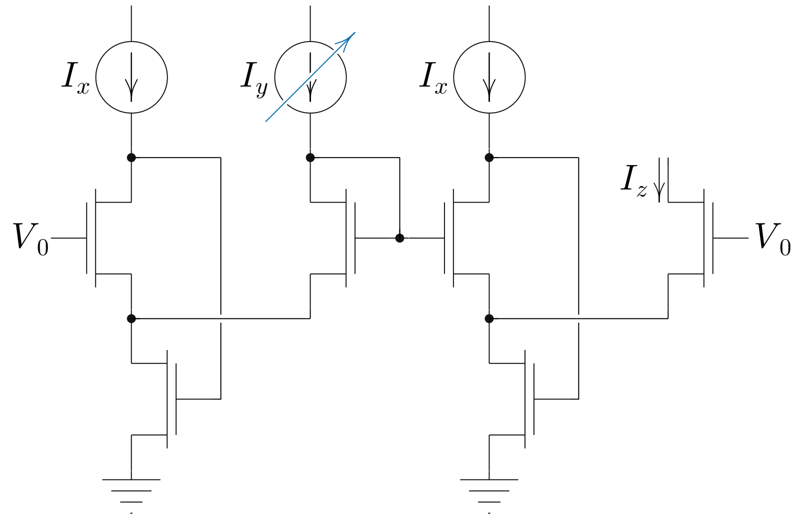




$$I_z = \frac{I_x^2}{I_y}$$

Static Translinear Circuits: Squaring/Reciprocal





$$I_z = \frac{I_x^2}{I_y}$$

Static Translinear Circuit Synthesis: Pythagorator

Synthesize a two-dimensional vector-magnitude circuit implementing

$$r = \sqrt{x^2 + y^2}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

Static Translinear Circuit Synthesis: Pythagorator

Synthesize a two-dimensional vector-magnitude circuit implementing

$$r = \sqrt{x^2 + y^2}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

We represent each signal as a ratio of a signal current to the unit current:

$$x \equiv \frac{I_x}{I_1}, \quad y \equiv \frac{I_y}{I_1}, \quad \text{and} \quad r \equiv \frac{I_r}{I_1}.$$

Static Translinear Circuit Synthesis: Pythagorator

Synthesize a two-dimensional vector-magnitude circuit implementing

$$r = \sqrt{x^2 + y^2}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

We represent each signal as a ratio of a signal current to the unit current:

$$x \equiv \frac{I_x}{I_1}, \quad y \equiv \frac{I_y}{I_1}, \quad \text{and} \quad r \equiv \frac{I_r}{I_1}.$$

We substitute these into the original equation and rearrange to obtain

$$\frac{I_r}{I_1} = \sqrt{\left(\frac{I_x}{I_1}\right)^2 + \left(\frac{I_y}{I_1}\right)^2}$$

Static Translinear Circuit Synthesis: Pythagorator

Synthesize a two-dimensional vector-magnitude circuit implementing

$$r = \sqrt{x^2 + y^2}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

We represent each signal as a ratio of a signal current to the unit current:

$$x \equiv \frac{I_x}{I_1}, \quad y \equiv \frac{I_y}{I_1}, \quad \text{and} \quad r \equiv \frac{I_r}{I_1}.$$

We substitute these into the original equation and rearrange to obtain

$$\frac{I_r}{I_1} = \sqrt{\left(\frac{I_x}{I_1}\right)^2 + \left(\frac{I_y}{I_1}\right)^2} \quad \Longrightarrow \quad I_r^2 = I_x^2 + I_y^2$$

Static Translinear Circuit Synthesis: Pythagorator

Synthesize a two-dimensional vector-magnitude circuit implementing

$$r = \sqrt{x^2 + y^2}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

We represent each signal as a ratio of a signal current to the unit current:

$$x \equiv \frac{I_x}{I_1}, \quad y \equiv \frac{I_y}{I_1}, \quad \text{and} \quad r \equiv \frac{I_r}{I_1}.$$

We substitute these into the original equation and rearrange to obtain

$$\frac{I_r}{I_1} = \sqrt{\left(\frac{I_x}{I_1}\right)^2 + \left(\frac{I_y}{I_1}\right)^2} \quad \Longrightarrow \quad I_r^2 = I_x^2 + I_y^2 \quad \Longrightarrow \quad I_r = \frac{I_x^2}{I_r} + \frac{I_y^2}{I_r}$$

Static Translinear Circuit Synthesis: Pythagorator

Synthesize a two-dimensional vector-magnitude circuit implementing

$$r = \sqrt{x^2 + y^2}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

We represent each signal as a ratio of a signal current to the unit current:

$$x \equiv \frac{I_x}{I_1}, \quad y \equiv \frac{I_y}{I_1}, \quad \text{and} \quad r \equiv \frac{I_r}{I_1}.$$

We substitute these into the original equation and rearrange to obtain

$$\frac{I_r}{I_1} = \sqrt{\left(\frac{I_x}{I_1}\right)^2 + \left(\frac{I_y}{I_1}\right)^2} \quad \Longrightarrow \quad I_r^2 = I_x^2 + I_y^2 \quad \Longrightarrow \quad I_r = \underbrace{\frac{I_x^2}{I_r}}_{I_{r1}} + \underbrace{\frac{I_y^2}{I_r}}_{I_{r2}}$$

Static Translinear Circuit Synthesis: Pythagorator

TLP: $I_{r1}I_r = I_x^2$ KCL: $I_r = I_{r1}+I_{r2}$

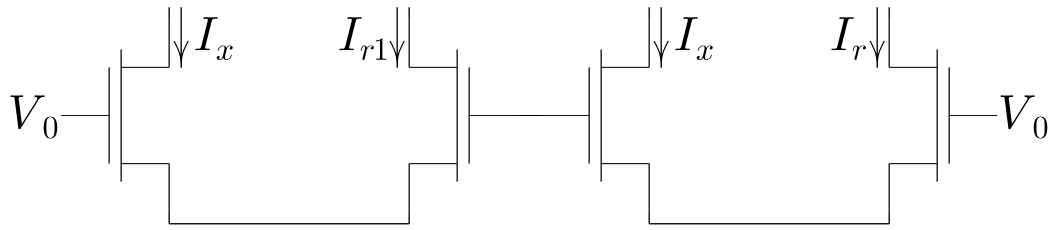
$I_{r2}I_r = I_y^2$

Static Translinear Circuit Synthesis: Pythagorator

TLP: $I_{r1} I_r = I_x^2$

$I_{r2} I_r = I_y^2$

KCL: $I_r = I_{r1} + I_{r2}$

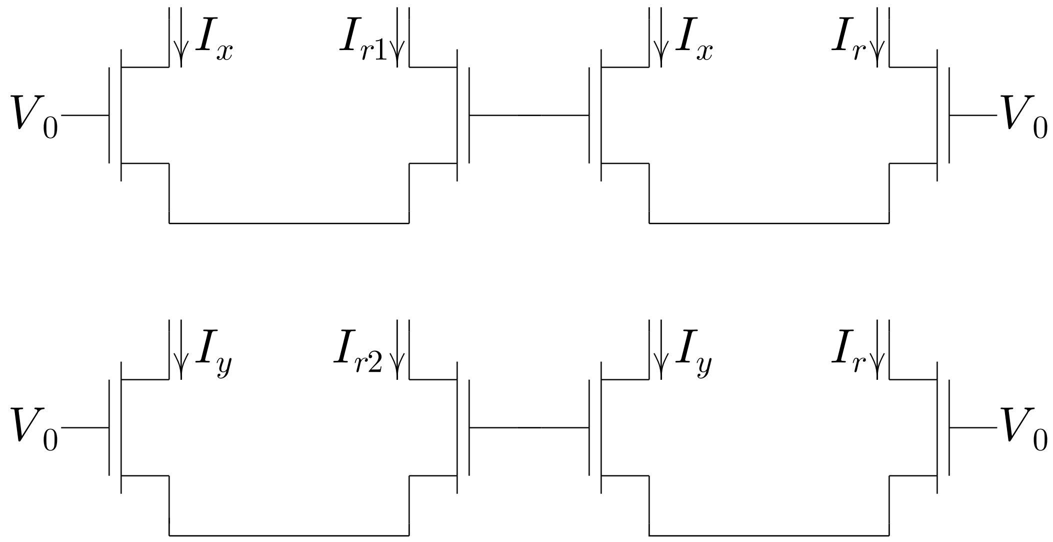


Static Translinear Circuit Synthesis: Pythagorator

TLP: $I_{r1} I_r = I_x^2$

$I_{r2} I_r = I_y^2$

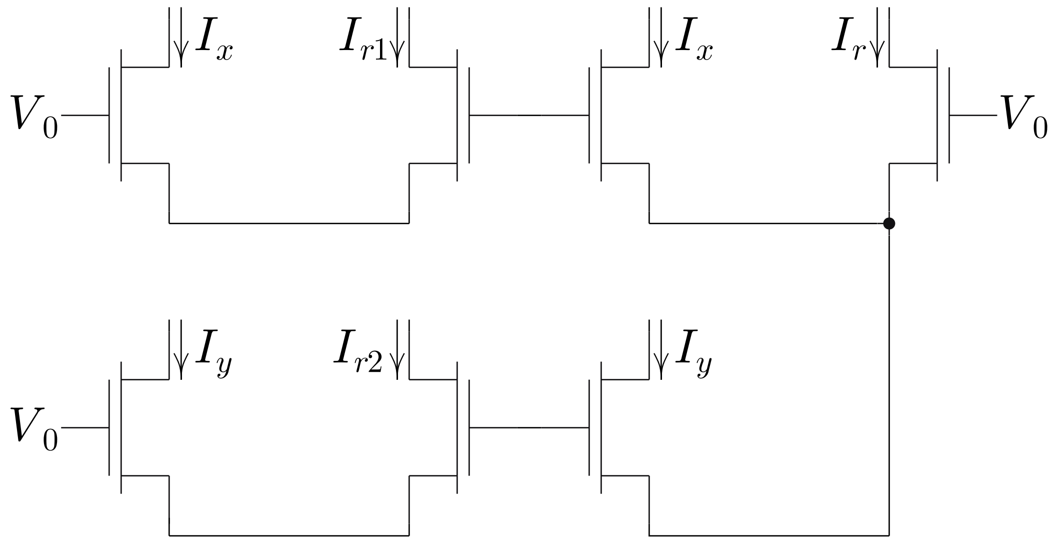
KCL: $I_r = I_{r1} + I_{r2}$



Static Translinear Circuit Synthesis: Pythagorator

TLP: $I_{r1} I_r = I_x^2$
$I_{r2} I_r = I_y^2$

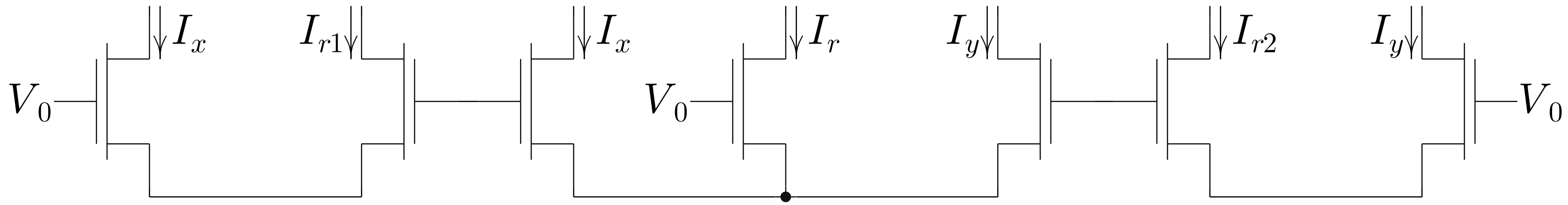
KCL: $I_r = I_{r1} + I_{r2}$



Static Translinear Circuit Synthesis: Pythagorator

TLP: $I_{r1} I_r = I_x^2$
$I_{r2} I_r = I_y^2$

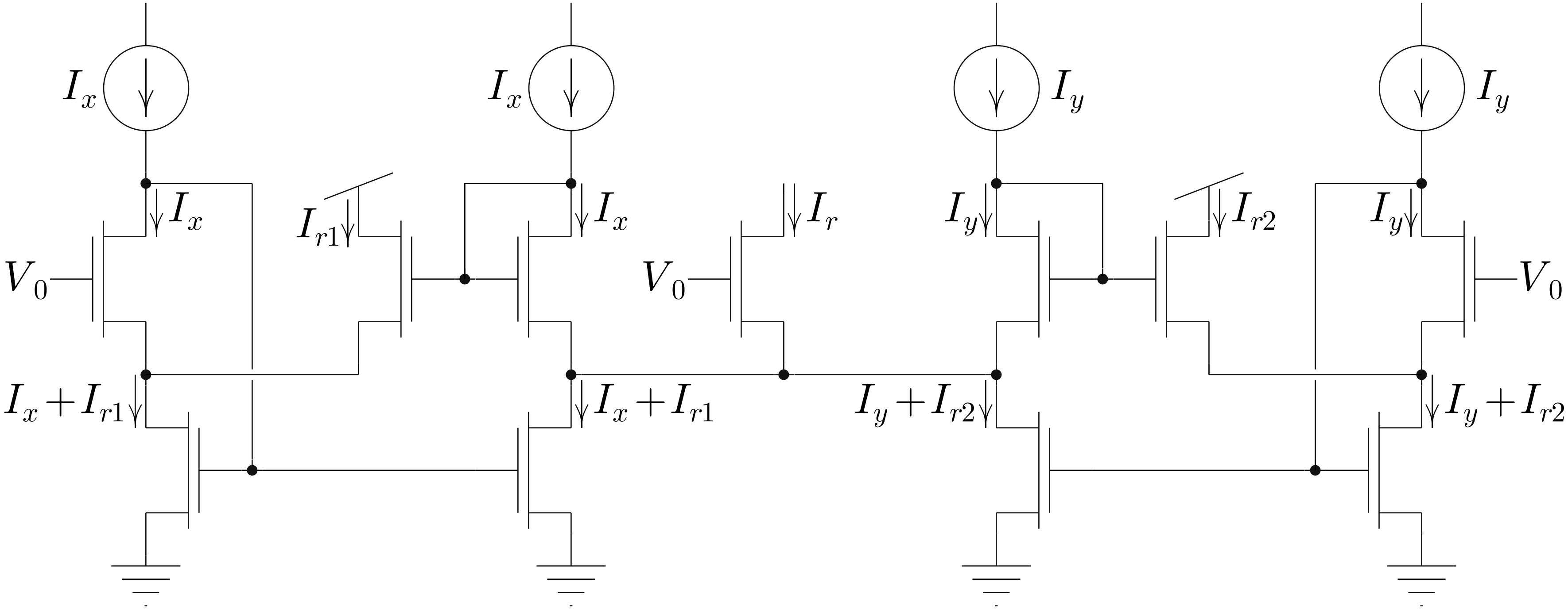
KCL: $I_r = I_{r1} + I_{r2}$



Static Translinear Circuit Synthesis: Pythagorator

TLP: $I_{r1}I_r = I_x^2$
$I_{r2}I_r = I_y^2$

KCL: $I_r = I_{r1} + I_{r2}$



Static Translinear Circuit Synthesis: Vector Normalizer

Synthesize a two-dimensional vector-normalization circuit implementing

$$u = \frac{x}{\sqrt{x^2 + y^2}} \quad \text{and} \quad v = \frac{y}{\sqrt{x^2 + y^2}}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

Static Translinear Circuit Synthesis: Vector Normalizer

Synthesize a two-dimensional vector-normalization circuit implementing

$$u = \frac{x}{\sqrt{x^2 + y^2}} \quad \text{and} \quad v = \frac{y}{\sqrt{x^2 + y^2}}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

Each equation shares $r \equiv \sqrt{x^2 + y^2}$, which we can use to decompose the system as

$$u = \frac{x}{r}, \quad v = \frac{y}{r}, \quad \text{and} \quad r = \sqrt{x^2 + y^2}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

Static Translinear Circuit Synthesis: Vector Normalizer

Synthesize a two-dimensional vector-normalization circuit implementing

$$u = \frac{x}{\sqrt{x^2 + y^2}} \quad \text{and} \quad v = \frac{y}{\sqrt{x^2 + y^2}}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

Each equation shares $r \equiv \sqrt{x^2 + y^2}$, which we can use to decompose the system as

$$u = \frac{x}{r}, \quad v = \frac{y}{r}, \quad \text{and} \quad r = \sqrt{x^2 + y^2}, \quad \text{where} \quad x > 0 \quad \text{and} \quad y > 0.$$

We represent each signal as a ratio of a signal current to the unit current:

$$x \equiv \frac{I_x}{I_1}, \quad y \equiv \frac{I_y}{I_1}, \quad u \equiv \frac{I_u}{I_1}, \quad v \equiv \frac{I_v}{I_1}, \quad \text{and} \quad r \equiv \frac{I_r}{I_1}.$$

Static Translinear Circuit Synthesis: Vector Normalizer

We substitute these into the original equations and rearrange to obtain

$$\frac{I_u}{I_1} = \frac{I_x/I_1}{I_r/I_1} \quad \text{and} \quad \frac{I_v}{I_1} = \frac{I_y/I_1}{I_r/I_1}$$

Static Translinear Circuit Synthesis: Vector Normalizer

We substitute these into the original equations and rearrange to obtain

$$\frac{I_u}{I_1} = \frac{I_x/I_1}{I_r/I_1} \quad \text{and} \quad \frac{I_v}{I_1} = \frac{I_y/I_1}{I_r/I_1} \qquad \Longrightarrow \qquad I_u I_r = I_x I_1 \quad \text{and} \quad I_v I_r = I_y I_1$$

Static Translinear Circuit Synthesis: Vector Normalizer

We substitute these into the original equations and rearrange to obtain

$$\frac{I_u}{I_1} = \frac{I_x/I_1}{I_r/I_1} \quad \text{and} \quad \frac{I_v}{I_1} = \frac{I_y/I_1}{I_r/I_1} \qquad \Longrightarrow \qquad I_u I_r = I_x I_1 \quad \text{and} \quad I_v I_r = I_y I_1$$

and

$$\frac{I_r}{I_1} = \sqrt{\left(\frac{I_x}{I_1}\right)^2 + \left(\frac{I_y}{I_1}\right)^2}$$

Static Translinear Circuit Synthesis: Vector Normalizer

We substitute these into the original equations and rearrange to obtain

$$\frac{I_u}{I_1} = \frac{I_x/I_1}{I_r/I_1} \quad \text{and} \quad \frac{I_v}{I_1} = \frac{I_y/I_1}{I_r/I_1} \quad \Longrightarrow \quad I_u I_r = I_x I_1 \quad \text{and} \quad I_v I_r = I_y I_1$$

and

$$\frac{I_r}{I_1} = \sqrt{\left(\frac{I_x}{I_1}\right)^2 + \left(\frac{I_y}{I_1}\right)^2} \quad \Longrightarrow \quad I_r^2 = I_x^2 + I_y^2$$

Static Translinear Circuit Synthesis: Vector Normalizer

We substitute these into the original equations and rearrange to obtain

$$\frac{I_u}{I_1} = \frac{I_x/I_1}{I_r/I_1} \quad \text{and} \quad \frac{I_v}{I_1} = \frac{I_y/I_1}{I_r/I_1} \quad \Longrightarrow \quad I_u I_r = I_x I_1 \quad \text{and} \quad I_v I_r = I_y I_1$$

and

$$\frac{I_r}{I_1} = \sqrt{\left(\frac{I_x}{I_1}\right)^2 + \left(\frac{I_y}{I_1}\right)^2} \quad \Longrightarrow \quad I_r^2 = I_x^2 + I_y^2 \quad \Longrightarrow \quad I_r = \frac{I_x^2}{I_r} + \frac{I_y^2}{I_r}$$

Static Translinear Circuit Synthesis: Vector Normalizer

We substitute these into the original equations and rearrange to obtain

$$\frac{I_u}{I_1} = \frac{I_x/I_1}{I_r/I_1} \quad \text{and} \quad \frac{I_v}{I_1} = \frac{I_y/I_1}{I_r/I_1} \quad \Longrightarrow \quad I_u I_r = I_x I_1 \quad \text{and} \quad I_v I_r = I_y I_1$$

and

$$\frac{I_r}{I_1} = \sqrt{\left(\frac{I_x}{I_1}\right)^2 + \left(\frac{I_y}{I_1}\right)^2} \quad \Longrightarrow \quad I_r^2 = I_x^2 + I_y^2 \quad \Longrightarrow \quad I_r = \underbrace{\frac{I_x^2}{I_r}}_{I_{r1}} + \underbrace{\frac{I_y^2}{I_r}}_{I_{r2}}$$

Static Translinear Circuit Synthesis: Vector Normalizer

TLP: $I_{r1} I_r = I_x^2$

$I_{r2} I_r = I_y^2$

$I_u I_r = I_x I_1$

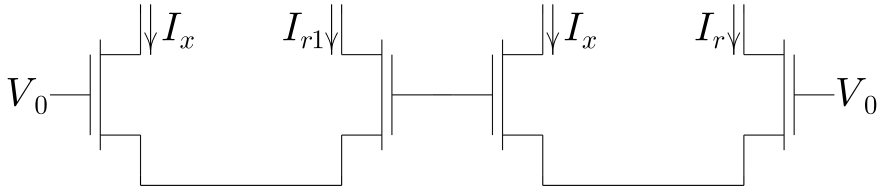
$I_v I_r = I_y I_1$

KCL: $I_r = I_{r1} + I_{r2}$

Static Translinear Circuit Synthesis: Vector Normalizer

TLP: $I_{r1}I_r = I_x^2$
$I_{r2}I_r = I_y^2$
$I_uI_r = I_xI_1$
$I_vI_r = I_yI_1$

KCL: $I_r = I_{r1}+I_{r2}$



Static Translinear Circuit Synthesis: Vector Normalizer

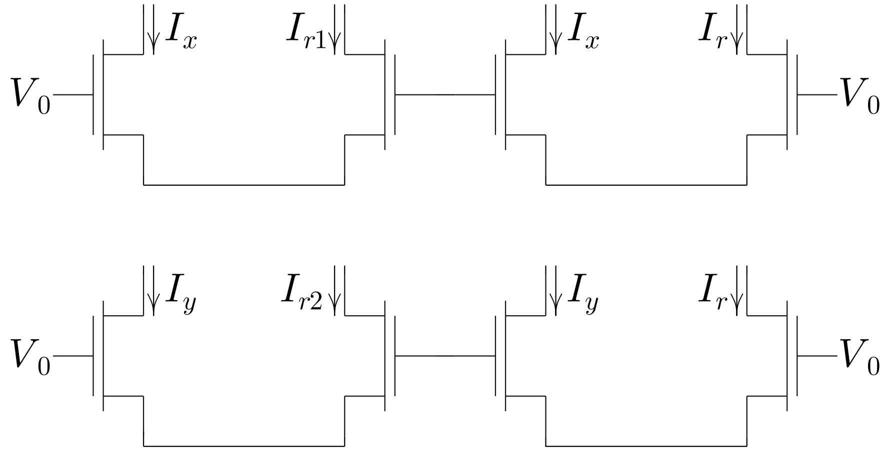
TLP: $I_{r1}I_r = I_x^2$

$I_{r2}I_r = I_y^2$

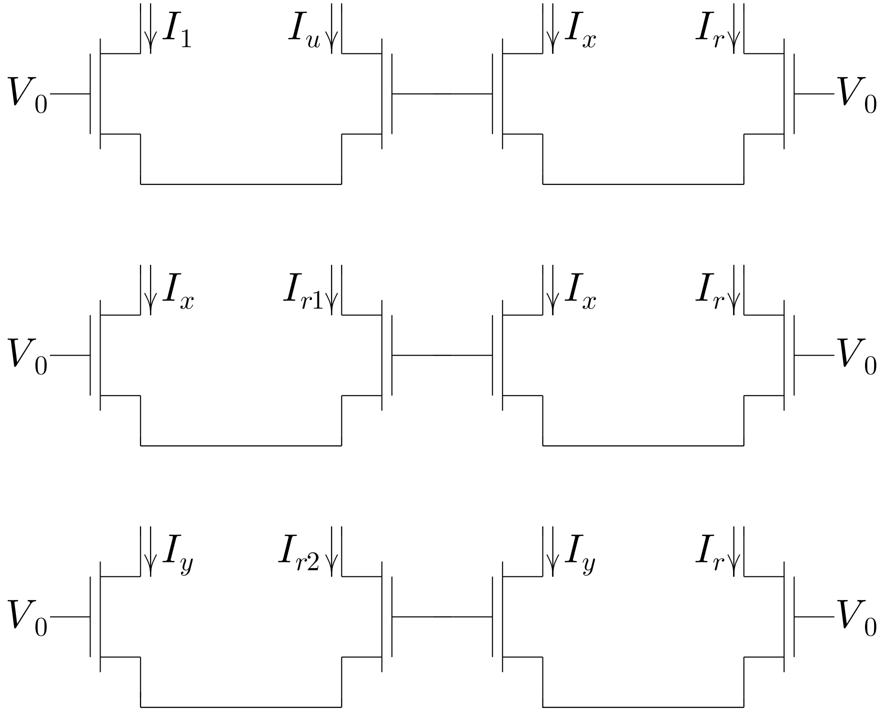
$I_uI_r = I_xI_1$

$I_vI_r = I_yI_1$

KCL: $I_r = I_{r1}+I_{r2}$



Static Translinear Circuit Synthesis: Vector Normalizer



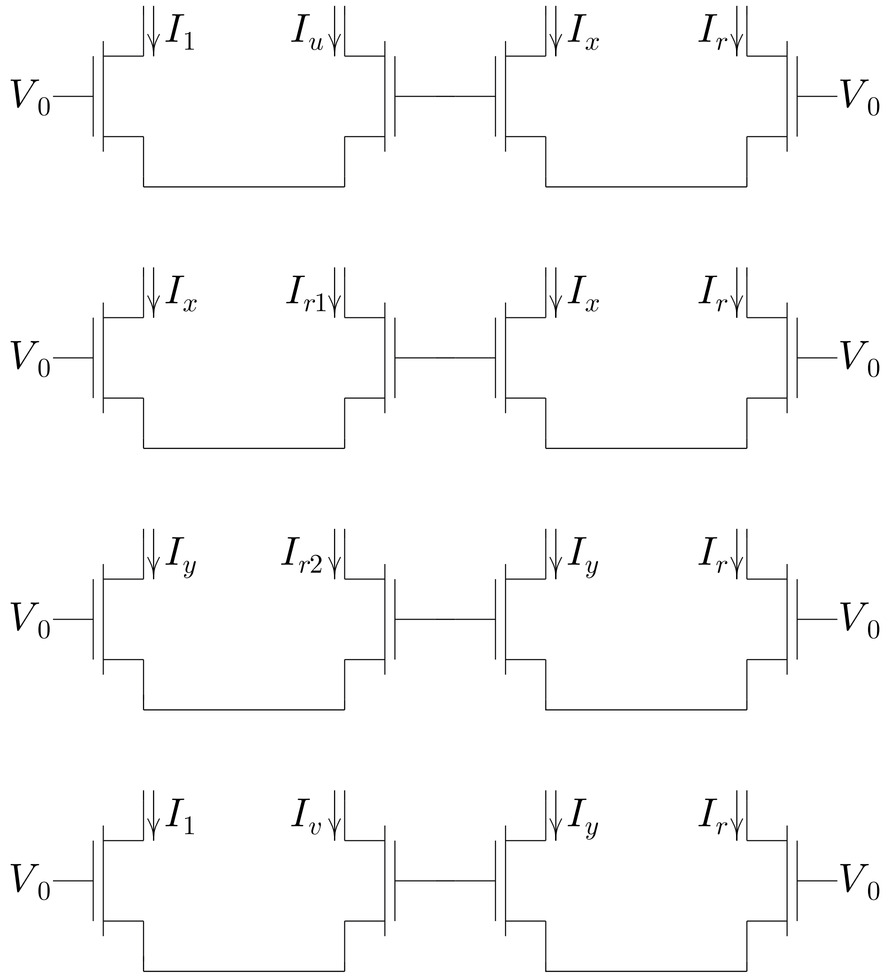
TLP: $I_{r1}I_r = I_x^2$
$I_{r2}I_r = I_y^2$
$I_uI_r = I_xI_1$
$I_vI_r = I_yI_1$

KCL: $I_r = I_{r1}+I_{r2}$

Static Translinear Circuit Synthesis: Vector Normalizer

TLP: $I_{r1}I_r = I_x^2$
$I_{r2}I_r = I_y^2$
$I_uI_r = I_xI_1$
$I_vI_r = I_yI_1$

KCL: $I_r = I_{r1}+I_{r2}$



Static Translinear Circuit Synthesis: Vector Normalizer

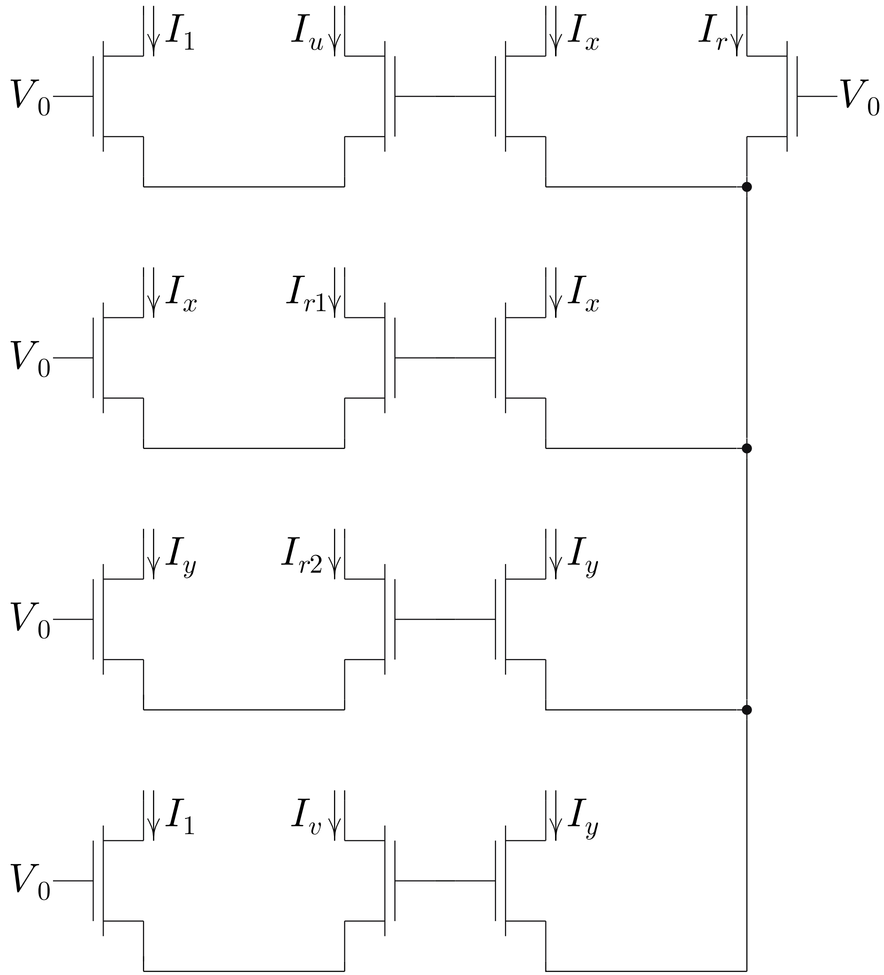
TLP: $I_{r1}I_r = I_x^2$

$I_{r2}I_r = I_y^2$

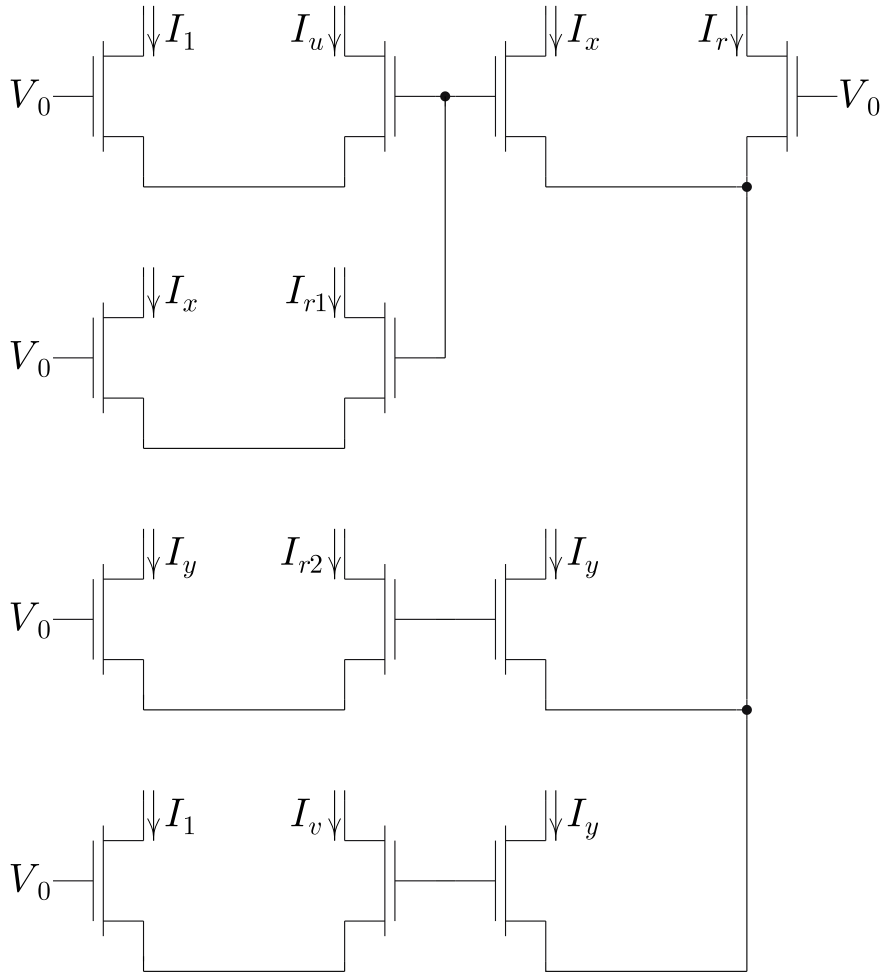
$I_uI_r = I_xI_1$

$I_vI_r = I_yI_1$

KCL: $I_r = I_{r1}+I_{r2}$



Static Translinear Circuit Synthesis: Vector Normalizer



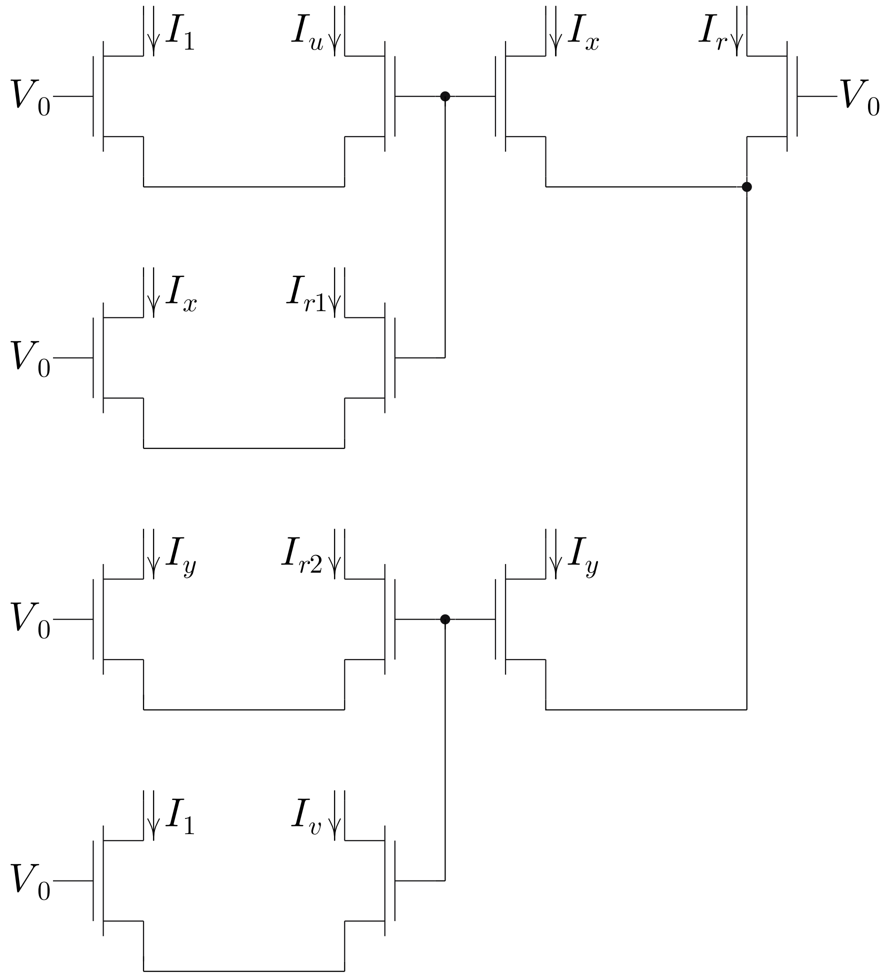
TLP: $I_{r1}I_r = I_x^2$
$I_{r2}I_r = I_y^2$
$I_uI_r = I_xI_1$
$I_vI_r = I_yI_1$

KCL: $I_r = I_{r1}+I_{r2}$

Static Translinear Circuit Synthesis: Vector Normalizer

TLP: $I_{r1}I_r = I_x^2$
$I_{r2}I_r = I_y^2$
$I_uI_r = I_xI_1$
$I_vI_r = I_yI_1$

KCL: $I_r = I_{r1} + I_{r2}$



Olin College

MAD VLSI
Circuits & Systems Lab

Static Translinear Circuit Synthesis: Vector Normalizer

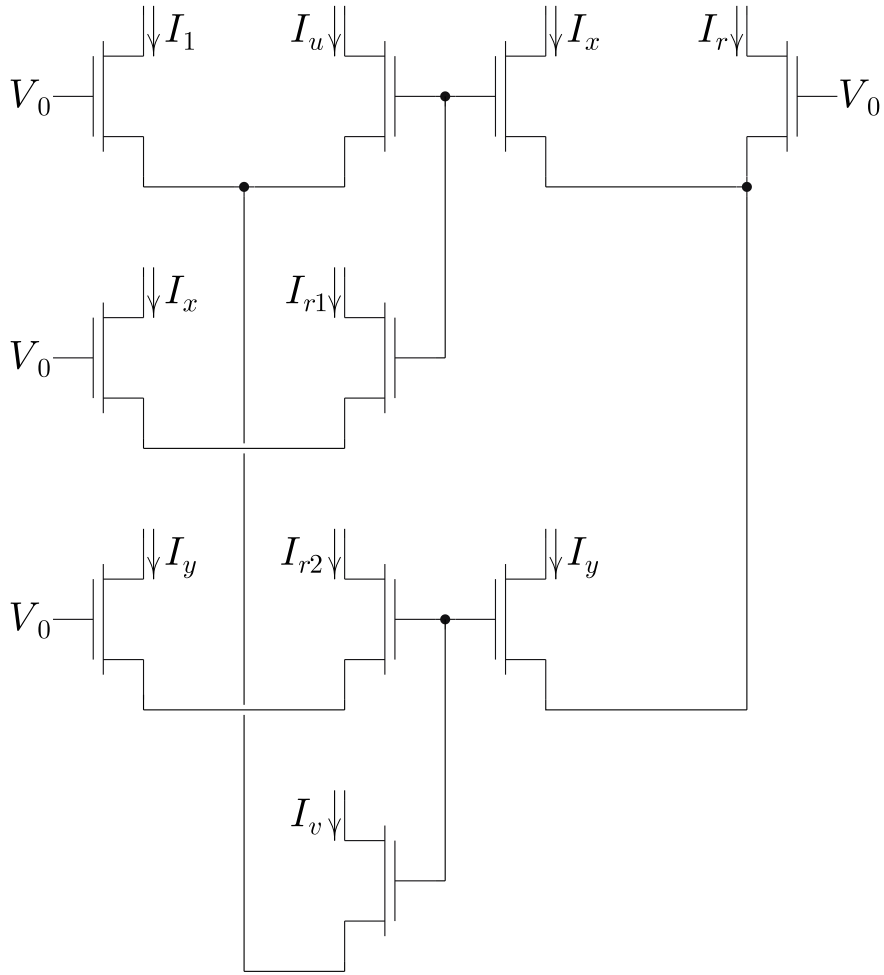
TLP: $I_{r1}I_r = I_x^2$

$I_{r2}I_r = I_y^2$

$I_uI_r = I_xI_1$

$I_vI_r = I_yI_1$

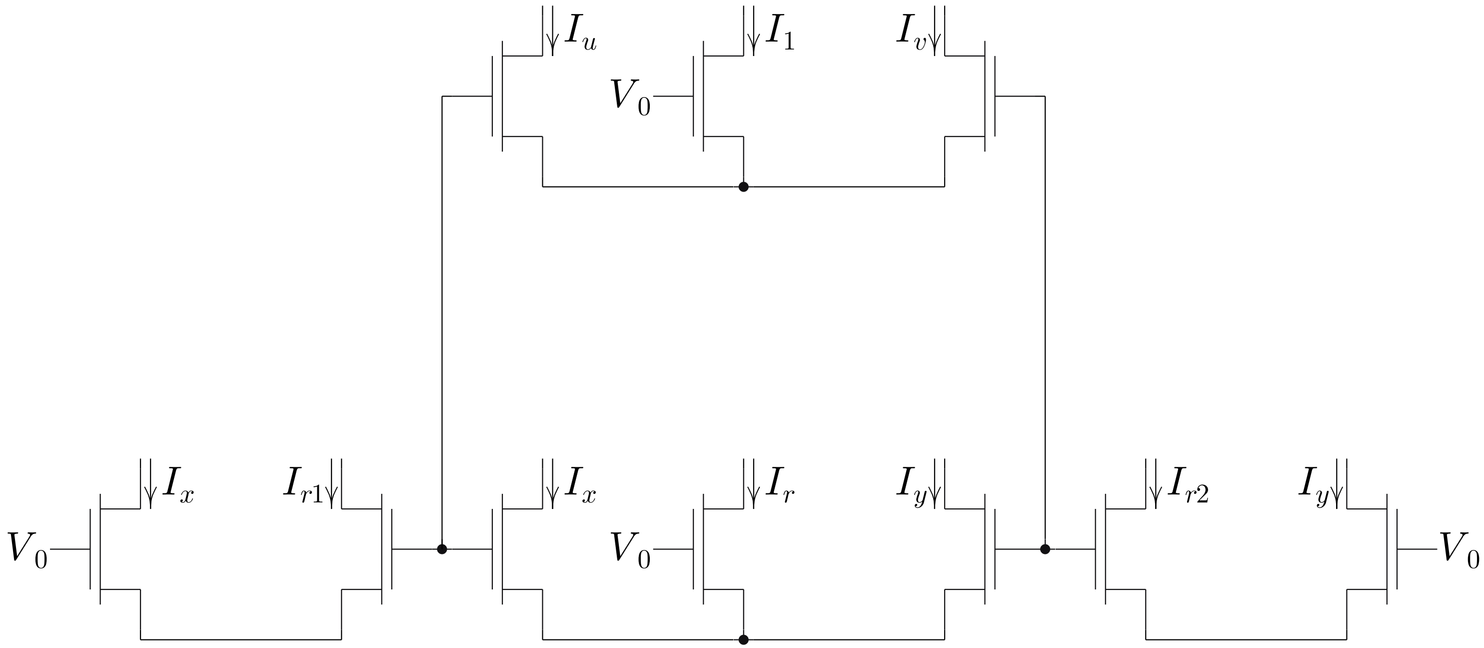
KCL: $I_r = I_{r1}+I_{r2}$



Static Translinear Circuit Synthesis: Vector Normalizer

TLP: $I_{r1} I_r = I_x^2$
$I_{r2} I_r = I_y^2$
$I_u I_r = I_x I_1$
$I_v I_r = I_y I_1$

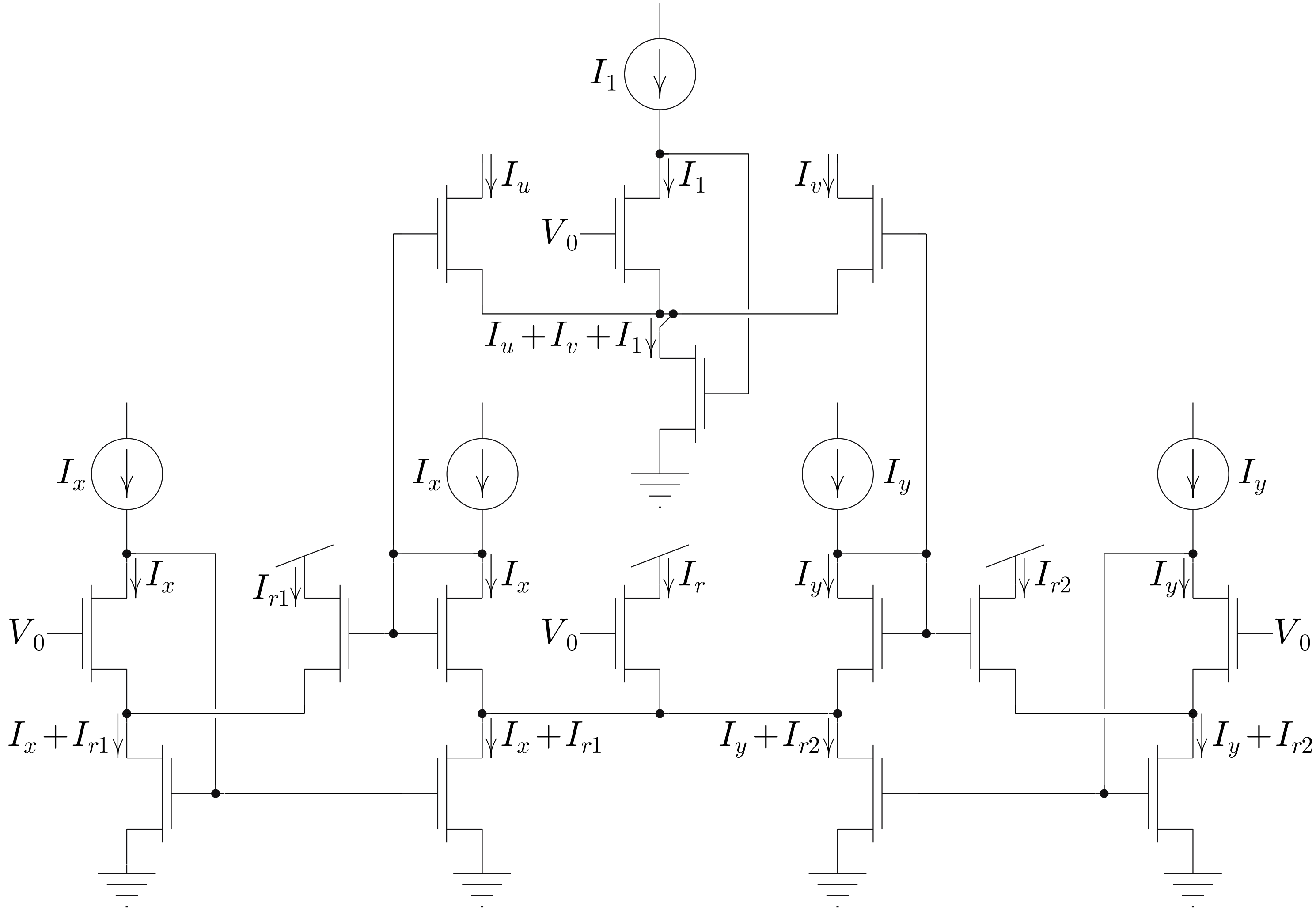
KCL: $I_r = I_{r1} + I_{r2}$



Static Translinear Circuit Synthesis: Vector Normalizer

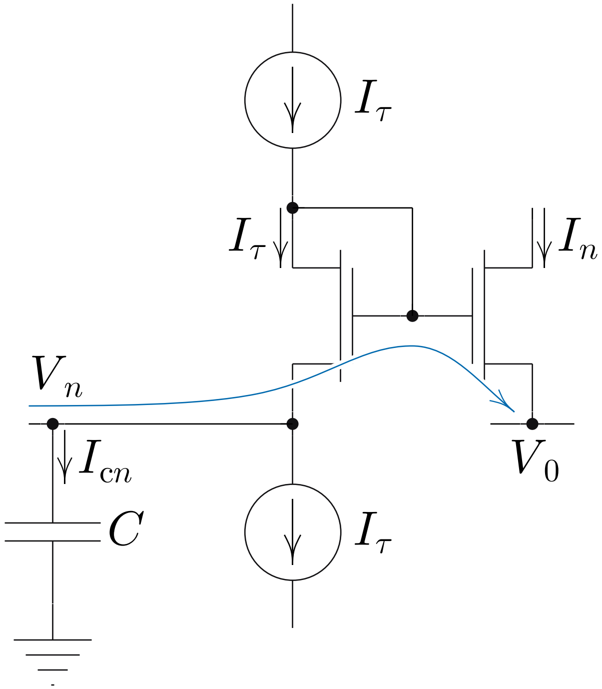
TLP: $I_{r1} I_r = I_x^2$
$I_{r2} I_r = I_y^2$
$I_u I_r = I_x I_1$
$I_v I_r = I_y I_1$

KCL: $I_r = I_{r1} + I_{r2}$



Dynamic Translinear Circuit Synthesis: Output Structures

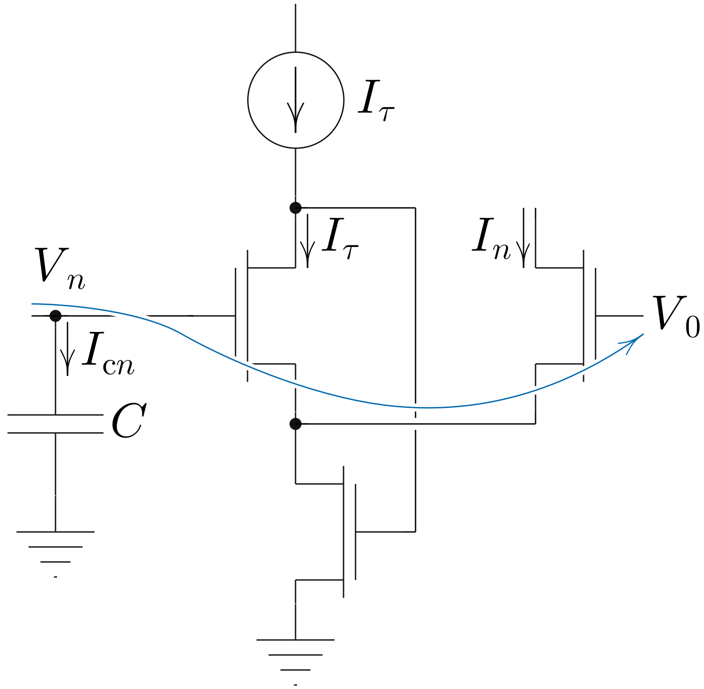
noninverting



$$I_n = I_\tau e^{(V_n - V_0)/U_\mathrm{T}}$$

$$\frac{\partial I_n}{\partial V_n} = \frac{I_n}{U_\mathrm{T}}$$

inverting



$$I_n = I_\tau e^{\kappa(V_0 - V_n)/U_\mathrm{T}}$$

$$\frac{\partial I_n}{\partial V_n} = -\frac{\kappa I_n}{U_\mathrm{T}}$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

Synthesize a first-order low-pass filter described by

$$\tau \frac{dy}{dt} + y = x, \quad \text{where} \quad x > 0.$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

Synthesize a first-order low-pass filter described by

$$\tau \frac{dy}{dt} + y = x, \quad \text{where} \quad x > 0.$$

We represent each signal as a ratio of a signal current to the unit current:

$$x \equiv \frac{I_x}{I_1} \quad \text{and} \quad y \equiv \frac{I_y}{I_1}.$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

Synthesize a first-order low-pass filter described by

$$\tau \frac{dy}{dt} + y = x, \quad \text{where} \quad x > 0.$$

We represent each signal as a ratio of a signal current to the unit current:

$$x \equiv \frac{I_x}{I_1} \quad \text{and} \quad y \equiv \frac{I_y}{I_1}.$$

Substituting these into the ODE, we obtain

$$\tau \frac{d}{dt}\left(\frac{I_y}{I_1}\right) + \frac{I_y}{I_1} = \frac{I_x}{I_1}$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

Synthesize a first-order low-pass filter described by

$$\tau \frac{dy}{dt} + y = x, \quad \text{where} \quad x > 0.$$

We represent each signal as a ratio of a signal current to the unit current:

$$x \equiv \frac{I_x}{I_1} \quad \text{and} \quad y \equiv \frac{I_y}{I_1}.$$

Substituting these into the ODE, we obtain

$$\tau \frac{d}{dt}\left(\frac{I_y}{I_1}\right) + \frac{I_y}{I_1} = \frac{I_x}{I_1} \quad \Longrightarrow \quad \tau \frac{dI_y}{dt} + I_y = I_x.$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

To implement the time derivative, we introduce a log-compressed voltage state variable, V_y. Using the chain rule, we can express the preceding equation as

$$\tau \frac{\partial I_y}{\partial V_y} \cdot \frac{dV_y}{dt} + I_y = I_x$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

To implement the time derivative, we introduce a log-compressed voltage state variable, V_y. Using the chain rule, we can express the preceding equation as

$$\tau \frac{\partial I_y}{\partial V_y} \cdot \frac{dV_y}{dt} + I_y = I_x \quad \Longrightarrow \quad \tau \left(-\frac{\kappa}{U_\mathrm{T}} I_y \right) \frac{dV_y}{dt} + I_y = I_x$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

To implement the time derivative, we introduce a log-compressed voltage state variable, V_y. Using the chain rule, we can express the preceding equation as

$$\tau \frac{\partial I_y}{\partial V_y} \cdot \frac{dV_y}{dt} + I_y = I_x \quad \Longrightarrow \quad \tau \left(-\frac{\kappa}{U_\mathrm{T}} I_y \right) \frac{dV_y}{dt} + I_y = I_x$$

$$\Longrightarrow -\frac{\kappa\tau}{U_\mathrm{T}} \cdot \frac{dV_y}{dt} + 1 = \frac{I_x}{I_y}$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

To implement the time derivative, we introduce a log-compressed voltage state variable, V_y. Using the chain rule, we can express the preceding equation as

$$\tau \frac{\partial I_y}{\partial V_y} \cdot \frac{dV_y}{dt} + I_y = I_x \quad \Longrightarrow \quad \tau \left(-\frac{\kappa}{U_\mathrm{T}} I_y \right) \frac{dV_y}{dt} + I_y = I_x$$

$$\Longrightarrow \; -\frac{\kappa\tau}{U_\mathrm{T}} \cdot \frac{dV_y}{dt} + 1 = \frac{I_x}{I_y} \quad \Longrightarrow \quad -\frac{\kappa\tau}{CU_\mathrm{T}} \cdot C\frac{dV_y}{dt} + 1 = \frac{I_x}{I_y}$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

To implement the time derivative, we introduce a log-compressed voltage state variable, V_y. Using the chain rule, we can express the preceding equation as

$$\tau \frac{\partial I_y}{\partial V_y} \cdot \frac{dV_y}{dt} + I_y = I_x \quad \Longrightarrow \quad \tau \left(-\frac{\kappa}{U_\mathrm{T}} I_y \right) \frac{dV_y}{dt} + I_y = I_x$$

$$\Longrightarrow \; -\frac{\kappa\tau}{U_\mathrm{T}} \cdot \frac{dV_y}{dt} + 1 = \frac{I_x}{I_y} \quad \Longrightarrow \quad -\underbrace{\frac{\kappa\tau}{CU_\mathrm{T}}}_{1/I_\tau} \cdot \underbrace{C\frac{dV_y}{dt}}_{I_c} + 1 = \frac{I_x}{I_y}$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

To implement the time derivative, we introduce a log-compressed voltage state variable, V_y. Using the chain rule, we can express the preceding equation as

$$\tau \frac{\partial I_y}{\partial V_y} \cdot \frac{dV_y}{dt} + I_y = I_x \quad \Longrightarrow \quad \tau \left(-\frac{\kappa}{U_\mathrm{T}} I_y \right) \frac{dV_y}{dt} + I_y = I_x$$

$$\Longrightarrow -\frac{\kappa\tau}{U_\mathrm{T}} \cdot \frac{dV_y}{dt} + 1 = \frac{I_x}{I_y} \quad \Longrightarrow \quad -\underbrace{\frac{\kappa\tau}{CU_\mathrm{T}}}_{1/I_\tau} \cdot \underbrace{C\frac{dV_y}{dt}}_{I_c} + 1 = \frac{I_x}{I_y}$$

$$\Longrightarrow -\frac{I_c}{I_\tau} + 1 = \frac{I_x}{I_y}$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

To implement the time derivative, we introduce a log-compressed voltage state variable, V_y. Using the chain rule, we can express the preceding equation as

$$\tau \frac{\partial I_y}{\partial V_y} \cdot \frac{dV_y}{dt} + I_y = I_x \quad \Longrightarrow \quad \tau \left(-\frac{\kappa}{U_\mathrm{T}} I_y \right) \frac{dV_y}{dt} + I_y = I_x$$

$$\Longrightarrow \; -\frac{\kappa\tau}{U_\mathrm{T}} \cdot \frac{dV_y}{dt} + 1 = \frac{I_x}{I_y} \quad \Longrightarrow \quad -\underbrace{\frac{\kappa\tau}{CU_\mathrm{T}}}_{1/I_\tau} \cdot \underbrace{C\frac{dV_y}{dt}}_{I_c} + 1 = \frac{I_x}{I_y}$$

$$\Longrightarrow \; -\frac{I_c}{I_\tau} + 1 = \frac{I_x}{I_y} \quad \Longrightarrow \quad I_\tau - I_c = \frac{I_\tau I_x}{I_y}.$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

To implement the time derivative, we introduce a log-compressed voltage state variable, V_y. Using the chain rule, we can express the preceding equation as

$$\tau \frac{\partial I_y}{\partial V_y} \cdot \frac{dV_y}{dt} + I_y = I_x \quad \Longrightarrow \quad \tau \left(-\frac{\kappa}{U_\mathrm{T}} I_y \right) \frac{dV_y}{dt} + I_y = I_x$$

$$\Longrightarrow \; -\frac{\kappa\tau}{U_\mathrm{T}} \cdot \frac{dV_y}{dt} + 1 = \frac{I_x}{I_y} \quad \Longrightarrow \quad -\underbrace{\frac{\kappa\tau}{CU_\mathrm{T}}}_{1/I_\tau} \cdot \underbrace{C\frac{dV_y}{dt}}_{I_c} + 1 = \frac{I_x}{I_y}$$

$$\Longrightarrow \; -\frac{I_c}{I_\tau} + 1 = \frac{I_x}{I_y} \quad \Longrightarrow \quad I_\tau - I_c = \frac{I_\tau I_x}{\underbrace{I_y}_{I_p}}.$$

Dynamic Translinear Circuit Synthesis: First-Order LPF

TLP: $I_p I_y = I_x I_\tau$ KCL: $I_c + I_p = I_\tau$

Dynamic Translinear Circuit Synthesis: First-Order LPF

TLP: $I_p I_y = I_x I_\tau$ KCL: $I_c + I_p = I_\tau$

Dynamic Translinear Circuit Synthesis: First-Order LPF

TLP: $I_p I_y = I_x I_\tau$ KCL: $I_c + I_p = I_\tau$