Generalized Optimization Methodology for System Design

ALEXANDER ZEMLIAK[1,2], RICARDO PEÑA[3], EDUARDO RIOS[4]
[1]Department of Physics and Mathematics, [3]Institute of Sciences, [4]Department of Electronics
Autonomous University of Puebla
MEXICO
[2]Institute of Physics and Technology
National Technical University of Ukraine
UKRAINE
azemliak@fcfm.buap.mx, dapena@siu.buap.mx, erios@ece.buap.mx

Abstract: **-** The new general methodology for the analog system optimization was elaborated by means of the optimum control theory formulation in order to improve the characteristics of the system design process. A special control vector is defined to redistribute the compute expensive between a network analysis and a parametric optimization. This approach generalizes the design process and generates a set of the different optimization strategies that serves as the structural basis to the optimal design strategy construction. The principal difference between this new methodology and before elaborated theory is the more general approach on the definition of the system parameters and more broadened structural basis. The main equations for the system optimization process were elaborated. These equations include the special control functions that generalize the total system optimization process. Numerical results that include as passive and active nonlinear networks demonstrate the efficiency and perspective of the proposed approach.

Key-Words: - Time-optimal design algorithm, control theory formulation, general methodology.

1 Introduction

The computer time reduction of a large system design is one of the sources of the total quality design improvement. This problem has a great significance because it has a lot of applications, for example on VLSI electronic circuit design. Any traditional system design strategy includes two main parts: the mathematical model of the physical system that can be defined by the algebraic equations or differential-integral equations and optimization procedure that achieves the optimum point of the design objective function. In limits of this conception it is possible to change optimization strategy and use the different models and different methods of analysis but in each step of the circuit optimization process there are a fixed number of the equations of the mathematical model and a fixed number of the independent parameters of the optimization procedure.

There are some powerful methods that reduce the necessary time for the circuit analysis. Because a matrix of the large-scale circuit is a very sparse, the special sparse matrix techniques are used successfully for this purpose [1]. Other approach to reduce the amount of computational required for both linear and nonlinear equations is based on the decomposition techniques. The partitioning of a circuit matrix into bordered-block diagonal form can be done by branches tearing as in [2], or by nodes tearing as in [3] and jointly with direct solution algorithms gives the solution of the problem. The extension of the direct solution methods can be obtained by hierarchical decomposition and macromodel representation [4]. Other approach for achieving decomposition at the nonlinear level consists on a special iteration techniques and has been realized in [5] for the iterated timing analysis and circuit simulation. Optimization technique that is used for the circuit optimization and design, exert a very strong influence on the total necessary computer time too. The numerical methods are developed both for the unconstrained and for the constrained optimization [6] and will be improved later on. The practical aspects of these methods were developed for the electronic circuits design with the different optimization criterions [7]. The fundamental problems of the development, structure elaboration, and adaptation of the automation design systems have been examine in some papers [8]-[9].

The above described system design ideas can be named as the traditional approach or the traditional strategy because the analysis method is based on the Kirchhoff laws.

The other formulation of the circuit optimization problem was developed on heuristic level some decades ago [10]. This idea was based on the

Kirchhoff laws ignoring for all the circuit or for the circuit part. The special cost function is minimized instead of the circuit equation solving. This idea was developed in practical aspect for the microwave circuit optimization [11] and for the synthesis of high-performance analog circuits [12] in extremely case, when the total system model was eliminated. The authors of the last papers affirm that the design time was reduced significantly. This last idea can be named as the modified traditional design strategy.

Nevertheless all these ideas can be generalized to reduce the total computer design time for the system design. This generalization can be done on the basis of the control theory approach and includes the special control function to control the design process. This approach consists of the reformulation of the total design problem and generalization of it to obtain a set of different design strategies inside the same optimization procedure [13]. The number of the different design strategies, which appear in the generalized theory, is equal to 2^M for the constant value of all the control functions, where M is the number of dependent parameters. These strategies serve as the structural basis for more strategies construction with the variable control functions. The main problem of this new formulation is the unknown optimal dependency of the control function vector that satisfies to the time-optimal design algorithm.

However, the developed theory [13] is not the most general. In the limits of this approach only initially dependent system parameters can be transformed to the independent but the inverse transformation is not supposed. The next more general approach for the system design supposes that initially independent and dependent system parameters are completely equal in rights, i.e. any system parameter can be defined as independent or dependent one. In this case we have more vast set of the design strategies that compose the structural basis and more possibility to the optimal design strategy construct.

2 Problem Formulation

In accordance with the new system design methodology [13] the design process can be defined as the problem of the cost function $C(X)$ minimization for $X \in R^N$ by the optimization procedure and by the analysis of the modified electronic system model. The optimization procedure can be determined in continuous form as:

$$\frac{dx_i}{dt} = f_i(X,U), \quad i=1,2,...,N \tag{1}$$

The modified electronic system model can be expressed in the next form:

$$(1-u_j)g_j(X) = 0, \quad j = 1,2,\dots,M \tag{2}$$

where $N=K+M$, K is the number of independent system parameters, M is the number of dependent system parameters, X is the vector of all variables $X = (x_1, x_2, \dots, x_K, x_{K+1}, x_{K+2}, \dots, x_N)$; U is the vector of control variables $U = (u_1, u_2, \dots, u_M)$; $u_j \in \Omega$; $\Omega = \{0;1\}$.

The functions of the right hand part of the system (1) depend on the concrete optimization algorithm and, for instance, for the gradient method are determined as:

$$f_i(X,U) = -b\frac{\delta}{\delta x_i}\left\{C(X) + \frac{1}{\varepsilon}\sum_{j=1}^{M} u_j g_j^2(X)\right\} \tag{3}$$

for $i = 1,2,\dots,K$,

$$f_i(X,U) = -b\cdot u_{i-K}\frac{\delta}{\delta x_i}\left\{C(X) + \frac{1}{\varepsilon}\sum_{j=1}^{M} u_j g_j^2(X)\right\} + \frac{(1-u_{i-K})}{dt}\left\{-x_i' + \eta_i(X)\right\} \tag{3'}$$

for $i = K+1, K+2, \dots, N$,

where b is the iteration parameter; the operator $\frac{\delta}{\delta x_i}$ hear and below means $\frac{\delta}{\delta x_i}\varphi(X) = \frac{\partial \varphi(X)}{\partial x_i} + \sum_{p=K+1}^{K+M}\frac{\partial \varphi(X)}{\partial x_p}\frac{\partial x_p}{\partial x_i}$, x_i' is equal to $x_i(t-dt)$; $\eta_i(X)$ is the implicit function ($x_i = \eta_i(X)$) that is determined by the system (2), $C(X)$ is the cost function of the design process.

The problem of the optimal design algorithm searching is determined now as the typical problem of the functional minimization of the control theory. The total computer design time serves as the necessary functional in this case. The optimal or quasi-optimal problem solution can be obtained on the basis of analytical [14] or numerical [15]-[18] methods. By this formulation the initially dependent parameters for $i = K+1, K+2, ..., N$ can be transformed to the independent ones when u_j=1 and it is dependent when u_j=0. On the other hand the initially independent parameters for $i = 1,2,\ldots,K$, are independent ones always.

We have been developed in the present paper the new approach that permits to generalize more the above described design methodology. We suppose now that all of the system parameters can be independent or dependent ones. In this case we need to change the equation (2) for the system model definition and the equation (3) for the right parts description.

The equation (2) defines the system model and is transformed now to the next one:

$$(1-u_i)g_j(X)=0\,,\; i=1,2,\ldots,N,\;\; j\in J \qquad (4)$$

where J is the index set for all those functions $g_j(X)$ for which $u_i = 0$, $J = \{j_1, j_2, \ldots, j_z\}$, $j_s \in \Pi$ with $s = 1, 2, \ldots, Z$, Π is the set of the indexes from 1 to M, $\Pi = \{1, 2, \ldots, M\}$, Z is the number of the equations that will be left in the system (4), $Z \in \{0, 1, \ldots, M\}$. The traditional design strategy (TDS) is defined now by the control vector (11…100…0) with K units and M zeros, the modified traditional design strategy (MTDS) is defined by the control vector (11…1) with N units.

The right hand side of the system (1) is defined now as:

$$\begin{aligned} f_i(X,U) = -b\cdot u_i\,\frac{\delta}{\delta x_i}F(X,U) \\ +\frac{(1-u_i)}{dt}\{-x_i(t-dt)+\eta(X)\} \end{aligned} \qquad (5)$$

for $i = 1,2,\ldots,N$,

where $F(X,U)$ is the generalized objective function and it is defined as:

$$F(X,U)=C(X)+\frac{1}{\varepsilon}\sum_{j\in\Pi\backslash J} g_j^2(X) \qquad (6)$$

This new definition of the design process is more general than in [13]. It generalizes the methodology for the system design and produces more representative structural basis of different design strategies. The total number of the different design strategies, which compose the structural basis, is equal to $\sum_{i=0}^{M} C_{K+M}^{i}$. We expect the new possibilities to accelerate the design process.

3 Numerical Results

New generalized methodology has been used for optimization of some non-linear electronic circuits. The numerical results correspond to the integration of the system (1) with variable optimized step. The cost function $C(X)$ has been defined as a sum of squares of differences between before defined and current value of some node voltages.

3.1 Example 1

In Fig. 1 there is a circuit that has seven parameters, i.e. four admittances y_1, y_2, y_3, y_4 and three nodal voltages V_1, V_2, V_3. The nonlinear elements were defined by the following dependencies: $y_{n1}=a_{n1}+b_{n1}\cdot(V_1-V_2)^2$, $y_{n2}=a_{n2}+b_{n2}\cdot(V_2-V_3)^2$.

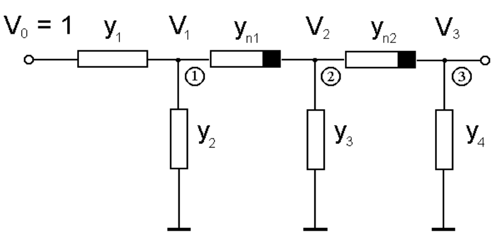

Fig. 1. Three-node circuit topology.

The vector X includes seven components: $x_1^2=y_1$, $x_2^2=y_2$, $x_3^2=y_3$, $x_4^2=y_4$, $x_5=V_1$, $x_6=V_2$, $x_7=V_3$ The mathematical model of this circuit (4) includes three equations (M=3), and the functions $g_j(X)$ are defined by the formulas:

$$g_1(X)\equiv -x_1^2+(x_1^2+x_2^2)x_5+\left[a_{n1}+b_{n1}(x_5-x_6)^2\right](x_5-x_6)=0$$

$$\begin{aligned} g_2(X)\equiv x_3^2x_6+\left[a_{n1}+b_{n1}(x_5-x_6)^2\right](x_6-x_5) \\ +\left[a_{n2}+b_{n2}(x_6-x_7)^2\right](x_6-x_7)=0 \end{aligned} \qquad (7)$$

$$g_3(X)\equiv x_4^2x_7+\left[a_{n2}+b_{n2}(x_6-x_7)^2\right](x_7-x_6)=0$$

The optimization procedure (1), (5) includes seven equations. The cost function $C(X)$ is defined by the formula: $C(X)=(V_1-V_2-k_1)^2+(V_2-V_3-k_2)^2+(V_3-k_3)^2$.

The total structural basis contains $\sum_{i=0}^{3} C_7^i = 64$ different strategies. For instance, the structural basis of the previous developed methodology includes only $2^3=8$ different strategies. The design results for all of the "old" strategies and for some of the new strategies are presented in Table 1.

Table 1. Some strategies of structural basis for three-node circuit.

N	Control functions vector U (u1,u2,u3,u4,u5,u6,u7)	Calculation results	
		Iterations number	Total design time (sec)
1	(0 1 0 1 1 1 1)	1127	0,8414
2	(0 1 1 0 1 1 1)	63	0,0122
3	(0 1 1 1 0 1 0)	2502	1,8411
4	(0 1 1 1 1 0 1)	1390	0,9731
5	(0 1 1 1 1 1 0)	224	0,3571
6	(0 1 1 1 1 1 1)	43	0,0125
7	(1 0 1 1 1 1 0)	354	0,5205
8	(1 0 1 1 1 1 1)	2190	1,1601
9	(1 1 0 0 1 1 1)	326	0,5042
10	(1 1 1 0 0 1 1)	23	0,0161
11	(1 1 1 0 1 0 1)	14	0,0099
12	(1 1 1 0 1 1 0)	27	0,0103
13	(1 1 1 0 1 1 1)	51	0,0102
14	(1 1 1 1 0 0 0)	59	0,2291
15	(1 1 1 1 0 0 1)	167	0,2732
16	(1 1 1 1 0 1 0)	174	0,2911
17	(1 1 1 1 0 1 1)	185	0,1543
18	(1 1 1 1 1 0 0)	63	0,1228
19	(1 1 1 1 1 0 1)	198	0,2451
20	(1 1 1 1 1 1 0)	228	0,2582
21	(1 1 1 1 1 1 1)	293	0,1765

Among the “old” strategies (14-21) there are three strategies (17, 18, and 21) that have the design time lesser than the traditional strategy 14. However, the time gain is not very large. The best strategy 18 among all of the “old” strategies has the time gain 1.86 only. Nevertheless, among the new strategies we have some ones (2, 6, 10, 11, 12, 13) that have the design time significantly lesser than the TDS and they have the time gain more than 14. The optimal strategy among all of the presented is the number 11. It has the computer time gain 23.1 times with respect to the traditional design strategy.

3.2 Example 2

The four-node circuit is analyzed below (Fig. 2) by means of the new generalized methodology. The design problem includes five parameters as admittances $(x_1, x_2, x_3, x_4, x_5)$, where $x_1^2 = y_1$, $x_2^2 = y_2$,

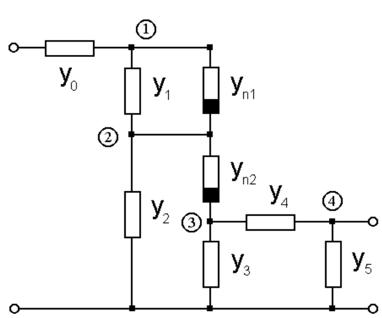

Fig. 2. Four-node circuit topology.

$x_3^2 = y_3$, $x_4^2 = y_4$, $x_5^2 = y_5$, and four parameters as nodal voltages (x_6, x_7, x_8, x_9), where $x_6 = V_1$, $x_7 = V_2$, $x_8 = V_3$, $x_9 = V_4$, The nonlinear elements are defined as: $y_{n1} = a_{n1} + b_{n1} \cdot (V_1 - V_2)^2$, $y_{n2} = a_{n2} + b_{n2} \cdot (V_2 - V_3)^2$. The control vector U includes nine components $(u_1, u_2, ..., u_9)$. The model of circuit (4) includes 4 equations and functions $g_j(X)$ are defined by (8):

$$
\begin{aligned}
&g_1(X) \equiv y_0(V_0 - x_6) - \left[x_1^2 + a_{n1} + b_{n1}(x_6 - x_7)^2\right](x_6 - x_7) = 0 \\
&g_2(X) \equiv \left[x_1^2 + a_{n1} + b_{n1}(x_6 - x_7)^2\right](x_6 - x_7) \\
&\qquad - x_2^2 x_7 - \left[a_{n2} + b_{n2}(x_7 - x_8)^2\right](x_7 - x_8) = 0 \\
&g_3(X) \equiv \left[a_{n2} + b_{n2}(x_7 - x_8)^2\right](x_7 - x_8) \\
&\qquad - \left(x_3^2 + x_4^2\right)x_8 - x_4^2 x_9 = 0 \\
&g_4(X) \equiv x_4^2 x_8 - \left(x_4^2 + x_5^2\right)x_9 = 0
\end{aligned}
\tag{8}
$$

The optimization procedure (1) includes nine equations. The cost function *C(X)* of the design process is defined by the following form: $C(X) = (x_9 - k_0)^2 + (x_6 - x_7 - k_1)^2 + (x_7 - x_8 - k_2)^2$.

The total number of the different design strategies that compose the structural basis of the generalized theory is equal $\sum_{i=0}^{4} C_9^i = 256$. At the same time the structural basis of the previous developed theory includes 16 strategies only (2^4). The results of the analysis of some strategies of structural basis that include all the “old” strategies (the last 16 strategies) and some new strategies (from 1 to 12) are shown in Table 2.

Strategy 13 corresponds to the TDS. There are seven different strategies in the “old” group that have the design time less that the TDS. These are the strategies 16, 18, 20, 24, 26, 27 and 28. The strategy 18 is the optimal one among all of the “old” strategies and it has the time gain 5.06 with respect to the TDS. On the other hand the best strategy among all the strategies (number 7) of the Table 2 has the time gain 29.2. So, we have an additional acceleration in 5.77 times. This effect was obtained due to the utilization of more extensive structural basis and it serves as the principal result of the new generalized methodology. It is clear that further optimization of the control vector U can increase this time gain and in this case we can improve all the results as shown in [19].

Table 2. Some strategies of structural basis for four-node circuit.

N	Control functions vector U (u1,u2,u3,u4,u5,u6,u7,u8,u9)	Calculation results	
		Iterations number	Total design time (sec)
1	(1 1 1 0 1 0 0 0 1)	5	0.0031
2	(1 1 1 1 1 0 0 0 1)	397	0.4312
3	(1 1 1 0 1 1 0 0 1)	5	0.0029
4	(1 1 0 1 1 1 1 1 0)	119	0.0209
5	(1 1 1 1 0 0 1 0 1)	101	0.0232
6	(1 1 1 0 1 0 0 1 1)	15	0.0134
7	(1 1 1 0 1 1 1 0 1)	5	0.0009
8	(1 1 1 0 1 1 1 1 1)	101	0.0243
9	(1 1 1 1 0 0 1 1 1)	185	0.0324
10	(1 1 1 1 0 1 0 0 1)	74	0.0102
11	(1 1 1 1 0 1 0 1 1)	121	0.0254
12	(1 1 1 1 0 1 1 1 1)	159	0.0127
13	(1 1 1 1 1 0 0 0 0)	33	0.0263
14	(1 1 1 1 1 0 0 0 1)	397	0.4317
15	(1 1 1 1 1 0 0 1 0)	6548	7.1392
16	(1 1 1 1 1 0 0 1 1)	76	0.0122
17	(1 1 1 1 1 0 1 0 0)	456	0.5113
18	(1 1 1 1 1 0 1 0 1)	24	0.0052
19	(1 1 1 1 1 0 1 1 0)	3750	4.3661
20	(1 1 1 1 1 0 1 1 1)	90	0.0095
21	(1 1 1 1 1 1 0 0 0)	68	0.0354
22	(1 1 1 1 1 1 0 0 1)	596	0.6213
23	(1 1 1 1 1 1 0 1 0)	5408	6.2191
24	(1 1 1 1 1 1 0 1 1)	78	0.0255
25	(1 1 1 1 1 1 1 0 0)	238	0.2104
26	(1 1 1 1 1 1 1 0 1)	77	0.0227
27	(1 1 1 1 1 1 1 1 0)	139	0.0131
28	(1 1 1 1 1 1 1 1 1)	131	0.0103

3.3 Example 3

This example corresponds to the active network in Fig.3.

The Ebers-Moll static model of transistor has been used [20]. The vector X includes six components: $x_1^2 = y_1,\ x_2^2 = y_2,\ x_3^2 = y_3,\ x_4 = V_1,\ x_5 = V_2,$
components: $x_1^2 = y_1,\ x_2^2 = y_2,\ x_3^2 = y_3,\ x_4 = V_1,\ x_5 = V_2,$
$x_6 = V_3$. The model (4) of this network includes

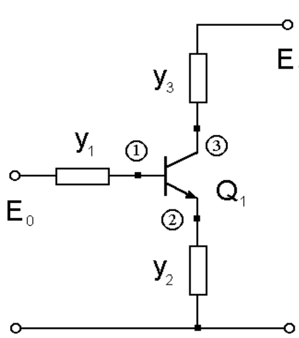

Fig. 3. One-stage transistor amplifier.

three equations (M=3), the optimization procedure (1) includes six equations (K+M=6). The total "old" structural basis contains eight different design strategies. The total number of the different design strategies that compose the new structural basis of the second level of generalized theory is equal $\sum_{i=0}^{3} C_6^i = 42$. The strategy that has the control vector (111000) is the TDS in terms of the first level of generalized methodology. In this case only three first equations of the system (1) are included in optimization procedure to minimize the generalized cost function $F(X,U)$. The model of the circuit includes three equations too. The cost function $C(X)$ was defined by the formula $C(X) = [(x_4 - x_5) - m_2]^2 + [(x_6 - x_5) - m_1]^2$ where m_1, m_2 are the necessary, before defined voltages on transistor junctions.

The strategy 16 that corresponds to the control vector (111111) is the MTDS. All six equations of system (1) are involved in the optimization procedure, but the model (2) has been vanished in this case. Other strategies can be divided in two parts. The strategies that have units for three first components of the control vector define the subset of "old" strategies in limits of the first level of generalized methodology. These are the strategies from 9 to 15 of Table 3.

Table 3. Some strategies of the structural basis for one-stage transistor amplifier.

N	Control functions vector U (u1,u2,u3,u4,u5,u6)	Calculation results	
		Iterations number	Total design time (sec)
1	(0 1 1 1 0 0)	12850	10992.33
2	(0 1 1 1 0 1)	47	19.73
3	(0 1 1 1 1 0)	30015	10998.24
4	(1 0 1 1 1 0)	55992	25094.21
5	(1 0 1 1 1 1)	1195	170
6	(1 1 0 0 1 1)	174	60.01
7	(1 1 0 1 0 1)	606	220.21
8	(1 1 0 1 1 1)	778	139.11
9	(1 1 1 0 0 0)	9311	7977.01
10	(1 1 1 0 0 1)	7514	4989.11
11	(1 1 1 0 1 0)	75635	43053.12
12	(1 1 1 0 1 1)	324	60.11
13	(1 1 1 1 0 0)	25079	10970.12
14	(1 1 1 1 0 1)	243	40.11
15	(1 1 1 1 1 0)	10232	2398.53
16	(1 1 1 1 1 1)	2418	196.21

We can see that two strategies 12 and 14 have the total computer time lesser that others. Strategy 14 corresponds to the optimal one in this case and it has time gain 198 times with respect to the TDS.

Strategies numbered from 1 to 8 are the "new" strategies of the second level of generalization. Strategy 2 has the minimal design time among all strategies and has more than twice time gain with respect to the best "old" strategy 14. The time gain achieves 404 times in this case. However, more impressive results were obtained analyzing more complex networks.

3.4 Example 4

In Fig. 4 there is a transistor amplifier that has three independent variables as admittance y_1, y_2, y_3 (*K=3*) and three dependent variables as nodal voltages V_1, V_2, V_3 (*M=3*) at the nodes 1, 2, 3. The control vector U includes six components $(u_1, u_2, u_3, u_4, u_5, u_6)$. The model of circuit (4) includes three equations and functions $g_j(X)$ are defined by system (9).

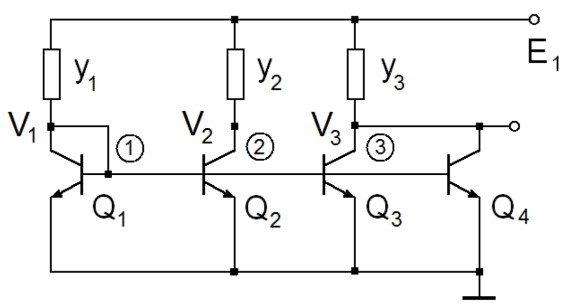

Fig. 4. Three-node transistor amplifier.

$$g_1(X) \equiv (E_1 - V_1)x_1^2 - I_{C1} - I_{B1} - I_{B2} - I_{B3} - I_{B4} = 0$$

$$g_2(X) \equiv (E_1 - V_2)x_2^2 - I_{C2} = 0 \qquad (9)$$

$$g_3(X) \equiv (E_1 - V_3)x_3^2 - I_{C3} - I_{C4} = 0$$

The vector X includes six components. The optimization procedure (1), (5) includes six equations. The cost function *C(X)* is defined by the formula: $C(X) = (I_{C1} - m_1)^2$, where m_1 is a given collector current for the first transistor. The total structural basis contains $\sum_{i=0}^{3} C_6^i = 42$ different strategies. For instance, the structural basis of the previous developed methodology includes only $2^3 = 8$ different strategies.

The results of the optimization process for some strategies as new structural basis and old structural basis are shown in Table 4.

Table 4. Some strategies of structural basis for circuit in Fig. 4.

N	Control functions vector U (u1,u2,u3,u4,u5,u6)	Calculation results: Iterations number	Total design time (sec)
1	(0 0 0 1 1 1)	71	0.0467
2	(0 0 1 1 1 1)	28	0.0119
3	(0 1 0 1 1 1)	25	0.0111
4	(0 1 1 1 0 1)	42	0.0176
5	(0 1 1 1 1 1)	38	0.0108
6	(1 0 1 0 1 1)	43	0.0201
7	(1 0 1 1 1 1)	49	0.0062
8	(1 1 0 1 1 1)	31	0.0051
9	(1 1 1 0 0 0)	2256	2.0992
10	(1 1 1 0 0 1)	59	0.0256
11	(1 1 1 0 1 1)	47	0.0132
12	(1 1 1 1 0 1)	34	0.0045
13	(1 1 1 1 1 1)	46	0.0036

Five last strategies are from the old structural basis and other strategies are from the new structural basis. As we can see the MTDS (number 13) is the best between both structural bases. The time gain of this strategy comparing with TDS is equal to 583. The new structural basis does not produce more fast strategies, but there many strategies that have time gain more than 100 times.

3.5 Example 5

Other example corresponds to the network in Fig 5. The vector X includes ten components in this case. The cost function *C(X)* for the optimization problem was defined by the formula similar to the previous examples.

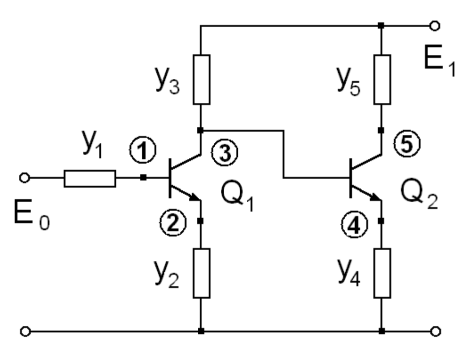

Fig. 5. Two-stage transistor amplifier.

The presented network is characterized by 5 independent parameters $x_1^2 = y_1$, $x_2^2 = y_2$, $x_3^2 = y_3$,

$x_4^2 = y_4$, $x_5^2 = y_5$ and 5 dependent parameters $x_6 = V_1$, $x_7 = V_2$, $x_8 = V_3$, $x_9 = V_4$, $x_{10} = V_5$ in accordance with the traditional approach. According to the first level of generalized methodology the control vector includes five control functions, but the same control vector has 10 components following to the second level of generalized methodology. The structural basis consists of 32 design strategies according to the first level of generalization. On the other hand the total number of the different design strategies, which compose the new structural basis is equal to $\sum_{i=0}^{5} C_{10}^{i} = 638$. This structural basis can provide significantly better results for the time minimization. The results of analysis of some design strategies are presented in Table 5.

The design strategies numbered from 35 to 46 belong to subset that appears in limits of the first level of generalization. The strategy 35 that corresponds to the control vector (1111100000) is the traditional design strategy. The strategy 38 that corresponds to the control vector (1111101111) has the minimum computer time among this subset. The time gain is equal to 258 times in this case. However, there are 21 others strategies that appear among the subset of new design strategies that have the computer design time lesser that this strategy. The best strategy 19 that corresponds to the control vector (0111110111) has the time gain 4068 times with respect to the traditional design strategy and has an additional gain 15.7 times with respect to the better "old" strategy. Other strategies, for instance 1, 7, 9, 12, 13, 16, 23, 24, 25, 28 and 34 have a significant value of the time gain that is change from 1000 to 3600 times. So, we can state that the second level of the generalization of design methodology includes more perspective strategies.

3.6 Example 6

The next example corresponds to the three-stage transistor amplifier in Fig.6.

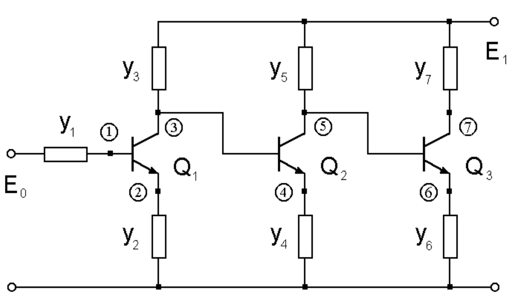

Fig. 6. Three-stage transistor amplifier.

Table 5. Some strategies of structural basis for circuit in Fig. 5.

N	Control functions vector U(u1,u2,u3,u4,u5,u6,u7,u8,u9,u10)	Calculation results	
		Iterations number	Total design time (sec)
1	(0000011111)	55	0.159
2	(0000111110)	7912	23.985
3	(0000111111)	209	0.429
4	(0001111100)	57245	229.963
5	(0001111111)	420	0.561
6	(0011111011)	25884	52.022
7	(0011111101)	232	0.309
8	(0011111110)	138426	230.014
9	(0011111111)	381	0.319
10	(0101010111)	201	0.401
11	(0101110100)	47186	190.979
12	(0101110111)	242	0.329
13	(0101111111)	371	0.319
14	(0110110111)	338	0.441
15	(0110111111)	414	0.341
16	(0111010111)	156	0.209
17	(0111011111)	480	0.409
18	(0111110110)	8511	11.998
19	(0111110111)	68	0.082
20	(0111111011)	22381	26.012
21	(0111111100)	31525	55.061
22	(0111111110)	9264	8.961
23	(0111111111)	205	0.091
24	(1000001111)	98	0.291
25	(1000011111)	150	0.309
26	(1001101100)	40121	165.003
27	(1001101111)	286	0.379
28	(1001111101)	170	0.239
29	(1011111100)	35624	63.014
30	(1011111111)	691	0.342
31	(1100000111)	4557	22.019
32	(1110111111)	976	0.945
33	(1111000001)	79079	326.941
34	(1111011111)	542	0.271
35	(1111100000)	83402	333.601
36	(1111100011)	6695	8.991
37	(1111100111)	3395	4.007
38	(1111101111)	253	1.292
39	(1111110001)	70887	125.994
40	(1111110111)	588	2.701
41	(1111111001)	148299	158.038
42	(1111111011)	24678	15.945
43	(1111111100)	56464	57.015
44	(1111111101)	496	2.402
45	(1111111110)	5583	2.007
46	(1111111111)	614	0.169

In this case the vector X includes 14 components. Seven components define the independent parameters $x_1^2 = y_1$, $x_2^2 = y_2$, $x_3^2 = y_3$, $x_4^2 = y_4$, $x_5^2 = y_5$, $x_6^2 = y_6$, $x_7^2 = y_7$ and other seven components $x_8 = V_1$, $x_9 = V_2$, $x_{10} = V_3$, $x_{11} = V_4$, $x_{12} = V_5$, $x_{13} = V_6$, $x_{14} = V_7$ define the dependent parameters in accordance with the traditional approach. The cost function $C(X)$ for the design problem was defined by the formula similar to the previous examples.

The structural basis consists of 128 different design strategies according to the first level of generalization. On the other hand the structural basis of the second level of generalization is equal to $\sum_{i=0}^{7} C_{14}^{i} = 9908$. Once again we have very broadened structural basis in the second case. The results of the analysis of some design strategies for this network are presented in Table 6.

The design strategies numbered from 15 to 28 belong to the subset that appears in limits of the first level of design methodology generalization. The strategy 15 that corresponds to the control vector (11111110000000) is the traditional design strategy. The strategy 22 that corresponds to the control vector (11111111011111) has the minimum computer time among all the strategies of this subset. The time gain in this case is equal to 368 times. The strategies from 1 to 14 belong to the subset of new design strategies. Six strategies of this subset have the design time lesser than the best strategy of the "old" structural basis. The best strategy among new structural basis has the time gain 11715 times with respect to the traditional design strategy and has an additional time gain 31.8 times with respect to the better "old" strategy.

3.7 Example 7

The last example corresponds to the transistor amplifier in Fig.7.

Table 6. Some strategies of the structural basis for three-stage transistor amplifier.

N	Control functions vector U (u1,u2,...,u14)	Calculation results	
		Iterations number	Total design time (sec)
1	(0 0 0 0 0 0 0 1 1 1 1 1 1 1)	72	0.549
2	(0 0 0 0 0 0 1 1 1 1 1 1 1 1)	235	1.030
3	(0 0 0 0 0 1 1 1 1 1 1 1 1 1)	506	1.031
4	(0 0 0 0 1 1 1 1 1 1 1 1 1 1)	891	2.980
5	(0 0 0 1 1 1 1 1 1 1 1 1 1 1)	660	1.050
6	(0 0 1 1 1 1 1 1 1 1 1 1 1 1)	1262	2.002
7	(0 1 1 1 1 1 1 1 1 1 1 1 1 1)	504	0.953
8	(1 0 1 1 1 1 1 1 1 1 1 1 1 1)	351	0.380
9	(1 1 0 1 1 1 1 1 1 1 1 1 1 1)	316	0.350
10	(1 1 1 0 1 1 1 1 1 1 1 1 1 1)	662	0.709
11	(1 1 1 1 0 1 1 1 1 1 1 1 1 1)	801	0.986
12	(1 1 1 1 1 0 1 1 1 1 1 1 1 1)	532	0.956
13	(1 1 1 1 1 1 0 0 0 0 0 0 0 1)	11993	129.003
14	(1 1 1 1 1 1 0 1 1 1 1 1 1 1)	308	0.030
15	(1 1 1 1 1 1 1 0 0 0 0 0 0 0)	38775	351.456
16	(1 1 1 1 1 1 1 0 0 0 0 0 0 1)	100843	742.993
17	(1 1 1 1 1 1 1 0 0 0 0 1 0 0)	45407	440.014
18	(1 1 1 1 1 1 1 0 0 1 0 0 0 0)	2643	29.002
19	(1 1 1 1 1 1 1 0 1 0 0 0 0 0)	82811	1163.987
20	(1 1 1 1 1 1 1 0 1 1 1 1 1 1)	1127	1.020
21	(1 1 1 1 1 1 1 1 0 0 0 0 0 0)	10454	89.019
22	(1 1 1 1 1 1 1 1 0 1 1 1 1 1)	540	0.955
23	(1 1 1 1 1 1 1 1 1 0 1 1 1 1)	53880	61.040
24	(1 1 1 1 1 1 1 1 1 1 0 1 1 1)	1008	1.007
25	(1 1 1 1 1 1 1 1 1 1 1 0 1 1)	5647	6.012
26	(1 1 1 1 1 1 1 1 1 1 1 1 0 1)	226	1.885
27	(1 1 1 1 1 1 1 1 1 1 1 1 1 0)	7441	7.999
28	(1 1 1 1 1 1 1 1 1 1 1 1 1 1)	3979	2.005

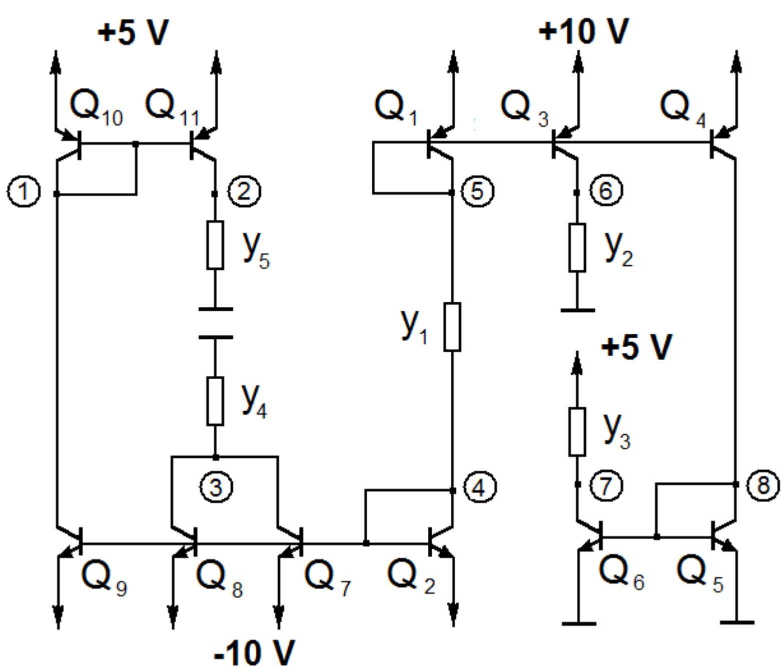

Fig. 7. Eight-node transistor amplifier.

In this case the vector X includes 13 components. Five components define the independent parameters $x_1^2 = y_1$, $x_2^2 = y_2$, $x_3^2 = y_3$, $x_4^2 = y_4$, $x_5^2 = y_5$ and other eight components $x_6 = V_1$, $x_7 = V_2$, $x_8 = V_3$, $x_9 = V_4$, $x_{10} = V_5$, $x_{11} = V_6$, $x_{12} = V_7$, $x_{13} = V_8$ define the dependent parameters in accordance with the traditional approach. The cost function $C(X)$ for the design problem was defined by the formula similar to the previous examples.

The structural basis consists of 256 different design strategies according to the first level of generalization. On the other hand the structural basis of the second level of generalization is equal to $\sum_{i=0}^{8} C_{13}^{i} = 7099$. Once again we have very broadened structural basis in the second case. The results of the analysis of TDS and some strategies that have the design time less than TDS for this network are presented in Table 7.

The design strategies numbered from 22 to 45 belong to the subset that appears on the basis of the first level of design methodology generalization. The strategy 22 that corresponds to the control vector (1111100000000) is the TDS. This strategy has a large number of iteration steps and a large computer time (24.75 sec). Other strategies that are presented in this table have considerably less iteration number and computer time. For instance the MTDS with control vector (1111111111111) has computer time 0.202 sec. The time gain in this case is equal to 123.7 times. The strategy 34 that corresponds to the control vector (1111111011110) has the minimum computer time among all the strategies of this subset. The time gain in this case is equal to 1295 times.

The strategies from 1 to 21 belong to the subset of new design strategies. Strategy 18 of this subset has the design time lesser than the best strategy of the “old” structural basis. This strategy belong to the new structural basis and it has the time gain 1447 times with respect to the traditional design strategy and has an additional time gain 1.12 times with respect to the better strategy of the first level of the generalization.

Moreover among the “old” strategies there are 6 strategies that have the time gain more than 500 and 9 strategies that have the time gain more than 400. On the other hand among the “new” strategies there are 11 strategies that have the time gain more than 500 and 13 strategies that have the time gain more than 400.

So, taking into consideration the obtained results we can state that the second level of the design methodology generalization gives the possibility to improve all characteristics of the generalized design theory. Further analysis may be focused on the problem of the optimal design strategy searching by means of the control vector manipulation into the broadened structural basis. It is intuitively clear that we can obtain very great time gain by means of the new structural basis.

Table 7. Some strategies of the structural basis for transistor amplifier in Fig. 7.

N	Control functions vector U(u1,u2,...,u13)	Calculation results	
		Iterations number	Total design time (sec)
1	(0 0 1 1 1 1 1 0 1 1 1 1 1)	131	0.0680
2	(0 0 1 1 1 1 1 1 1 1 1 1 1)	138	0.0477
3	(0 1 0 1 1 1 1 1 1 1 1 1 1)	118	0.0441
4	(0 1 1 0 1 1 1 1 1 1 1 1 1)	83	0.0343
5	(0 1 1 1 0 1 1 1 1 1 1 1 1)	142	0.0536
6	(0 1 1 1 1 0 1 1 1 1 1 1 1)	123	0.0464
7	(0 1 1 1 1 1 1 1 1 1 1 1 1)	155	0.0422
8	(1 0 0 1 1 1 1 1 1 1 1 1 1)	232	0.0754
9	(1 0 1 0 1 1 1 1 1 1 1 1 1)	338	0.0982
10	(1 0 1 1 0 1 1 1 1 1 1 1 1)	247	0.0668
11	(1 0 1 1 1 0 1 1 1 1 1 1 1)	145	0.0402
12	(1 0 1 1 1 1 0 1 1 1 1 1 1)	247	0.0657
13	(1 0 1 1 1 1 1 0 1 1 1 1 1)	156	0.0478
14	(1 0 1 1 1 1 1 1 0 1 1 1 1)	502	0.1425
15	(1 0 1 1 1 1 1 1 1 0 1 1 1)	300	0.1145
16	(1 0 1 1 1 1 1 1 1 1 1 0 1)	287	0.0825
17	(1 0 1 1 1 1 1 1 1 1 1 1 0)	132	0.0425
18	(1 0 1 1 1 1 1 1 1 1 1 1 1)	77	0.0171
19	(1 1 1 0 1 1 1 1 1 1 1 1 0)	83	0.0248
20	(1 1 1 0 1 1 1 1 1 1 1 1 1)	254	0.0602
21	(1 1 1 1 0 1 1 1 1 1 1 1 1)	176	0.0339
22	(1 1 1 1 1 0 0 0 0 0 0 0 0)	6990	24.7500
23	(1 1 1 1 1 0 0 0 0 0 0 0 1)	90	0.1454
24	(1 1 1 1 1 0 0 0 0 0 0 1 1)	246	0.3410
25	(1 1 1 1 1 0 0 0 0 0 1 1 1)	203	0.2231
26	(1 1 1 1 1 0 0 0 0 1 1 1 1)	875	0.7300
27	(1 1 1 1 1 0 0 0 1 1 1 1 1)	299	0.1530
28	(1 1 1 1 1 0 0 1 1 1 1 1 1)	301	0.1210
29	(1 1 1 1 1 1 0 0 0 0 0 0 1)	159	0.2040
30	(1 1 1 1 1 1 0 0 0 1 1 1 1)	777	0.6000
31	(1 1 1 1 1 1 0 1 1 1 1 1 0)	89	0.0380
32	(1 1 1 1 1 1 0 1 1 1 1 1 1)	216	0.0611
33	(1 1 1 1 1 1 1 0 0 0 0 0 1)	157	0.1450
34	(1 1 1 1 1 1 1 0 1 1 1 1 0)	59	0.0191
35	(1 1 1 1 1 1 1 0 1 1 1 1 1)	153	0.0530
36	(1 1 1 1 1 1 1 1 0 1 1 1 0)	303	0.1100
37	(1 1 1 1 1 1 1 1 0 1 1 1 1)	379	0.0980
38	(1 1 1 1 1 1 1 1 1 0 1 1 0)	90	0.0420
39	(1 1 1 1 1 1 1 1 1 0 1 1 1)	190	0.0750
40	(1 1 1 1 1 1 1 1 1 1 0 1 0)	132	0.0361
41	(1 1 1 1 1 1 1 1 1 1 0 1 1)	207	0.0452
42	(1 1 1 1 1 1 1 1 1 1 1 0 0)	155	0.0571
43	(1 1 1 1 1 1 1 1 1 1 1 0 1)	257	0.0573
44	(1 1 1 1 1 1 1 1 1 1 1 1 0)	121	0.0350
45	(1 1 1 1 1 1 1 1 1 1 1 1 1)	607	0.0871

4 Conclusion

The traditional approach for the analog circuit design is not time-optimal. The problem of the optimum algorithm construction can be solved more adequately on the basis of the optimal control theory application. The time-optimal design algorithm is formulated as the problem of the functional minimization of the optimal control theory. In this case it is necessary to select one optimal trajectory from the quasi-infinite number of the different design strategies, which are produced. The new and more complete approach to the electronic network design methodology has been developed now. This approach generates structural basis of the different design strategies that is more broadened than for the previous developed methodology. The total number of the different design strategies, which compose the structural basis by this approach, is equal to $\sum_{i=0}^{M} C_{K+M}^{i}$. This new structural basis serves as the necessary set for searching the optimal design strategy. This approach can reduce considerably the total computer time for the system design. Analysis of the different problems of the electronic system design shows a significant potential of the new level of generalized design methodology. The potential gain of computer time that can be obtain on the basis of new approach is significantly more than for the previous developed methodology.

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