



Klippel Non-Linear Test Results

LSI (Large Signal Identification)

Model #: PS220-8

Introduction

Large Signal Modeling

At higher amplitudes, loudspeakers produce substantial distortion in the output signal, generated by nonlinearities inherent in the transducer. The dominant nonlinear distortions are predictable and are closely related with the general principle, particular design, material properties and assembling techniques of the loudspeaker. The Klippel Distortion Analyzer combines nonlinear measurement techniques with computer simulation to explain the generation of the nonlinear distortions, to identify their physical causes and to give suggestion for constructional improvements. Better insight into the nonlinear mechanisms makes it possible to further optimize the transducer in respect with sound quality, weight, size and cost.

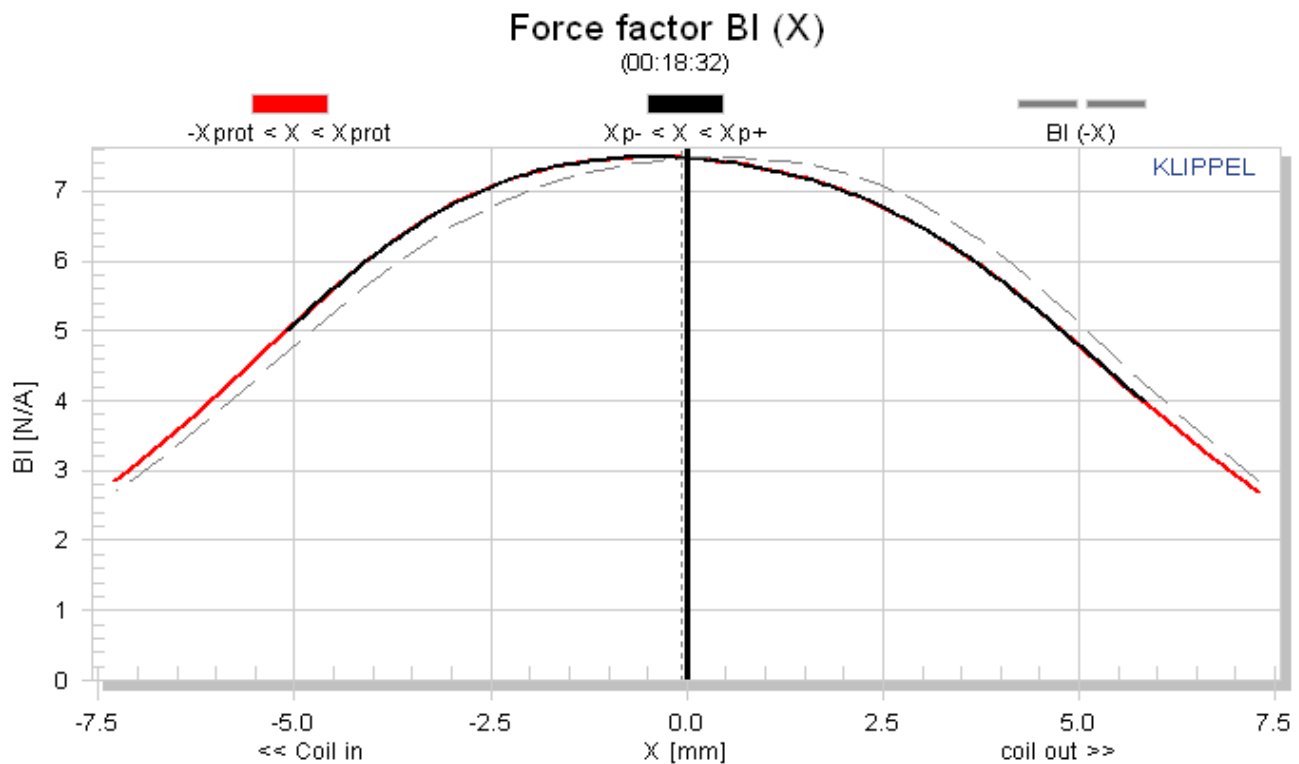
Nonlinear Characteristics

The dominant nonlinearities are modelled by variable parameters such as

| | |
|--------|---|
| BI(x) | instantaneous electro-dynamic coupling factor (force factor of the motor) defined by the integral of the magnetic flux density B over voice coil length l as a function of displacement |
| KMS(x) | mechanical stiffness of driver suspension a function of displacement |
| LE(i) | voice coil inductance as a function of input current (describes nonlinear permeability of the iron path) |
| LE(x) | voice coil inductance as a function of displacement |

More information about these parameters can be found in the article ["Displacement limits"](#)

Nonlinear Parameters

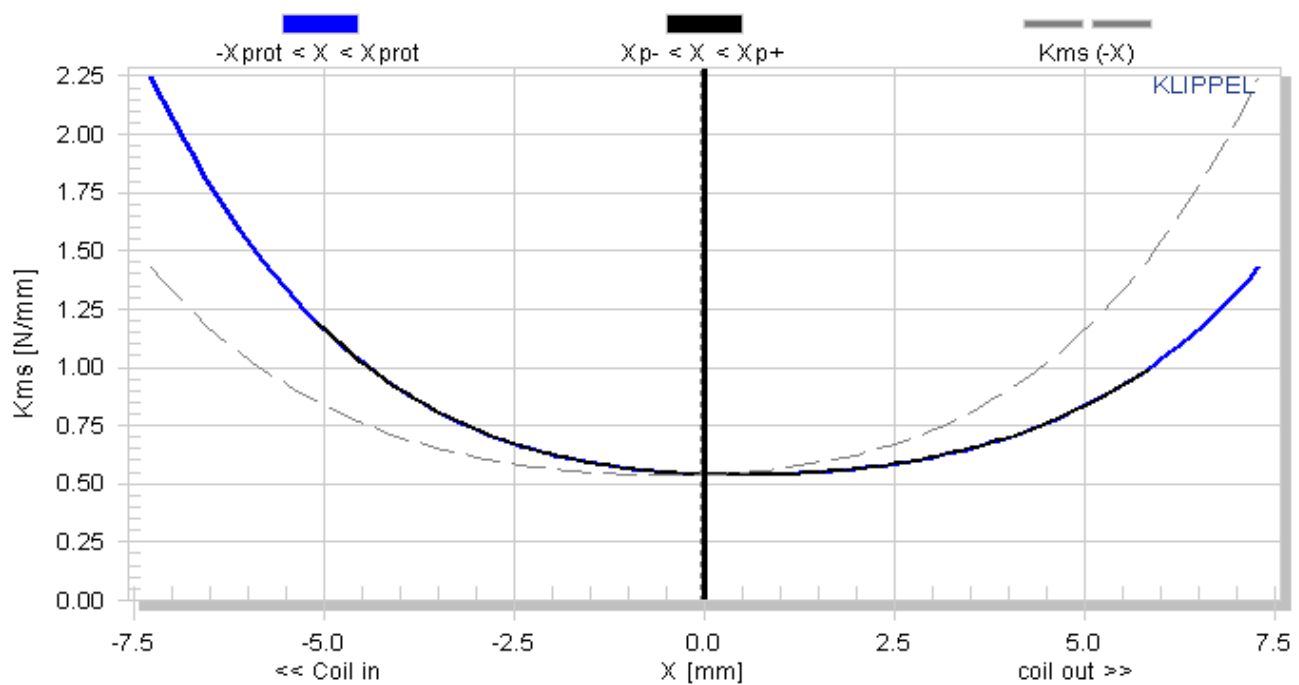


The electrodynamic coupling factor, also called BI-product or force factor $BI(x)$, is defined by the integral of the magnetic flux density B over voice coil length l , and translates current into force. In traditional modeling this parameter is assumed to be constant. The force factor $BI(0)$ at the rest position corresponds with the BI-product used in linear modeling. The red curve displays BI over the entire displacement range covered during the measurement. You see the typical decay of BI when the voice coil moves out of the gap. At the end of the measurement, the black curve shows the confidential range (interval where the voice coil displacement in this range occurred 99% of the measurement time). During the measurement, the black curve shows the current working range. The dashed curve displays $BI(x)$ mirrored at the rest position of the voice coil – this way, asymmetries can be quickly identified. Since a laser was connected during the measurement, a "coil in / coil out" marker is displayed on the bottom left / bottom right.

More information regarding $BI(x)$ and its optimization can be found in the article ["Optimal Voice Coil Rest Position"](#)

Stiffness of suspension $K_{ms}(X)$

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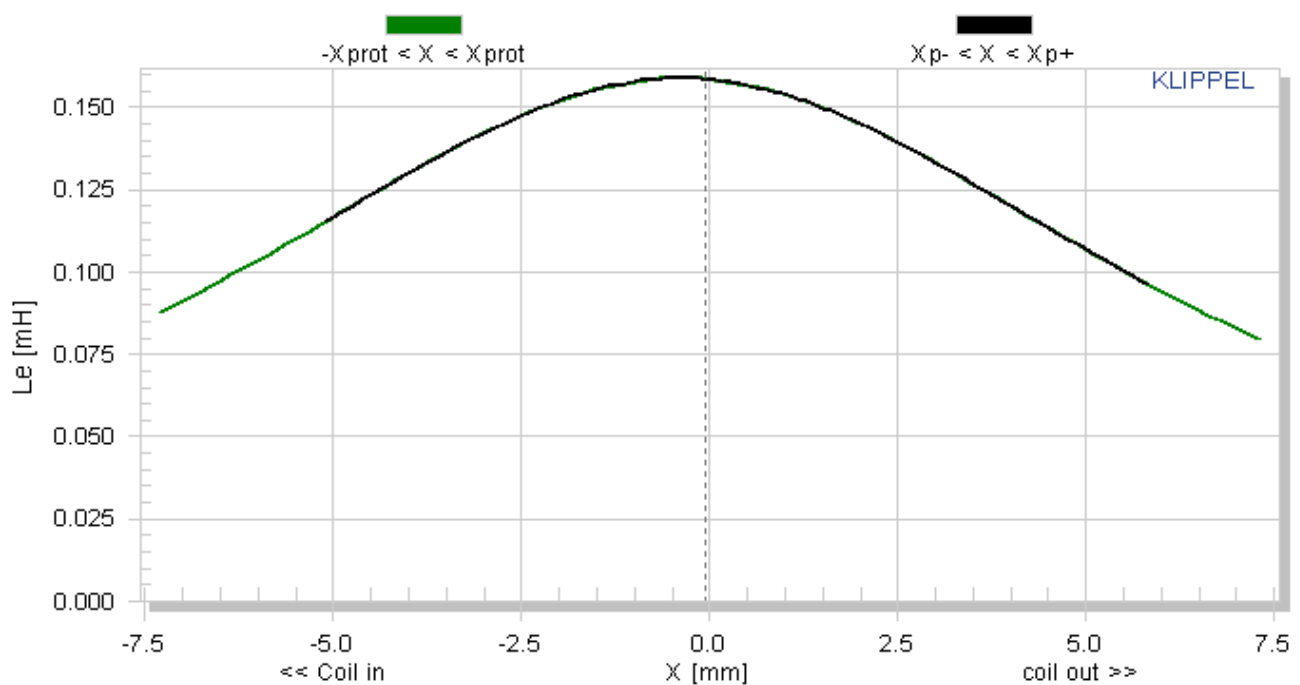


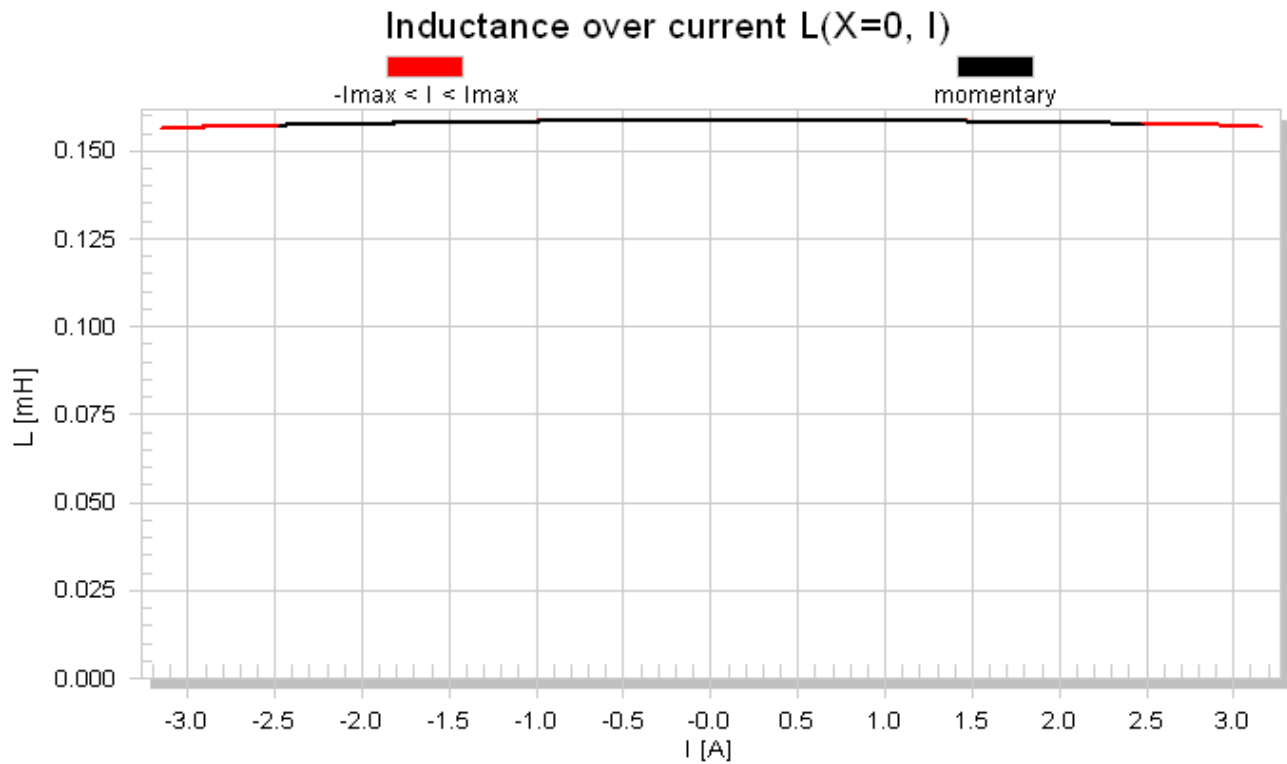
The stiffness $K_{MS}(x)$ describes the mechanical properties of the suspension. Its inverse is the compliance $CMS(x)$

More information regarding $K_{ms}(x)$ and its optimization can be found in the article ["Adjusting Mechanical Suspension"](#)

Electrical inductance $L(X, I=0)$

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The inductance components $L_e(x)$ and $Bl(i)$ of most drivers have a strong asymmetric characteristic. If the voice coil moves towards the back plate the inductance usually increases since the magnetic field generated by the current in the voice coil has a lower magnetic resistance due to the shorter air path.

The nonlinear inductance $L_e(x)$ has two nonlinear effects. First the variation of the electrical impedance with voice coil displacement x affects the input current of the driver. Here the nonlinear source of distortion is the multiplication of displacement and current. The second effect is the generation of a reluctance force which may be interpreted as an electromagnetic motor force proportional to the squared input current.

The flux modulation $Bl(i)$ has two effects too. On the electrical side the back EMF $Bl(i) \cdot v$ produces nonlinear distortion due to the multiplication of current i and velocity v . On the mechanical side the driving force $F = Bl(i) \cdot i$ comprises a nonlinear term due to the squared current i . This force produces similar effects as the variable term $L_e(x)$.

Nonlinear Parameters

The displacement limits XBL, XC, XL and Xd describe the limiting effect for the force factor $Bl(x)$, compliance $Cms(x)$, inductance $Le(x)$ and Doppler effect, respectively, according to the threshold values Bl_{min} , C_{min} , Z_{max} and d_2 used. The thresholds $Bl_{min}=82\%$, $C_{min}=75\%$, $Z_{max}=10\%$ and $d_2=10\%$ generate for a two-tone-signal ($f_1=f_s$, $f_2=8.5f_s$) 10% total harmonic distortion and 10% intermodulation distortion. The thresholds $Bl_{min}=70\%$, $C_{min}=50\%$, $Z_{max}=17\%$ create 20% total harmonic distortion which is becoming the standard for acceptable subwoofer distortion thresholds.

Traditionally, X_{max} has been defined as the physical overhang of the voice coil, 15% times the physical overhang, or the point where BL has dropped 70% from its $X=0$ value (same as X_{BL}). The additional nonlinear limits allow us to quantify the other factors that limit a loudspeaker's performance.

These parameters are defined in more detail in the papers: "[AN04 – Measurement of Peak Displacement \$X_{max}\$](#) ", "[AN05 - Displacement Limits due to Driver Nonlinearities.](#)", "[AN17 - Credibility of Nonlinear Parameters](#)", "[Prediction of Speaker Performance at High Amplitudes](#)", "[Assessment of Voice Coil Peak Displacement \$X_{max}\$](#) ", and "[Assessing Large Signal Performance of Loudspeakers](#)"

| Symbol | Number | Unit | Comment |
|------------------------|--------|------|---|
| Displacement Limits | | | thresholds can be changed in Processing property page |
| X BL @ $Bl_{min}=70\%$ | 4.8 | mm | Displacement limit due to force factor variation |
| X C @ $C_{min}=50\%$ | 4.8 | mm | Displacement limit due to compliance variation |
| X L @ $Z_{max}=10\%$ | >5.1 | mm | Displacement limit due to inductance variation |
| X d @ $d_2=10\%$ | 25.2 | mm | Displacement limit due to IM distortion (Doppler) |

Parameters at the Rest Position

The value of the nonlinear parameters at the rest position ($x=0$) may be used as input for the traditional linear modelling and may be referred as "linear parameters". Please note that these parameters depend on the instantaneous state of the driver (voice coil temperature, peak value of displacement) and are presented for three different modes of operation:

| Mode | Properties |
|--------------|---|
| LARGE+WARM | the transducer is operated in the large signal domain, the peak value of the displacement is high ($ x < x_{max}$), the variation of the parameters is not negligible, the voice coil temperature is increased ($D_{TV} > 0$) due to heating. |
| LARGE+COLD | the transducer is operated in the large signal domain, the peak value of the displacement is high ($ x < x_{max}$), the variation of the parameters is not negligible, the effect of heating is compensated while considering the cold voice coil resistance $Re(D_{TV}=0)$. |
| SMALL SIGNAL | the transducer is operated in the small signal domain, the amplitude of the excitation signal is sufficiently small, the displacement is small in comparison to the allowed maximal displacement ($ x \ll x_{max}$), the variations of the nonlinear parameters are negligible, the increase of voice coil temperature is negligible ($D_{TV} \gg 0$), the effects of the nonlinear, thermal and time-varying mechanisms are negligible, the transducer behaves almost linear. |

Linear Parameters

| Symbol | Large + Warm | Large + Cold | Small Signal | Unit | Comment |
|-------------------------|--------------|--------------|--------------|-----------------|---|
| Note: | | | | | for accurate small signal parameters, use LPM module |
| Delta $T_v = T_v - T_a$ | 18 | 0 | 0 | K | increase of voice coil temperature during the measurement |
| Xprot | 7.3 | 7.3 | 4.9 | mm | maximal voice coil excursion (limited by protection system) |
| Re (T_v) | 6.39 | 5.97 | 5.97 | Ohm | (imported) voice coil resistance considering increase of voice coil temperature T_v |
| Le ($X=0$) | 0.16 | 0.16 | 0.16 | mH | voice coil inductance at the rest position of the voice coil |
| L2 ($X=0$) | 0.70 | 0.70 | 0.39 | mH | para-inductance at the rest position due to the effect of eddy current |
| R2 ($X=0$) | 0.45 | 0.45 | 0.61 | Ohm | resistance at the rest position due to eddy currents |
| Cmes ($X=0$) | 214 | 214 | 247 | μ F | electrical capacitance representing moving mass |
| Lces ($X=0$) | 92.04 | 92.04 | 49.53 | mH | electrical inductance at the rest position representing driver compliance |
| Res ($X=0$) | 195.99 | 195.99 | 51.18 | Ohm | resistance at the rest position due to mechanical losses |
| Qms ($X=0, T_v$) | 9.44 | 9.44 | 3.61 | | mechanical Q-factor considering Rms only |
| Qes (T_v) | 0.27 | 0.26 | 0.32 | | electrical Q-factor considering Re (T_v) only |
| Qts ($X=0, T_v$) | 0.27 | 0.25 | 0.30 | | total Q-factor considering Re (T_v) and Rms only |
| fs | 35.9 | 35.9 | 45.5 | Hz | driver resonance frequency |
| Mms | 10.600 | 10.600 | 10.600 | g | (imported) mechanical mass of driver diaphragm assembly including voice-coil and air load |
| Rms ($X=0$) | 0.253 | 0.253 | 0.839 | kg/s | mechanical resistance of total-driver losses |
| Cms ($X=0$) | 1.86 | 1.86 | 1.15 | mm/N | mechanical compliance of driver suspension at the rest position |
| Bl ($X=0$) | 7.47 | 7.47 | 7.47 | N/A | (imported) force factor at the rest position (Bl product) |
| Vas | 127.0133 | 127.0133 | 78.9623 | l | equivalent air volume of suspension |
| N0 | 2.057 | 2.200 | 2.200 | % | reference efficiency (2Pi-sr radiation using Re) |
| Lm | 95.3 | 95.6 | 95.6 | dB | characteristic sound pressure level |
| Sd | 220.35 | 220.35 | 220.35 | cm ² | diaphragm area |

For accurate system modelling “Large + Cold” parameters are preferable to “Small Signal” parameters because they more closely reflect the parameters in their typical operating range.

Asymmetrical Nonlinearities

Asymmetrical nonlinearities produce not only second- and higher-order distortions but also a dc-part in the displacement by rectifying low frequency components.

For an asymmetric stiffness characteristic the dc-components moves the voice coil for any excitation signal in the direction of the stiffness minimum.

For an asymmetric force factor characteristic the dc-component depends on the frequency of the excitation signal. A sinusoidal tone below resonance ($f < f_S$) would generate a force moving the voice coil always in the force factor maximum. This effect is most welcome for stabilizing voice coil position. However, above the resonance frequency ($f > f_S$) would generate a dc-component moving the voice coil in the force factor minimum and may cause severe stability problems.

For an asymmetric inductance characteristic the dc-component moves the voice coil for any excitation signal in the direction of the inductance maximum.

Please note that the dynamically generated DC-components cause interactions between the driver nonlinearities. An optimal rest position of the coil in the gap may be destroyed by an asymmetric compliance or inductance characteristic at higher amplitudes. The module "Large Signal Simulation (SIM)" allows systematic investigation of the complicated behaviour.

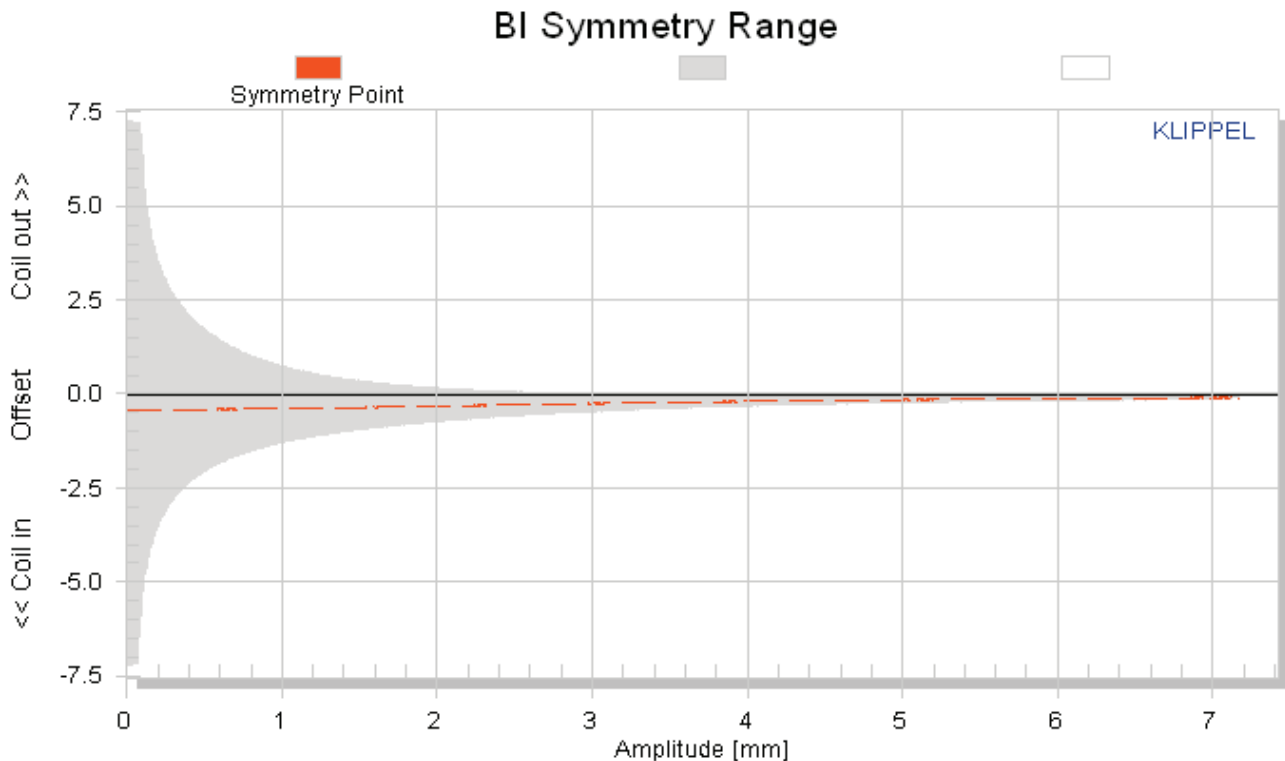
BI Symmetry $x_b(x)$

This curve shows *the* symmetry point in the nonlinear BI-curve where a negative and positive displacement $x = x_{peak}$ will produce the same force factor

$$Bl(x_b(x) + x) = Bl(x_b(x) - x).$$

If the shift $x_b(x)$ is independent on the displacement amplitude x then the force factor asymmetry is caused by an offset of the voice coil position and can be simply compensated.

If the optimal shift $x_b(x)$ varies with the displacement amplitude x then the force factor asymmetry is caused by an asymmetrical geometry of the magnetic field and can not completely be compensated by coil shifting.

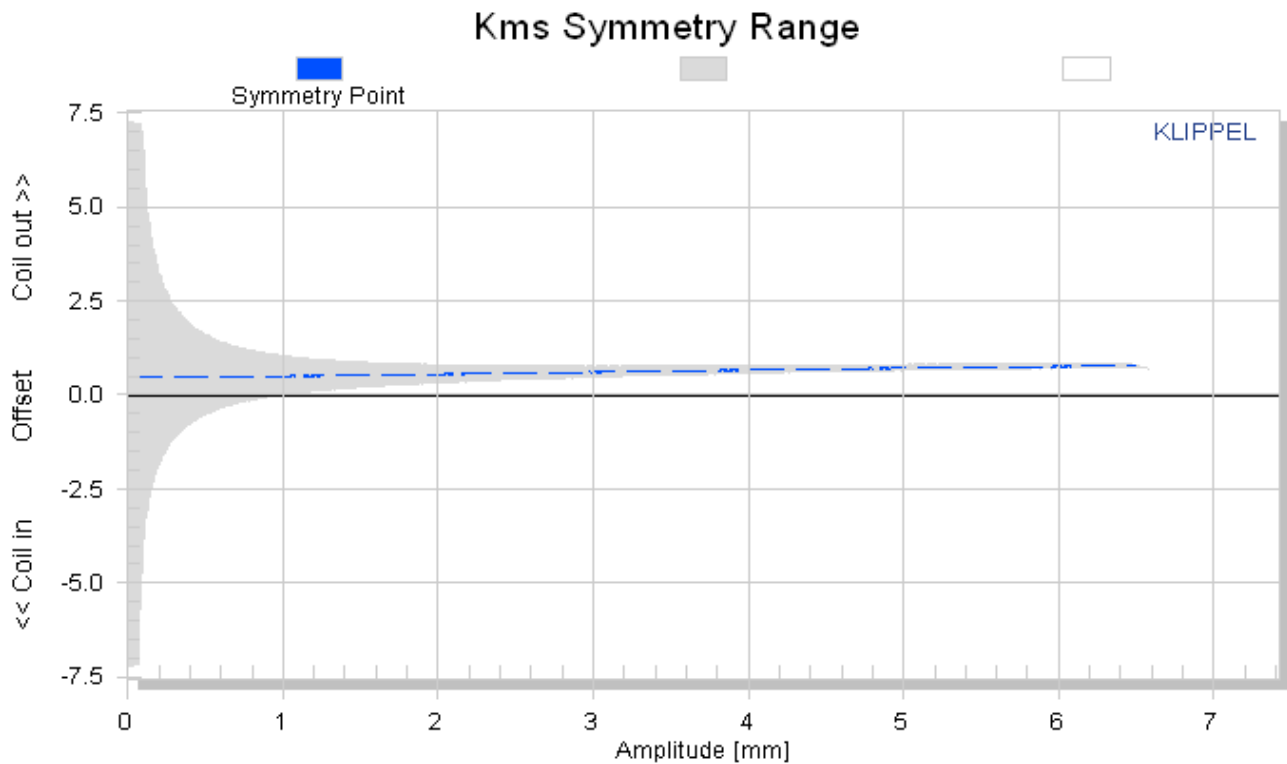


Kms Symmetry $x_c(x)$

This curve shows *the* symmetry point in the nonlinear compliance curve where a negative and positive displacement $x=x_{peak}$ will produce the same compliance value

$$kms(x_c(x) + x) = kms(x_c(x) - x).$$

A high value of the symmetry point $x_c(x)$ at small displacement amplitudes $x \gg 0$ indicates that the rest position does not agree with the minimum of the stiffness characteristic. This may be caused by an asymmetry in the geometry of the spider (cup form) or surround (half wave). A high value of the symmetry point $x_c(x)$ at maximal displacement $x \gg x_{max}$ may be caused by asymmetric limiting of the surround.



You can find a detailed description of these non-linearities and their remedies in the papers [“Loudspeaker Nonlinearities - Causes and Symptoms, Assessing Large Signal Performance of Loudspeakers”](#), and [“Diagnosis and Remedy of Nonlinearities”](#)

Testing performed by Redrock Acoustics – www.redrockacoustics.com