

## EE404ES: CONTROL SYSTEMS

B.Tech. II Year II Sem.

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**Prerequisite:** Ordinary Differential Equations & Laplace Transform, Mathematics I

### Course objectives:

- To understand the different ways of system representations such as Transfer function representation and state space representations and to assess the system dynamic response
- To assess the system performance using time domain analysis and methods for improving it
- To assess the system performance using frequency domain analysis and techniques for improving the performance
- To design various controllers and compensators to improve system performance

**Course outcomes:** After completion of this course the student is able to

- Improve the system performance by selecting a suitable controller and/or a compensator for a specific application
- Apply various time domain and frequency domain techniques to assess the system performance
- Apply various control strategies to different applications (example: Power systems, electrical drives etc...)
- Test system Controllability and Observability using state space representation and applications of state space representation to various systems.

### UNIT – I

**Introduction:** Concepts of Control Systems- Open Loop and closed loop control systems and their differences- Different examples of control systems- Classification of control systems, Feed-Back Characteristics, Effects of feedback. Mathematical models – Differential equations - Impulse Response and transfer functions - Translational and Rotational mechanical systems.

**Transfer Function Representation:** Transfer Function of DC Servo motor - AC Servo motor- Synchro transmitter and Receiver, Block diagram representation of systems considering electrical systems as examples - Block diagram algebra – Representation by Signal flow graph - Reduction using mason's gain formula.

### UNIT-II

**Time Response Analysis:** Standard test signals - Time response of first order systems – Characteristic Equation of Feedback control systems, Transient response of second order systems - Time domain specifications – Steady state response - Steady state errors and error constants – Effects of proportional derivative, proportional integral systems.

### **UNIT – III**

**Stability Analysis:** The concept of stability - Routh stability criterion – qualitative stability and conditional stability.

**Root Locus Technique:** The root locus concept - construction of root loci-effects of adding poles and zeros to  $G(s)H(s)$  on the root loci.

**Frequency Response Analysis:** Introduction, Frequency domain specifications-Bode diagrams-Determination of Frequency domain specifications and transfer function from the Bode Diagram-Phase margin and Gain margin-Stability Analysis from Bode Plots.

### **UNIT - IV**

**Stability Analysis In Frequency Domain:** Polar Plots, Nyquist Plots and applications of Nyquist criterion to find the stability - Effects of adding poles and zeros to  $G(s)H(s)$  on the shape of the Nyquist diagrams.

**Classical Control Design Techniques:** Compensation techniques – Lag, Lead, and Lead-Lag Controllers design in frequency Domain, PID Controllers.

### **UNIT – V**

**State Space Analysis of Continuous Systems:** Concepts of state, state variables and state model, derivation of state models from block diagrams, Diagonalization- Solving the Time invariant state Equations- State Transition Matrix and its Properties.

### **TEXT BOOKS:**

1. “I. J. Nagrath and M. Gopal”, “Control Systems Engineering”, New Age International (P) Limited, Publishers, 5<sup>th</sup> edition, 2009
2. “B. C. Kuo”, “Automatic Control Systems”, John wiley and sons, 8th edition, 2003.

### **REFERENCE BOOKS:**

1. “N. K. Sinha”, “Control Systems”, New Age International (P) Limited Publishers, 3<sup>rd</sup> Edition, 1998.
2. “NISE”, “Control Systems Engineering”, John wiley, 6<sup>th</sup> Edition, 2011.
3. “Katsuhiko Ogata”, “Modern Control Engineering”, Prentice Hall of India Pvt. Ltd., 3<sup>rd</sup> edition, 1998.