

EC3103PC: CONTROL SYSTEMS**B. Tech. III Year I Sem.****L T P C**

Prerequisite: Linear Algebra and Calculus, Ordinary Differential Equations and Multivariable Calculus Laplace Transforms, Numerical Methods and Complex variables

3 1 0 4**Course objectives:**

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

Course Outcomes: At the end of this course, students will demonstrate the ability to

1. Understand the modeling of linear-time-invariant systems using transfer function and state-space representations.
2. Understand the concept of stability and its assessment for linear-time invariant systems.
3. Design simple feedback controllers.

UNT - I

Introduction to Control Problem: Industrial Control examples. Mathematical models of physical systems. Control hardware and their models. Transfer function models of linear time-invariant systems. Feedback Control: Open-Loop and Closed-loop systems. Benefits of Feedback. Block diagram algebra. Representation by Signal flow graph - Reduction using mason's gain formula

UNT - II

Time Response Analysis of Standard Test Signals: Time response of first and second order systems for standard test inputs. Application of initial and final value theorem. Design specifications for second-order systems based on the time-response. Concept of Stability. Routh-Hurwitz Criteria. Relative Stability analysis. Root-Locus technique. Construction of Root-loci.

UNT - III

Frequency-Response Analysis: Relationship between time and frequency response, Polar plots, Bode plots. Nyquist stability criterion. Relative stability using Nyquist criterion – gain and phase margin. Closed-loop frequency response.

UNT - IV

Introduction to Controller Design: Stability, steady-state accuracy, transient accuracy, disturbance rejection, insensitivity and robustness of control systems. Root-loci method of feedback controller design. Design specifications in frequency-domain. Frequency-domain methods of design. Application of Proportional, Integral and Derivative Controllers, Lead and Lag compensation in designs. Analog and Digital implementation of controllers.

UNT - V

State Variable Analysis and Concepts of State Variables: State space model. Diagonalization of State Matrix. Solution of state equations. Eigen values and Stability Analysis. Concept of controllability and observability. Pole-placement by state feedback. Discrete-time systems. Difference Equations. State-space models of linear discrete-time systems. Stability of linear discrete-time systems.

TEXT BOOKS:

1. M. Gopal, "Control Systems: Principles and Design", McGraw Hill Education, 1997.
2. B. C. Kuo, "Automatic Control System", Prentice Hall, 1995.

REFERENCE BOOKS:

1. K. Ogata, "Modern Control Engineering", Prentice Hall, 1991.
2. J. Nagrath and M. Gopal, "Control Systems Engineering", New Age International, 2009.