II Year – II SEMESTER

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CONTROL SYSTEMS

Preamble :

This course introduces the elements of linear control systems and their analysis. Classical methods of design using frequency response are included. The state space approach for modeling and analysis is the added feature of this course.

UNIT – I:

Learning Objective:

To learn the mathematical modeling of physical systems and to use block diagram algebra and signal flow graph to determine overall transfer function.

MATHEMATICAL MODELING OF CONTROL SYSTEMS

Open Loop and closed loop control systems and their differences, Classification of control systems, Feed-Back Characteristics, transfer function of linear system, Differential equations of electrical networks, Translational and Rotational mechanical systems, Transfer Function of DC Servo motor - AC Servo motor- Synchro-transmitter and Receiver, Block diagram algebra – Representation by Signal flow graph - Reduction using Mason's gain formula.

Outcome:

Ability to derive the transfer function of physical systems and determination of overall transfer function using block diagram algebra and signal flow graphs.

UNIT-II:

Learning Objective:

To analyze the time response of first and second order systems and improvement of performance by proportional plus derivative and proportional plus integral controllers.

TIME RESPONSE ANALYSIS

Standard test signals - Time response of first order systems –Time response of second order systems - Time domain specifications - Steady state errors and error constants – Effects of proportional derivative, proportional integral systems.

Outcome:

Capability to determine time response specifications of second order systems and to determine error constants.

UNIT – III:

Learning Objective :

To investigate the stability of closed loop systems using Routh's stability criterion and the analysis by root locus method.

STABILITY AND ROOTLOCUS TECHNIQUE

The concept of stability – Routh's stability criterion –limitations of Routh's stability – The root locus concept - construction of root loci (Simple problems).

Outcome:

Acquires the skill to analyze absolute and relative stability of LTI systems using Routh's stability criterion and the root locus method.

UNIT–IV:

Learning Objective :

To present the Frequency Response approaches for the analysis of linear time invariant (LTI) systems using Bode plots, polar plots and Nyquist stability criterion.

FREQUENCY RESPONSE ANALYSIS

Introduction, Frequency domain specifications-Bode diagrams- transfer function from the Bode Diagram-Phase margin and Gain margin-Stability Analysis from Bode Plots, Polar Plots, Nyquist Stability criterion.

Outcome:

Capable to analyze the stability of LTI systems using frequency response methods.

UNIT–V:

Learning Objective :

To discuss basic aspects of design and compensation of linear control systems using Bode plots.

CLASSICAL CONTROL DESIGN TECHNIQUES

Lag, Lead, Lag-Lead compensators, design of compensators – using Bode plots.

Outcome:

Able to design Lag, Lead, Lag-Lead compensators to improve system performance from Bode diagrams.

UNIT–VI:

Learning Objective:

Ability to formulate state models and analyze the systems. To present the concepts of Controllability and Observability.

STATE SPACE ANALYSIS OF CONTINUOUS SYSTEMS

Concepts of state, state variables and state model, state space representation of transfer function, Diagonalization- Solving the Time invariant state Equations- State Transition Matrix and it's Properties – Concepts of Controllability and Observability.

Outcome:

Ability to represent physical systems as state models and determine the response. Understanding the concepts of controllability and observability.

TEXT BOOKS:

1. Modern Control Engineering, Kotsuhiko Ogata, Prentice Hall of India.
2. Automatic control systems, Benjamin C.Kuo, Prentice Hall of India, 2nd Edition

REFERENCE BOOKS:

1. Control Systems, Manik Dhanesh N, Cengage publications .
2. Control Systems principles and design, M.Gopal, Tata Mc Graw Hill education Pvt Ltd., 4th Edition.
3. Control Systems Engineering, S.Palani, Tata Mc Graw Hill Publications.