



Paper Code: ARI 208

Subject: Control Systems

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T/P
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Credits
4

Marking Scheme

- Teachers Continuous Evaluation: 25 Marks
- End Term Theory Examination: 75 Marks

INSTRUCTIONS TO PAPER SETTERS:

Maximum Marks : 75

- There should be 9 questions in the end term examination question paper
- Question No. 1 should be compulsory and cover the entire syllabus. This question should have objective or short answer type questions. It should be of 15 marks.
- Apart from Question No. 1, rest of the paper shall consist of four units as per the syllabus. Every unit should have two questions. However, student may be asked to attempt only 1 question from each unit. Each question should be 15 marks.
- The questions are to be framed keeping in view the learning outcomes of course/paper. The standard/level of the questions to be asked should be at the level of the prescribed textbooks.
- The requirement of (scientific) calculators/ log-tables/ data-tables may be specified if required

Course Outcomes:

CO1:	Ability of students to utilize concepts of control system components and mathematical modeling of electrical system, mechanical system, etc.										
CO2:	Ability of students to identify and implement the concept of time response and frequency response of the system.										
CO3:	Ability of students to utilize understanding of different plots such as Bode plot, Nyquist plot, Root locus method and Polar plot and implement them for robot applications										
CO4:	Ability of students to practically implement knowledge on joint space and task space control schemes in robots.										

Course Outcomes (CO) to Programme Outcomes (PO) Mapping (Scale 1: Low, 2: Medium, 3: High)

CO/PO	PO01	PO02	PO03	PO04	PO05	PO06	PO07	PO08	PO09	PO10	PO11	PO12
CO1	3	3	3	3	2	-	-	-	1	1	-	3
CO2	3	3	3	3	2	-	-	-	1	1	-	3
CO3	3	3	3	3	-	-	-	-	1	1	-	3
CO4	3	3	3	3	-	-	-	-	1	1	-	3

Unit I

[10]

Introduction to Control System:

Elements of control systems, concept of open loop and closed loop systems. Examples and application of open loop and closed loop systems. Concept of feedback and Automatic control. Effects of feedback. Transfer function of electrical, mechanical (translational and rotational) System. Force Voltage and Force Current analogies.

Transfer function model of AC & DC servomotor, potentiometer & tacho-generator. Block diagram reduction technique and signal flow graph, Mason's rule. Signal flow graph of electrical network. Conversion of BDR to SFG and vice versa.

Unit II

[10]

Time Domain Analysis: Time domain analysis of a standard second order closed loop system. Concept of un-damped natural frequency, damping, overshoot, rise time and settling time. Dependence of time domain performance parameters on natural frequency and damping ratio. Step and Impulse response of first and second order systems. Effects of Pole and Zeros

Prof. Ajay S. Singholi

Professor In-charge, USAR

Approved by BoS of USAR: 1/08/22

Approved by Ad. Sub-committee: 29/08/22

Applicable from Batch Admitted in Academic Session 2021-22 Onwards

Guru Gobind Singh Indraprastha University

(East Delhi Campus)

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Surajmal Vihar, Delhi-110092



**University School of Automation and Robotics
GURU GOBIND SINGH INDRAPRASTHA UNIVERSITY
East Delhi Campus, Surajmal Vihar
Delhi - 110092**

on transient response. Stability by pole location. Routh-Hurwitz criteria and applications. Error Analysis: Steady state errors in control systems due to step, ramp and parabolic inputs. Concepts of system types and error constants. Root locus Techniques: Definition and properties of root locus, rules for plotting root locus, stability analysis using root locus.

Frequency Domain Analysis:

Polar plots, Bode plot, stability in frequency domain, Nyquist plots. Nyquist stability criterion. Gain margin and phase margin via Nyquist diagram and Bode plots.

Unit III

[10]

State Variable Analysis

Introduction to state variable, General state space representation, State space representation of Electrical and Mechanical systems. Conversion between state space and transfer function. Alternative representations in state space: (Phase variable, canonical, parallel & cascade).

Similarity transformations, diagonalizing a system matrix. Laplace Transform solution of state equation, stability in state space, pole placement topology, controller design by pole placement topology in phase variable form, controllability, controllability matrix, controllability by inspection, alternative approach to controller design, controller design by transformation.

Introduction to Observer / estimator, observability, observability matrix, observability by inspection, observer design by pole placement, alternative approach to Observer design. Steady state error design using integral control.

Unit IV

[10]

Introduction to the Compensator:

Basic concept of compensator design, requirement, cascade compensator, feedback compensator, gain compensation, lag, lead and lag-lead compensator, proportional, derivative, integral Compensation, physical realization of compensator with passive and active components, basic block diagrams of a compensated closed loop control system.

Textbooks: -

1. Nise N. (2004). *Control system engineering*. 2nd edition
2. Kuo B. C. (1995) *Digital Control Systems*. Oxford series. 2nd Edition
3. Wilkie J., Johnson M., Katebi R. (2002). *Control Engineering: An Introductory Course*. Palgrave MacMillan.

Reference Books: -

1. Dorf R.C., (1998). *Modern control Engineering*. SH Bishop, & Wesley edition, Eighth Edition.
2. J. J. Azzo, Houpis C. H., Sheldon S. N., Dekkar M. (2003). *Linear Control system Analysis and design with MATLAB*. ISBN 0824740386

Prof. Ajay S. Singholi
Professor In-charge, USAR
Guru Gobind Singh Indraprastha University
(East Delhi Campus)
Surajmal Vihar, Delhi-110092