Course code	Course Name	L-T-P -Credits	Year of Introduction
EE304	**Advanced Control Theory**	**3-1-0-4**	**2016**

Prerequisite: EE303 Linear control systems

Course Objectives:

- To provide a strong concept on the compensator design and on advanced control system analysis and design techniques
- To analyse the behaviour of discrete time systems and nonlinear control systems.

Syllabus:

Compensator design-Frequency domain approach-root locus method-Tuning of P, PI and PID controller-State space analysis of systems-state feedback controller design-sampled data control systems-Nonlinear systems-describing function-phase plane-Lyapunov method.

Expected outcome.

On successful completion, students will have the ability to

i. design compensators using classical techniques.
ii. analyse both linear and nonlinear system using state space methods.
iii. analyse the stability of discrete system and nonlinear system.

Text Book:

1. Hassan K Khalil, Nonlinear Systems, Prentice - Hall International (UK), 2002.
2. Kuo B.C, Analysis and Synthesis of Sampled Data Systems, Prentice Hall Publications.
3. Nagarath I. J. and Gopal M., Control System Engineering, Wiley Eastern, 2008.
4. Nise N. S., Control Systems Engineering, 6/e, Wiley Eastern, 2010.
5. Ogata K., Modern Control Engineering, Prentice Hall of India, New Delhi, 2010.

Data Book (Approved for use in the examination):

References:

1. Alberto Isidori, Nonlinear Control Systems, Springer Verlag, 1995.
2. Gibson J. E., F.B. Tuteur and J. R. Ragazzini, Control System Components, Tata McGraw Hill, 2013
3. Gopal M., Control Systems Principles and Design, Tata McGraw Hill, 2008.
4. Jean-Jacques E. Slotine & Weiping Li, Applied Nonlinear Control, Prentice-Hall., NJ, 1991.

Course Plan

Module	Contents	Hours	Sem. Exam Marks
I	Types of controller- Feedforward-feedback-cascade-P, PI and PID. Compensator design: Realization of compensators – lag, lead and lag-lead -Design of compensator using bode plot.	7	15%
II	Compensator design: Realization of compensators – lag, lead and lag-lead. Design of compensator using rootlocus. Design of P, PI and PID controller using Ziegler-Nichols tuning method.	7	15%
FIRST INTERNAL EXAMINATION			
III	State space analysis of systems: Introduction to state concept - state equation of linear continuous time systems, matrix representation of state equations. Phase variable and canonical forms of state representation-controllable, observable, diagonal	7	15%

	and Jordan canonical forms- solution of time invariant autonomous systems, forced system-state transition matrix-relationship between state equations and transfer function. Properties of state transition matrix-Computation of state transition matrix using Laplace transform-Cayley-Hamilton method. Conversion from canonical form to phase variable form.		
IV	State feedback controller design: Controllability & observability. State feed-back design via pole placement technique. Sampled data control system: Pulse Transfer function-Stability of sampled data system -Routh Hurwitz criterion and Jury's test. Introduction to state-space representation of sampled data systems.	7	15%
SECOND INTERNAL EXAMINATION			
V	Nonlinear systems: Introduction - characteristics of nonlinear systems. Types of nonlinearities. Analysis through harmonic linearisation - Determination of describing function of nonlinearities (relay, dead zone and saturation only) - application of describing function for stability analysis of autonomous system with single nonlinearity.	7 hrs	20%
VI	Phase Plane Analysis: Concepts- Construction of phase trajectories for nonlinear systems and linear systems with static nonlinearities - Singular points – Classification of singular points. Definition of stability- asymptotic stability and instability Liapunov methods to stability of linear and nonlinear, continuous time systems.	7 hrs	20%
END SEMESTER EXAM			

QUESTION PAPER PATTERN:

Maximum Marks: 100 Exam Duration: 3Hourrs.

Part A: 8 compulsory questions.

One question from each module of Modules I - IV; and two each from Module V & VI.

Student has to answer all questions. (8 x5)=40

Part B: 3 questions uniformly covering Modules I & II. Student has to answer any 2 from the 3 questions: (2 x 10) =20. Each question can have maximum of 4 sub questions (a,b,c,d), if needed.

Part C: 3 questions uniformly covering Modules III & IV. Student has to answer any 2 from the 3 questions: (2 x 10) =20. Each question can have maximum of 4 sub questions (a,b,c,d), if needed.

Part D: 3 questions uniformly covering Modules V & VI. Student has to answer any 2 from the 3 questions: (2 x 10) =20. Each question can have maximum of 4 sub questions (a,b,c,d), if needed.