

**B.Tech. ELECTRICAL ENGINEERING
(BTCLVI)**

Term-End Examination

December, 2013

BIEEE-017 : ADVANCED CONTROL SYSTEM

Time : 3 Hours

Maximum Marks : 70

*Note : Attempt **any seven** questions out of **10** questions. Use of scientific calculator is **permitted**.*

1. Consider the state space model of a system with 10

$$A = \begin{bmatrix} 0 & 1 & 0 \\ 0 & -1 & 1 \\ 0 & -1 & -10 \end{bmatrix}; B = \begin{bmatrix} 0 \\ 0 \\ 10 \end{bmatrix}; C = [1 \ 0 \ 0]$$

Obtain characteristic polynomial and transfer function of the system.

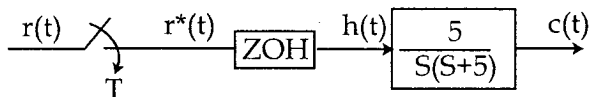
2. (a) Show that the system given by 2x5=10

$$\dot{x} = \begin{bmatrix} 0 & 1 \\ -1 & -2 \end{bmatrix} x + \begin{bmatrix} 1 \\ -1 \end{bmatrix} u$$

is not controllable.

- (b) Explain the procedure for designing state observer.

3. For the system shown find the output at the sampling instants $C(KT)$. The input is a unit impulse and the sampling period is 0.1s. Find the final value $C(KT)$ as $K \rightarrow \infty$ 10



4. State and explain Jury's stability criterion. For the following characteristic polynomial investigate the necessary and sufficient condition of stability : 10

$$F(z) = z^4 + 17z^3 + 2z^2 + 2z + 2$$

5. An ideal relay is introduced as a non linearity in a unity feedback linear servo system with forward transfer function. 10

$$G(S) = \frac{100}{S(0.1S + 1)}$$

The relay has a maximum output of 10 volts.
Discuss the stability of the system.

6. Write notes on : 2x5=10
- Popov's stability criterion.
 - Common non-linearities.

7. Find an extremal for the functional 10

$$J(X) = \int_0^{\pi/2} [\dot{X}^2(t) - X^2(t)] dt \text{ which satisfies the}$$

boundary conditions. $X(0) = 0$ and $X(\pi/2) = 1$

8. Explain : 2x5=10
- Constrained optimization.
 - Linear quadratic problem.

9. What do you understand by adaptive control ? 10
Give the classification of Model Reference
adaptive control. Also explain its features.
10. (a) Give the scheme for self tuning control
system. 2x5=10
(b) State Fuzzy rules of Mamdani.
-