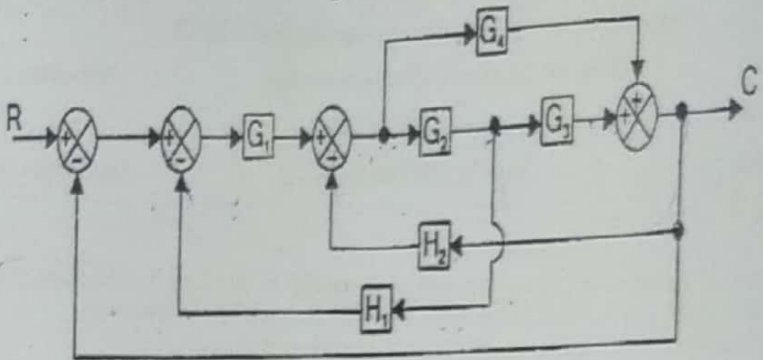


**Instructions to the Students:**

1. All the questions are compulsory.
2. The level of question/expected answer as per OBE or the Course Outcome (CO) on which the question is based is mentioned in ( ) in front of the question.
3. Use of non-programmable scientific calculators is allowed.
4. Assume suitable data wherever necessary and mention it clearly.

	(Level/CO)	Marks
<b>Q.1 Solve Any Two of the following.</b>		<b>12</b>
A) Define sensitivity? Explain the effect of feedback gain on sensitivity.	L1	6
B) Obtain transfer function $\frac{I_2(S)}{V(S)}$ of given system.	L2	6
C) Obtain Transfer Function of given mechanical rotational system	L3	6
<b>Q.2 Solve Any Two of the following.</b>		<b>12</b>
A) Determine transfer function using signal flow graph.	L2	6
B) Explain open loop system and closed loop control system with example.	L2	6

	<p>C) Obtain transfer function of given system.</p> 	L2	6
Q. 3	Solve Any Two of the following.		12
A)	Define order and Type of the system? Explain response of first order system for unit step input.	L3	6
B)	<p>Find the steady state error for unit step, unit ramp and unit acceleration inputs for the following systems.</p> $TF = \frac{10}{S(0.1S + 1)(0.5S + 1)}$	L1	6
C)	<p>Determine delay time, rise time, peak time, settling time and maximum overshoot of the given system</p> $TF = \frac{10}{(S + 2)(S + 5)}$	L2	6
Q.4	Solve Any Two of the following.		12
A)	<p>Explain PI Controller and PD Controller with its advantages and disadvantages.</p>	L1	6
B)	<p>Sketch bode plot of given equation and determine phase margin and gain margin.</p> $G(S) = \frac{75(1 + 0.2S)}{S(S^2 + 16S + 100)}$	L3	6
C)	<p>Determine stability of given characteristics equation using Routh array Criterion.</p> $\text{Characterstics eq} = S^4 + 8S^3 + 18S^2 + 16S + 5 = 0$	L3	6
Q. 5	Solve Any Two of the following.		12
A)	<p>Sketch root locus of given open loop transfer function.</p> $G(S) = \frac{K}{S(S^2 + 4S + 13)}$	L3	6

ENGG SOLUTION

2=9

X

B)	Derive expression for transfer function equation using state space equation formula.	L2	6
C)	Verify controllability and observability of control system which is represented in state space model.  $\dot{\mathbf{x}} = \begin{bmatrix} \dot{x}_1 \\ \dot{x}_2 \end{bmatrix} = \begin{bmatrix} -1 & -1 \\ 1 & 0 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} + \begin{bmatrix} 1 \\ 0 \end{bmatrix} [u]$ $Y = [0 \quad 1] \begin{bmatrix} x_1 \\ x_2 \end{bmatrix}$	L3	6
*** End ***			

ENGG SOLUTION