UNIVERSITY DEPARTMENTS

ANNA UNIVERSITY, CHENNAI

REGULATIONS – 2013 (FULL TIME)

CURRICULUM FROM I TO IV SEMESTERS FOR

M.E CONTROL AND INSTRUMENTATION ENGINEERING

SEMESTER I

SL.NO.	CODE NO.	COURSE TITLE	L	T	P	C
THEORY						
1.	CO8101	Control System Design	3	1	0	4
2.	CO8102	Transducers and Measurements	3	1	0	4
3.	CO8151	Soft Computing Techniques	3	0	2	4
4.	MA8156	Applied Mathematics for Electrical Engineers	3	1	0	4
5.		Elective I	3	0	0	3
PRACTICAL						
6.	CO8111	Control System Design Lab	0	0	3	2
		TOTAL	**15**	**3**	**5**	**21**

SEMESTER – II

SL.NO.	CODE	COURSE TITLE	L	T	P	C
THEORY						
1.	CO8201	Dynamics and Control of Industrial Process	3	1	0	4
2.	CO8202	Industrial Process Automation	3	1	0	4
3.	CO8251	Non Linear Control	3	0	2	4
4.		Elective II	3	0	0	3
5.		Elective III	3	0	0	3
PRACTICAL						
6.	CO8211	Automation Lab	0	0	3	2
		TOTAL	**15**	**2**	**5**	**20**

SEMESTER – III

SL.NO.	CODE NO.	COURSE TITLE	L	T	P	C
THEORY						
1.		Elective IV	3	0	0	3
2.		Elective V	3	0	0	3
3.		Elective VI	3	0	0	3
PRACTICAL						
4.	CO8311	Project Work Phase I	0	0	12	6
		TOTAL	**9**	**0**	**12**	**15**

Attested

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SEMESTER – IV

SL.NO.	CODE NO.	COURSE TITLE	L	T	P	C
PRACTICAL						
1.	CO8411	Project Work Phase II	0	0	24	12
		TOTAL	**0**	**0**	**24**	**12**

TOTAL NO OF CREDITS : 68

ELECTIVES

Control & Instrumentation

SL. NO	COURSE CODE	COURSE TITLE	L	T	P	C
1	CO8001	Advanced Non-linear Systems	3	0	0	3
2	CO8002	Control of Electrical Drives	3	0	0	3
3	CO8003	Multi Sensor Data Fusion	3	0	0	3
4	CO8004	Optimal Control and Filtering	3	0	0	3
5	CO8071	Robotics and Control	3	0	0	3
6	CO8072	Robust Control	3	0	0	3
7	CO8073	System Identification and Adaptive Control	3	0	0	3
8	CO8074	System Theory	3	0	0	3

ELECTIVES FROM OTHER PG DIVISIONS

SL. NO	COURSE CODE	COURSE TITLE	L	T	P	C
1	PW8203	SCADA System and Applications Management	3	0	0	3
2	ET8071	Advanced Digital Signal Processing	3	0	0	3
3	ET8072	MEMS Technology	3	0	0	3
4	ET8151	Advanced Digital Principles and Design	3	1	0	4
5	ET8152	Microcontroller Based System Design	3	0	0	3
6	ET8251	Real Time Operating System	3	0	0	3
7	ET8252	Software for Embedded Systems	3	1	0	4
8	ET8253	VLSI Based Design Methodologies	3	1	0	4
9	HV8071	Applications of High Electric Fields	3	0	0	3
10	HV8072	Electromagnetic Interference and Compatibility	3	0	0	3
11	IN8251	Applied Industrial Instrumentation	3	0	0	3
12	PE8152	Analysis of Electrical Machines	3	0	0	3
13	PE8153	Analysis of Power Converters	3	0	0	3
14	PE8251	Solid State DC Drives	3	0	0	3
15	PE8252	Special Electrical Machines	3	0	0	3
16	PE8351	Power Electronics for Renewable Energy Systems	3	0	0	3
17	HV8073	Design of Substations	3	0	0	3
18	PS8075	Optimisation Techniques	3	0	0	3
19	PS8076	Solar and Energy Storage System	3	0	0	3
20	PS8255	Smart Grids	3	0	0	3

Attested

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CO8101 **CONTROL SYSTEM DESIGN** **LT P C**
3 1 0 4

PROGRAM OBJECTIVE

- To impart knowledge on performance specification, limitations and structure of controllers
- To impart knowledge on design of controllers using root-locus and frequency domain techniques
- To educate on concept of state space and design of controllers and observers
- To introduce the techniques of extending the theory on continuous systems to discrete time systems
- To introduce the linear quadratic regulator and estimation in the presence of noise

UNIT I BASICS AND ROOT-LOCUS DESIGN 9

Design specifications-sensitivity and stability- Limitations- Controller structure- one and two degrees of freedom- PID controllers and Lag-lead compensators- Root locus design- Design examples

UNIT II FREQUENCY RESPONSE BASED DESIGN 9

PID controllers and Lag-lead compensators – Design using Bode plots- use of Nyquist plots and Routh-hurwitz Criterion-Design examples

UNIT III STATE VARIABLE DESIGN 9

Representation- solution- Controlability, observability- state and output feedback- observers - estimated state feedback –PID control via state feedback- compensator design- Design examples

UNIT IV DESIGN IN DISCRETE DOMAIN 9

Sample and Hold devices -Discretisation - Effect of sampling on transfer function and state models- Direct discrete design -Design examples

UNIT V LQR AND LQG DESIGN 9

Formulation of LQR problem- Pontryagin's minimum principle and Hamiltonian solutions- Ricatti's equation – Optimal estimation- Kalman filter –solution to continuous and discrete systems - Design examples.

L=45, T=15, TOTAL= 60 PERIODS

REFERENCES

1. M. Gopal "Modern control system Theory" New Age International, 2005.
2. Arthur G. O. Mutambara, "Design and Analysis of Control Systems", CRC Press, Indian reprint 2009.
3. G. F. Franklin, J. D. Powell and A. E. Naeini "Feedback Control of Dynamic Systems", PHI (Pearson), 2002.

4. Graham C. Goodwin, Stefan F. Graebe and Mario E. Salgado “Control system Design”, PHI (Pearson), 2003.
5. G. F. Franklin, J. D. Powell and M Workman, “Digital Control of Dynamic Systems”, PHI (Pearson), 2002.
6. B.D.O. Anderson and J.B. Moore., ‘Optimal Filtering’, Prentice hall Inc., N.J., 1979.
7. Loan D. Landau, Gianluca Zito,” Digital Control Systems, Design, Identification and Implementation”, Springer, 2006.
8. Benjamin C. Kuo “Digital control systems”, Oxford University Press, 2004.

CO8102 TRANSDUCERS AND MEASUREMENTS L T P C
3 1 0 4

PROGRAM OBJECTIVE

- To introduce the resistive, inductive and capacitive transducers and their transduction principles
- To educate on magnetic transducer elements
- Study of acoustic , mechanical and flow metering elements , their working principle
- To introduce various optical sensors, their transduction principles and their applications
- To introduce various advanced and miniature sensors and their applications

UNIT I RESISTIVE, INDUCTIVE AND CAPACITIVE ELEMENTS 9

Potentiometric, strain-gage and electrode elements – Inductive and Capacitive elements: structures, equivalent circuits and characteristics, single, differential and angle displacement elements, displacement to phase converters, and proximity elements, magnetostrictive elements, temperature instabilities and features.

UNIT II TRANSFORMER, ELECTRODYNAMIC, SERVO AND RESONANT ELEMENTS 9

Transformer elements: Single core, differential, rotating coil and synchro transformers, weak-field sensors - Electrodynamic elements: Moving-coil, variable-reluctance- - Resonant elements: vibrating strings, vibrating beams, vibrating cylinders, piezoelectric resonators, acoustical resonators, microwave cavity resonators.

UNIT III MECHANICAL, ACOUSTICAL AND FLOWMETERING ELEMENTS 9

Stresses state of diaphragm, dynamic characteristics of diaphragm, temperature drifts, sensitivity drifts, sensitivity to acceleration – Inertial mass elements: sensing and transduction elements of flowmeters, electromagnetic flowmeters, nanoelectrode electromagnetic flowmeters -ultrasonic elements – Acoustical elements: acoustical filters.

UNIT IV OPTICAL MICROSTRUCTURE SENSORS 9

Photo detectors: Thermal detectors, pneumatic detectors, pyroelectric detectors, photoemissive devices, photo conductive detectors, photo diodes, avalanche photo diodes, schottky photo diodes, photo transistors – Fiber optic sensors: Fibers as light guides, reflection sensors, Intrinsic multimode sensor, temperature sensor, phase modulated sensor, fiber optic gyroscopes and other fiber sensors

UNIT V MISCELLANEOUS MINIATURE SENSORS 9

Magnetic sensors: Hall Effect sensors, magnetoresistors and other sensors – Solid state chemical sensors: Silicon based sensors, metal oxide sensors, solid electrolyte sensors, membranes – Electromechanical micro sensors and basic factors of design

L=45, T=15 TOTAL : 60 PERIODS

REFERENCES:

1. Alexander D Khazan, “Transducers and their elements – Design and application”, PTR Prentice Hall, 1994.
2. Pavel Ripka and Alois Tipek,“Modern sensors hand book”, Instrumentation and measurement series, ISTE Ltd., 2007
3. David Fraden. , PHI, 2004 “ Hand book of Modern Sensors, Physics,Design and Applications”, Third Edition, Springer India Pvt.Ltd, 2006.

CO8151	SOFT COMPUTING TECHNIQUES	LT P C 3 0 2 4

PROGRAM OBJECTIVES

- To review the fundamentals of ANN and fuzzy set theory
- To make the students understand the use of ANN for modeling and control of non-linear system and to get familiarized with the ANN tool box.
- To impart knowledge of using Fuzzy logic for modeling and control of non-linear systems and get familiarized with the FLC tool box.
- To make the students to understand the use of optimization techniques.
- To familiarize the students on various hybrid control schemes, P.S.O and get familiarized with the ANFIS tool box.

UNIT I OVERVIEW OF ARTIFICIAL NEURAL NETWORK (ANN) & FUZZY LOGIC 9

Review of fundamentals - Biological neuron, Artificial neuron, Activation function, Single Layer Perceptron – Limitations – Multi Layer Perceptron – Back propagation algorithm (BPA); Fuzzy set theory – Fuzzy sets – Operation on Fuzzy sets - Scalar cardinality, fuzzy cardinality, union and intersection, complement (yager and sugeno), equilibrium points, aggregation, projection, composition, decomposition, cylindrical extension, fuzzy relation – Fuzzy membership functions.

UNIT II NEURAL NETWORKS FOR MODELLING AND CONTROL 9

Modeling of non linear systems using ANN- NARX,NNSS,NARMAX - Generation of training data - optimal architecture – Model validation- Control of non linear system using ANN- Direct and Indirect neuro control schemes- Adaptive neuro controller – Case study - Familiarization of Neural Network Control Tool Box.

UNIT III FUZZY LOGIC FOR MODELLING AND CONTROL 9

Modeling of non linear systems using fuzzy models(Mamdani and Sugeno) –TSK model - Fuzzy Logic controller – Fuzzification – Knowledge base – Decision making logic – Defuzzification-Adaptive fuzzy systems- Case study - Familiarization of Fuzzy Logic Tool Box.

UNIT IV GENETIC ALGORITHM 9

Basic concept of Genetic algorithm and detail algorithmic steps, adjustment of free parameters. Solution of typical control problems using genetic algorithm. Concept on some

other search techniques like Tabu search, Ant-colony search and Particle Swarm Optimization.

UNIT IV HYBRID CONTROL SCHEMES 9

Fuzzification and rule base using ANN–Neuro fuzzy systems-ANFIS –Optimization of membership function and rule base using Genetic Algorithm and Particle Swarm Optimization - Case study–Introduction to Support Vector Regression – Familiarization of ANFIS Tool Box.

TOTAL : 45+30 = 75 PERIODS

Soft Computing Techniques - Lab

To implement adaline and madaline with bipolar inputs and outputs using NN toolbox.
To implement back propagation for a given input pattern using NN toolbox.
To implement discrete hopfield network and test for given input pattern using NN toolbox.
To implement fuzzy set operation and properties using FUZZY toolbox.
To perform max-min composition of two matrices obtained from Cartesian product using 'm file' in MATLAB.
Write a program to verify the various laws associated with fuzzy set using FUZZY toolbox.
Write a matlab program for maximizing $f(x) = x^2$ using GA, where x is ranges from 0 to 31 (Perform only 5 iterations). Find the objective function and 'x' value.
Design FLC for a FOPDT process using FUZZY toolbox.
Design a Neuro model for an inverted pendulum using NN toolbox.
Design Fuzzy model for an inverted pendulum using FUZZY toolbox.

REFERENCES

1. Laurene V.Fausett, "Fundamentals of Neural Networks, Architecture, Algorithms, and Applications", Pearson Education, 2008.
2. Timothy J.Ross, "Fuzzy Logic with Engineering Applications", Wiley, Third Edition, 2010.
3. George J.Klir and Bo Yuan, "Fuzzy Sets and Fuzzy Logic: Theory and Applications", Prentice Hall, First Edition, 1995.
4. David E.Goldberg, "Genetic Algorithms in Search, Optimization, and Machine Learning", Pearson Education, 2009.
5. W.T.Miller, R.S.Sutton and P.J.Webrose, "Neural Networks for Control", MIT Press, 1996.
6. C.Cortes and V.Vapnik, "Support-Vector Networks, Machine Learning", 1995.

MA8156 APPLIED MATHEMATICS FOR ELECTRICAL ENGINEERS L T P C
3 1 0 4

OBJECTIVES:

- To develop the ability to apply the concepts of Matrix theory and Linear programming in Electrical Engineering problems.
- To achieve an understanding of the basic concepts of one dimensional random variables and apply in electrical engineering problems.
- To familiarize the students in calculus of variations and solve problems using Fourier transforms associated with engineering applications.

UNIT I MATRIX THEORY (9+3)

The Cholesky decomposition - Generalized Eigen vectors, Canonical basis - QR factorization - Least squares method - Singular value decomposition.

UNIT II CALCULUS OF VARIATIONS (9+3)

Concept of variation and its properties – Euler's equation – Functional dependant on first and higher order derivatives – Functionals dependant on functions of several independent variables – Variational problems with moving boundaries – problems with constraints - Direct methods: Ritz and Kantorovich methods.

UNIT III ONE DIMENSIONAL RANDOM VARIABLES (9+3)

Random variables - Probability function – moments – moment generating functions and their properties – Binomial, Poisson, Geometric, Uniform, Exponential, Gamma and Normal distributions – Function of a Random Variable.

UNIT IV LINEAR PROGRAMMING (9+3)

Formulation – Graphical solution – Simplex method – Two phase method - Transportation and Assignment Models

UNIT V FOURIER SERIES (9+3)

Fourier Trigonometric series: Periodic function as power signals – Convergence of series – Even and odd function: cosine and sine series – Non-periodic function: Extension to other intervals - Power signals: Exponential Fourier series – Parseval's theorem and power spectrum – Eigen value problems and orthogonal functions – Regular Sturm-Liouville systems – Generalized Fourier series.

L:45 +T: 15 TOTAL: 60 PERIODS

BOOKS FOR STUDY:

1. Richard Bronson, "Matrix Operation", Schaum's outline series, 2nd Edition, McGraw Hill, 2011.
2. Gupta, A.S., Calculus of Variations with Applications, Prentice Hall of India Pvt. Ltd., New Delhi, 1997.
3. Oliver C. Ibe, "Fundamentals of Applied Probability and Random Processes, Academic Press, (An imprint of Elsevier), 2010.
4. Taha, H.A., "Operations Research, An introduction", 10th edition, Pearson education, New Delhi, 2010.
5. Andrews L.C. and Phillips R.L., Mathematical Techniques for Engineers and Scientists, Prentice Hall of India Pvt.Ltd., New Delhi, 2005.

REFERENCES:

1. Elsgolts, L., Differential Equations and the Calculus of Variations, MIR Publishers, Moscow, 1973.
2. Grewal, B.S., Higher Engineering Mathematics, 42nd edition, Khanna Publishers, 2012.
3. O'Neil, P.V., Advanced Engineering Mathematics, Thomson Asia Pvt. Ltd., Singapore, 2003.
4. Johnson R. A. and Gupta C. B., "Miller & Freund's Probability and Statistics for Engineers", Pearson Education, Asia, 7th Edition, 2007.

CO8111 CONTROL SYSTEM DESIGN LAB L T P C
0 0 3 2

1. Simulation of transfer function models and obtain time and frequency response
2. Simulation of state space models for linear continuous and discrete time systems and obtain the time response
3. Mathematical modeling and simulation of a mechanical system
4. Mathematical modeling and simulation of a electrical mechanical system
5. Mathematical modeling and simulation of a power electronic system
6. Mathematical modeling and simulation of a chemical process
7. Design and performance analysis of PID controlled physical systems using Root-locus technique
8. Design and performance analysis of PID controlled physical systems using Bode plots
9. Design and performance analysis of PID controlled physical systems using Zeigler Nichols approach
10. Design and performance analysis of Lag-lead compensator controlled physical systems using Bode plots
11. Solution of Ricatti's equation in continuous and discrete domain
12. Design and performance analysis of state and output feedback control of physical systems
13. Design and performance analysis of estimator and estimated feedback control of physical systems
14. Design and performance analysis of optimal control of physical systems
15. Design and performance analysis of optimal estimation and control of physical systems

TOTAL : 45 PERIODS

CO8201 DYNAMICS AND CONTROL OF INDUSTRIAL PROCESS **L T P C**
3 1 0 4

OBJECTIVES

- To give an overview of the features associated with Industrial Type PID Controller such as reset windup, bumpless auto-manual transfer, proportional kick and derivative kick.
- To make the students understand the various PID tuning methods
- To elaborate different types of control schemes such as cascade control, feed-forward control etc.
- To educate on multivariable systems and multi-loop control
- To educate on various industrial processes

UNIT I PROCESS DYNAMICS & CONTROL ACTIONS 9

Need for process control – Hierarchical decomposition of Control Functions - Continuous and batch processes – P&ID diagram - Self regulation - Interacting and non-interacting systems - Mathematical model of Level, Flow and Thermal processes – Lumped and Distributed parameter models – Linearization of nonlinear systems - Characteristic of ON-OFF, P, P+I, P+D and P+I+D control modes – Digital PID algorithm – Auto/manual transfer - Reset windup – Practical forms of PID Controller

UNIT II PID CONTROLLER TUNING – SINGLE LOOP REGULATORY CONTROL 9

Evaluation criteria – IAE, ISE, ITAE and ¼ decay ratio – Tuning - Process reaction curve method- Z-N and Cohen-Coon methods, Continuous cycling method and Damped oscillation method – optimization methods – Auto tuning.

UNIT III ENHANCEMENT TO SINGLE LOOP REGULATORY CONTROL & MODEL BASED CONTROL SCHEMES 9

Cascade control – Split-range - Feed-forward control – Ratio control – Inferential control — override control - Smith predictor control scheme - Internal Model Controller - IMC PID controller – Single Loop Dynamic Matrix Control – Generalized Predictive Control

UNIT IV MULTIVARIABLE SYSTEMS & MULTI-LOOP REGULATORY CONTROL 9

Multivariable Systems – Transfer Matrix Representation – Poles and Zeros of MIMO System - - Multi-loop Control - Introduction – Process Interaction – Pairing of Inputs and Outputs -The Relative Gain Array (RGA) – Properties and Application of RGA - Multi-loop PID Controller - Decoupling Control

UNIT V CASE –STUDIES 9

Introduction to Multivariable control – Multivariable PID Controller –Predictive PID Control - Control Schemes for Distillation Column, CSTR, Four-tank system and pH .

L:45 +T: 15 TOTAL: 60 PERIODS

REFERENCES

1 B.Wayne Bequette, “Process Control: Modeling, Design, and Simulation”, Prentice Hall of India, 2004.
2 George Stephanopolus, "Chemical Process Control", Prentice Hall India, 2006

3 Dale E. Seborg , Duncan A. Mellichamp , Thomas F. Edgar, and Francis J. Doyle, III "Process Dynamics and Control", John Wiley and Sons, 3rd Edition, 2010.
4 Jose A. Romagnoli and Ahmet Palazoglu , "Introduction to Process Control", CRC Press, Taylor and Francis Group, Second Edition, First Indian Reprint, 2010.
5 Coleman Brosilow and Babu Joseph, "Techniques of Model-based Control", Prentice Hall International Series, PTR, New Jersey, 2001.
6 Pertrezeulla, "Programmable Controllers", McGraw-Hill, 1989
7 Chidambarm. M, " Computer control of processes", Narosa Publications, 2002.

CO8202 INDUSTRIAL PROCESS AUTOMATION LT P C
3 1 0 4

PROGRAM OBJECTIVE

- To educate on design of signal conditioning circuits for various applications
- To educate on signal transmission techniques and their design
- Study of components used in data acquisition systems interface techniques
- To educate on the components used in distributed control systems
- To introduce the communication buses namely field bus and profibus.

UNIT I DESIGN OF SIGNAL CONDITIONING AND TRANSMISSION 9

Design of V/I Converter and I/V Converter- Analog and Digital filter design and Adaptive filter design – Signal conditioning circuit for pH measurement, Level Measurement – Temperature measurement: Thermocouple, RTD and Thermistor - Cold Junction Compensation and Linearization – software and Hardware approaches **-** Electrical, Pneumatic and fibre optic transmissions-Digital transmission protocols-Study of 2 wire and 4 wire transmitters – Design of RTD based Temperature Transmitter, Thermocouple based Temperature Transmitter, Capacitance based Level Transmitter and Smart Flow Transmitters-smart sensors

UNIT II DATA ACQUISITION AND INSTRUMENT INTERFACE 9

Programming and simulation of Building block of instrument Automation system – Signal analysis, I/O port configuration with instrument bus protocols - ADC, DAC, DIO, counters & timers, PC hardware structure, timing, interrupts, DMA, software and hardware installation, current loop, RS 232/RS485, GPIB, USB protocols,

UNIT III PLC AND SCADA 9

Evolution of PLC – Sequential and Programmable controllers – Architecture – Programming of PLC – Relay logic and Ladder logic – Functional blocks – Communication Networks for PLC. PLC based control of processes – Computer control of liquid level system – heat exchanger – Smart sensors and Field bus.
SCADA:- Remote terminal units, Master station, Communication architectures and Open SCADA protocols.

UNIT IV DISTRIBUTED CONTROL SYSTEM 9

Evolution - Different architectures - Local control unit - Operator Interface – Displays - Engineering interface - Study of any one DCS available in market - Factors to be considered in selecting DCS .

UNIT V COMMUNICATION PROTOCOLS 9

Introduction- Evolution of signal standard – HART communication protocol – Communication modes – HART Networks – HART commands –HART and OSI models- HART applications Fieldbus:- Introduction, General Fieldbus architecture, Basic requirements of Fieldbus standard, Fieldbus topology, Interoperability and Interchangeability Profibus:- Introduction, Profibus protocol stack, Profibus communication model, Communication objects, System operation and Troubleshooting – Foundation fieldbus versus Profibus.

L:45 +T: 15 TOTAL: 60 PERIODS

REFERENCES

1. Alan S Morris “Measurement and Instrumentation Principles”, Elsevier, 2006
2. C.J.Chesmond, P.A.Wilson & M.R.Le Pla “Advanced Control System Technology” ,
3. viva books Private Limited, 1998
4. Patrick H.Garrett “High Performance Instrumentation And Automation” CRC Press,
5. Taylor & Francis Group, 2005

CO8251 NON LINEAR CONTROL L T P C
3 0 2 4

PROGRAM OBJECTIVES

- To impart knowledge on phase plane analysis of non-linear systems.
- To impart knowledge on Describing function based approach to non-linear systems.
- To educate on stability analysis of systems using Lyapunov’s theory.
- To educate on stability analysis of systems using Lyapunov’s theory.
- To introduce the concept of sliding mode control.

UNIT I PHASE PLANE ANALYSIS 9

Concepts of phase plane analysis- Phase portraits- singular points- Symmetry in phase plane portraits-Constructing Phase Portraits- Phase plane Analysis of Linear and Nonlinear Systems- Existence of Limit Cycles. simulation of phase portraits in matlab

UNIT II DESCRIBING FUNCTION 9

Describing Function Fundamentals-Definitions-Assumptions-Computing Describing Functions-Common Nonlinearities and its Describing Functions-Nyquist Criterion and its Extension-Existence of Limit Cycles-Stability of limit Cycles. simulation of limit cycles in matlab

UNIT III LYAPUNOV THEORY 9

Nonlinear Systems and Equilibrium Points-Concepts of Stability-Linearization and Local Stability-Lyapunov's Direct Method-Positive definite Functions and Lyapunov Functions-Equilibrium Point Theorems-Invariant Set Theorems-LTI System Analysis based on Lyapunov's Direct Method-Krasovski's Method-Variable Gradient Method-Physically – Control Design based on Lyapunov's Direct Method.

UNIT IV FEEDBACK LINEARIZATION 9

Feedback Linearization and the Canonical Form-Mathematical Tools-Input-State Linearization of SISO Systems- input-Output Linearization of SISO Systems-Generating a Linear Input-Output Relation-Normal Forms-The Zero-Dynamics-Stabilization and Tracking-Inverse Dynamics and Non-Minimum-Phase Systems-Feedback Linearization of MIMO Systems Zero-Dynamics and Control Design. Simulation of tracking problems in matlab

UNIT V SLIDING MODE CONTROL 9

Sliding Surfaces- Continuous approximations of Switching Control laws-The Modeling/Performance Trade-Offs- MIMO Systems. simulation of sliding mode controller in matlab

L=45, P=30 TOTAL : 75 PERIODS

PRACTICALS

1. Development of state trajectories and phase portraits
2. Development of algorithms to construct Describing functions
3. Performance analysis of non-linear systems using Describing function approach
4. Simulation and performance evaluation using Input-Output Linearization
5. Simulation and performance evaluation using Feedback Linearization
6. Design and performance evaluation of sliding mode controllers.
7. Design of controllers for MIMO systems
8. Design of controllers for chemical process loops
9. Design of controllers for power converters
10. Design of controllers for electro-mechanical systems

REFERENCES

1. J A E Slotine and W Li, Applied Nonlinear control, PHI, 1991.
2. Hasan Khalil, "Nonlinear systems and control", Prentice Hall.
3. S H Zak, "Systems and control", Oxford University Press, 2003.
4. Torkel Glad and Lennart Ljung, "Control Theory – Multivariable and Nonlinear Methods", Taylor & Francis, 2002.
5. G. J. Thaler, "Automatic control systems", Jaico publishers, 1993.

CO8211 AUTOMATION LAB L T P C
0 0 3 2

1. Simulation and performance analysis of transfer function models using virtual Instrumentation packages
2. Simulation and performance analysis of state space models using virtual Instrumentation packages
3. Simulation of signal conditioning and processing circuits using circuit design packages.
4. Demonstration of discretisation blocks in the virtual instrumentation package
5. Configuration of analog and digital data acquisition systems
6. Development of GUI application for PID control
7. Development of GUI application to mimic closed loop performance of a physical system
8. Ladder logic programming using PLC simulator software packages
9. Simulation of process control loop using PLC with GUI
10. Simulation of SCADA based control of physical system
11. Development of PID and Lag-lead control algorithms for microcontroller application
12. Configuration of simulation of RS232 and SPI interface protocols
13. Configuration of simulation of instrumentation bus protocols
14. Simulation of state diagram based application using virtual instrumentation package
15. Design of complete automation system for a given application
16. Design of Feed Forward Controller for a given application

TOTAL : 45 PERIODS

CO8001 ADVANCED NON-LINEAR SYSTEMS L T P C
3 0 0 3

COURSE OBJECTIVES

- To educate on the theory of perturbation
- To educate on stability analysis and theory of singular perturbation
- To educate on gain scheduling and feedback linearization techniques
- To educate on the concepts input-output stability and passivity
- To educate on the theory and design of back stepping controllers

UNIT I PERTURBATION THEORY 9

Vanishing and Non vanishing Perturbations – Continuity of solutions on the infinite interval – Interconnected systems – Slowly varying systems – Perturbation method – Averaging - Weakly nonlinear second-order oscillators – Exercises

UNIT II SINGULAR PERTURBATIONS 9

Standard singular perturbation model – Time scale properties – Singular perturbation on the infinite interval – Slow and fast manifolds – stability analysis – exercises

UNIT III GAIN SCHEDULING AND FEEDBACK LINEARIZATION 9

Control problem – stabilization via linearization – integral control via linearization – gain scheduling – Input output linearization – Full state linearization – state feedback control – tracking- exercises

UNIT IV INPUT-OUTPUT STABILITY 9

L stability – L stability of state models – L_2 gain – feedback system: small gain theorem – exercises – Passivity – State models - L_2 and Lyapunov stability

UNIT V BAKSTEPPING CONTROL ALGORITHMS 9

Passivity based control – High gain observers – stabilization – Regulation via integral control - exercises

TOTAL : 45 PERIODS

REFERENCES

1. Hasan Khalil," Nonlinear systems and control", 3rd ed, PHI,
2. Slotine, J A E Slotine and W Li, "Applied Nonlinear control",1991, PHI
3. S.H. Zak," Systems and control", Oxford University Press

CO8002 CONTROL OF ELECTRICAL DRIVES L T P C

3 0 0 3

COURSE OBJECTIVES

- To introduce the PWM converters and their analysis
- To educate on modeling of dc motor, drives and control techniques
- To educate on dynamic modeling of Induction motor drive
- To educate on the V/f and vector control of Induction motor
- To educate on generation of firing pulses and control algorithms in embedded platforms

UNIT I POWER ELECTRONIC CONVERTERS FOR DRIVES 9

Power electronic switches-state space representation of switching converters-Fixed frequency PWM-variable frequency PWM- space vector PWM- Hysteresis current control-dynamic analysis of switching converters-PWM modulator model

UNIT II CONTROL OF DC DRIVES 9

Modelling of DC machines-block diagram/transfer function-phase control-1phase/3phase converter fed DC drives- Chopper fed DC drives-four quadrant chopper circuit-closed loop control-speed control-current control-cascade control –constant torque/power operation-comparison of chopper/converter fed drives- techniques-merits/demits

UNIT III ANALYSIS AND MODELLING OF INDUCTION MOTOR DRIVE 9

Basics of induction motor drive-classification – equivalent circuit- torque Vs slip characteristics-steady state performance- Dynamic modeling of induction motor, Three

phase to two phase transformation-stator, rotor, synchronously rotating reference frame model

UNIT IV CONTROL OF INDUCTION MOTOR DRIVE 9

VSI fed induction motor drives- waveforms for 1-phase, 3-phase Non-PWM and PWM VSI fed induction motor drives -principles of V/F control- principle of vector control-direct vector control- space vector modulation- indirect vector control .

UNIT V EMBEDDED CONTROL OF DRIVES 9

Generation of firing pulses- generation of PWM pulses using embedded processors-IC control of DC drives- fixed frequency/variable frequency/current control- V/F control using PIC microcontroller- vector control using embedded processors

TOTAL : 45 PERIODS

REFERENCES

1. R.Krishnan, "Electric Motor Drives, Modeling, Analysis and Control" Prentice Hall of India, 2002.
2. Thyristor control of Electric drives, Vedam Subrahmanyam, Tata McGraw Hill, 1988
3. Ion Boldea & S.A.Nasar "ELECTRIC DRIVES", CRC Press, 2006
4. Simon Ang, Alejandro Oliva "POWER SWITCHING CONVERTERS", CRC Press, 2005
5. Buxbaum, A. Schierau, and K.Staughen, "A design of control systems for DC Drives", Springer- Verlag, Berlin,1990.

CO8003 MULTI SENSOR DATA FUSION L T P C
3 0 0 3

COURSE OBJECTIVES

- To educate on sensor data inference hierarchy and fusion models
- To educate on the algorithms used for data fusion
- To educate on Kalman filter and its application to decision identity fusion
- To educate on advanced filtering and sensor fusion concepts
- To introduce various high performance data structures

UNIT I MULTISENSOR DATA FUSION INTRODUCTION 9

sensors and sensor data, Use of multiple sensors, Fusion applications. The inference hierarchy: output data. Data fusion model. Architectural concepts and issues. Benefits of data fusion, Mathematical tools used:Algorithms, co-ordinate transformations, rigid body motion. Dependability and Markov chains, Meta – heuristics.

UNIT II ALGORITHMS FOR DATA FUSION 9

Taxonomy of algorithms for multisensor data fusion. Data association. Identity declaration.

UNIT III ESTIMATION: 9

Kalman filtering, practical aspects of Kalman filtering, extended Kalmal filters. Decision level identify fusion. Knowledge based approaches.

UNIT IV ADVANCED FILTERING 9

Data information filter, extended information filter. Decentralized and scalable decentralized estimation. Sensor fusion and approximate agreement. Optimal sensor fusion using range trees recursively. Distributed dynamic sensor fusion.

UNIT V HIGH PERFORMANCE DATA STRUCTURES: 9

Tessellated, trees, graphs and function. Representing ranges and uncertainty in data structures. Designing optimal sensor systems with in dependability bounds. Implementing data fusion system.

TOTAL : 45 PERIODS

REFERENCES:

1. David L. Hall, Mathematical techniques in Multisensor data fusion, Artech House, Boston, 1992.
2. R.R. Brooks and S.S. Iyengar, Multisensor Fusion: Fundamentals and Applications with Software, Prentice Hall Inc., New Jersey, 1998.
3. Arthur Gelb, Applied Optimal Estimation, The M.I.T. Press, 1982.
4. James V. Candy, Signal Processing: The Model Based Approach, McGraw –Hill Book Company, 1987.

CO8004 OPTIMAL CONTROL AND FILTERING L T P C
3 0 0 3

COURSE OBJECTIVES

- To educate on formulation of optimal control problems and introduce the minimum principle
- To educate on Linear Quadratic tracking problems- in continuous and discrete domain
- To introduce the numerical techniques used for solving optimal control problems
- To educate on the concepts of filtering in the presence of noise
- To educate on the theory and design of Kalman filter

UNIT I INTRODUCTION 9

Statement of optimal control problem – Problem formulation and forms of optimal Control – Selection of performance measures. Necessary conditions for optimal control – Pontryagin's minimum principle – State inequality constraints – Minimum time problem.

UNIT II LINEAR QUADRATIC TRACKING PROBLEMS 9

Linear tracking problem – LQG problem – Computational procedure for solving optimal control problems – Characteristics of dynamic programming solution – Dynamic

programming application to discrete and continuous systems – Hamilton Jacobi Bellman equation.

UNIT III NUMERICAL TECHNIQUES FOR OPTIMAL CONTROL 9

Numerical solution of 2-point boundary value problem by steepest descent and Fletcher Powell method solution of Ricatti equation by negative exponential and interactive Methods

UNIT IV FILTERING AND ESTIMATION 9

Filtering – Linear system and estimation – System noise smoothing and prediction – Gauss Markov discrete time model – Estimation criteria – Minimum variance estimation – Least square estimation – Recursive estimation.

UNIT V KALMAN FILTER AND PROPERTIES 9

Filter problem and properties – Linear estimator property of Kalman Filter – Time invariance and asymptotic stability of filters – Time filtered estimates and signal to noise ratio improvement – Extended Kalman filter.

TOTAL : 45 PERIODS

REFERENCES:

1. KiRk D.E., 'Optimal Control Theory – An introduction', Prentice hall, N.J., 1970.
2. Sage, A.P., 'Optimum System Control', Prentice Hall N.H., 1968.
3. Anderson, BD.O. and Moore J.B., 'Optimal Filtering', Prentice hall Inc., N.J., 1979.
4. S.M. Bozic, "Digital and Kalman Filtering", Edward Arnould, London, 1979.
5. Astrom, K.J., "Introduction to Stochastic Control Theory", Academic Press, Inc, N.Y., 1970.

CO8071 ROBOTICS AND CONTROL L T P C
3 0 0 3

COURSE OBJECTIVES

- To introduce robot terminologies and robotic sensors
- To educate direct and inverse kinematic relations
- To educate on formulation of manipulator Jacobians and introduce path planning techniques
- To educate on robot dynamics
- To introduce robot control techniques

UNIT I INTRODUCTION AND TERMINOLOGIES 9

Definition-Classification-History- Robots components-Degrees of freedom-Robot joints-coordinates- Reference frames-workspace-Robot languages-actuators-sensors-Position, velocity and acceleration sensors-Torque sensors-tactile and touch sensors-proximity and range sensors- vision system-social issues

UNIT II KINEMATICS **9**

Mechanism-matrix representation-homogenous transformation-DH representation-Inverse kinematics-solution and programming-degeneracy and dexterity

UNIT III DIFFERENTIAL MOTION AND PATH PLANNING **9**

Jacobian-differential motion of frames-Interpretation-calculation of Jacobian-Inverse Jacobian- Robot Path planning

UNIT IV DYNAMIC MODELLING **9**

Lagrangian mechanics- Two-DOF manipulator- Lagrange-Euler formulation – Newton-Euler formulation – Inverse dynamics

UNIT V ROBOT CONTROL SYSTEM **9**

- Linear control schemes- joint actuators- decentralized PID control- computed torque control – force control- hybrid position force control- Impedance/ Torque control

TOTAL : 45 PERIODS

REFERENCES

1. R.K. Mittal and I J Nagrath, " Robotics and Control", Tata MacGraw Hill, Fourth
2. Saeed B. Niku ,"Introduction to Robotics ", Pearson Education, 2002
3. Fu, Gonzalez and Lee Mcgrahill ,"Robotics ", international
4. R.D. Klafter, TA Chmielewski and Michael Negin, "Robotic Engineering, An Integrated approach", Prentice Hall of India, 2003.

CO8072 **ROBUST CONTROL** **L T P C**
3 0 0 3

COURSE OBJECTIVES

- To introduce norms, random spaces and robustness measures
- To educate on H2 optimal control and estimation techniques
- To educate on Hinfinity optimal control techniques
- To educate on the LMI approach of Hinfinity control
- To educate on synthesis techniques for robust controllers and illustrate through case studies

UNIT I INTRODUCTION **9**

Norms of vectors and Matrices – Norms of Systems – Calculation of operator Norms – vector Random spaces- Specification for feedback systems – Co-prime factorization and Inner functions –structured and unstructured uncertainty- robustness

UNIT II H_2 OPTIMAL CONTROL **9**

Linear Quadratic Controllers – Characterization of H_2 optimal controllers – H2 optimal

estimation-Kalman Bucy Filter – LQG Controller

UNIT III H-INFINITY OPTIMAL CONTROL-RICCATI APPROACH 9

Formulation – Characterization of H-infinity sub-optimal controllers by means of Riccati equations – H-infinity control with full information – Hinfinity estimation

UNIT IV H-INFINITY OPTIMAL CONTROL- LMI APPROACH 9

Formulation – Characterization of H-infinity sub-optimal controllers by means of LMI Approach – Properties of H-infinity sub-optimal controllers – H-infinity synthesis with pole-placement constraints

UNIT V SYNTHESIS OF ROBUST CONTROLLERS & CASE STUDIES 9

Synthesis of Robust Controllers – Small Gain Theorem – D-K –iteration- Control of Inverted Pendulum- Control of CSTR – Control of Aircraft – Robust Control of Second-order Plant-Robust Control of Distillation Column

TOTAL : 45 PERIODS

REFERENCES

1. U. Mackenroth “Robust Control Systems: Theory and Case Studies”,Springer International Edition, 2010.
2. J. B. Burl, “ Linear optimal control H2 and H-infinity methods”, Addison W Wesley, 1998
3. D. Xue, Y.Q. Chen, D. P. Atherton, "Linear Feedback Control Analysis and Design with MATLAB, Advances In Design and Control”, Society for Industrial and Applied Mathematics, 2007.
4. I.R. Petersen, V.A. Ugrinovskii and A. V. Savkin, “Robust Control Design using H-infinity Methods”, Springer, 2000.
5. M. J. Grimble, “Robust Industrial Control Systems: Optimal Design Approach for Polynomial Systems”, John Wiley and Sons Ltd., Publication, 2006.

CO8073 SYSTEM IDENTIFICATION AND ADAPTIVE CONTROL L T P C
3 0 0 3

COURSE OBJECTIVES

- To introduce various model structures for system identification
- To impart knowledge on parametric and non-parametric identification
- To introduce non-linear identification techniques
- To introduce the concept of adaptation techniques and control
- To illustrate the identification and adaptive control techniques through case studies

UNIT I MODELS FOR INDENTIFICATION 9

Models of LTI systems: Linear Models-State space Models-OE model- Model sets, Structures and Identifiability-Models for Time-varying and Non-linear systems: Models with Nonlinearities – Non-linear state-space models-Black box models, Fuzzy models’.

UNIT II NON-PARAMETRIC AND PARAMETRIC IDENTIFICATON 9

Transient response and Correlation Analysis – Frequency response analysis – Spectral Analysis – Least Square – Recursive Least Square –Forgetting factor- Maximum Likelihood – Instrumental Variable methods.

UNIT III NON-LINEAR IDENTIFICATION 9

Open and closed loop identification: Approaches – Direct and indirect identification – Joint input-output identification – Non-linear system identification – Wiener models – Power series expansions - State estimation techniques – Non linear identification using Neural Network and Fuzzy Logic.

UNIT IV ADAPTIVE COTROL AND ADAPTATION TECHNIQUES 9

Introduction – Uses – Auto tuning – Self Tuning Regulators (STR) – Model Reference Adaptive Control (MRAC) – Types of STR and MRAC – Different approaches to self-tuning regulators – Stochastic Adaptive control – Gain Scheduling.

UNIT V CASE STUDIES 9

Inverted Pendulum, Robot arm, process control application: heat exchanger, Distillation column, application to power system, Ship steering control.

TOTAL : 45 PERIODS

REFERENCES

1. Ljung," System Identification Theory for the User", PHI, 1987.
2. Torsten Soderstrom, Petre Stoica, "System Identification", prentice Hall `International (UK) Ltd,1989.
3. Astrom and Wittenmark," Adaptive Control ", PHI
4. William S. Levine, " Control Hand Book".
5. Narendra and Annasamy," Stable Adaptive Control Systems, Prentice Hall, 1989.

CO8074 SYSTEM THEORY L T P C

3 0 0 3

COURSE OBJECTIVES

- To educate on modeling and representing systems in state variable form
- To educate on solving linear and non-linear state equations
- To illustrate the role of controllability and observability
- To educate on stability analysis of systems usig Lyapunov's theory
- To educate on modal concepts and design of state and output feedback controllers and estimators

UNIT I STATE VARIABLE REPRESENTATION 9

Introduction-Concept of State-State equation for Dynamic Systems -Time invariance and linearity- Non uniqueness of state model-State Diagrams - Physical System and State Assignment.

UNIT II SOLUTION OF STATE EQUATIONS 9

Existence and uniqueness of solutions to Continuous-time state equations-Solution of Nonlinear and Linear Time Varying State equations-Evaluation of matrix exponential-System modes- Role of Eigenvalues and Eigenvectors.

UNIT III CONTROLLABILITY AND OBSERVABILITY 9

Controllability and Observability-Stabilizability and Detectability-Test for Continuous time Systems- Time varying and Time invariant case-Output Controllability-Reducibility-System Realizations.

UNIT IV STABILTY 9

Introduction-Equilibrium Points-Stability in the sense of Lyapunov-BIBO Stability-Stability of LTI Systems-Equilibrium Stability of Nonlinear Continuous Time Autonomous Systems-The Direct Method of Lyapunov and the Linear Continuous-Time Autonomous Systems-Finding Lyapunov Functions for Nonlinear Continuous Time Autonomous Systems-Krasovskii and Variable-Gradiant Method.

UNIT V MODAL CONTROL 9

Introduction-Controllable and Observable Companion Forms-SISO and MIMO Systems-The Effect of State Feedback on Controllability and Observability-Pole Placement by State Feedback for both SISO and MIMO Systems-Full Order and Reduced Order Observers.

TOTAL : 45 PERIODS

REFERENCES:

1. M. Gopal, “Modern Control System Theory”, New Age International, 2005.
2. K. Ogatta, “Modern Control Engineering”, PHI, 2002.
3. John S. Bay, “Fundamentals of Linear State Space Systems”, McGraw-Hill, 1999.
4. D. Roy Choudhury, “Modern Control Systems”, New Age International, 2005.
5. John J. D’Azzo, C. H. Houpis and S. N. Sheldon, “Linear Control System Analysis and Design with MATLAB”, Taylor Francis, 2003.
6. Z. Bubnicki, ”Modern Control Theory”, Springer, 2005.

PW8203 SCADA SYSTEM AND APPLICATIONS MANAGEMENT L T P C
3 0 0 3

UNIT I INTRODUCTION TO SCADA 9

Evolution of SCADA, SCADA definitions, SCADA Functional requirements and Components, SCADA Hierarchical concept, SCADA architecture, General features, SCADA Applications, Benefits

UNIT II SCADA SYSTEM COMPONENTS 9

Remote Terminal Unit (RTU), Interface units, Human- Machine Interface Units (HMI), Display Monitors/Data Logger Systems, Intelligent Electronic Devices (IED), Communication Network, SCADA Server, SCADA Control systems and Control panels

UNIT III SCADA COMMUNICATION 9

SCADA Communication requirements, Communication protocols: Past, Present and Future, Structure of a SCADA Communications Protocol, Comparison of various communication protocols, IEC61850 based communication architecture, Communication media like Fiber optic, PLCC etc. Interface provisions and communication extensions, synchronization with NCC, DCC.

UNIT IV SCADA MONITORING AND CONTROL 9

Online monitoring the event and alarm system, trends and reports, Blocking list, Event disturbance recording. Control function: Station control, bay control, breaker control and disconnector control.

UNIT V SCADA APPLICATIONS IN POWER SYSTEM 9

Applications in Generation, Transmission and Distribution sector, Substation SCADA system Functional description, System specification, System selection such as Substation configuration, IEC61850 ring configuration, SAS cubicle concepts, gateway interoperability list, signal naming concept. System Installation, Testing and Commissioning.

CASE STUDIES: SCADA Design for 66/11KV and 132/66/11KV or 132/66 KV any utility Substation and IEC 61850 based SCADA Implementation issues in utility Substations,

TOTAL: 45 PERIODS

REFERENCES:

1. Stuart A. Boyer: SCADA-Supervisory Control and Data Acquisition, Instrument Society of America Publications,USA,2004
2. Gordon Clarke, Deon Reynders: Practical Modern SCADA Protocols: DNP3, 60870.5 and Related Systems, Newnes Publications, Oxford, UK,2004
3. William T. Shaw, Cybersecurity for SCADA systems, PennWell Books, 2006
4. David Bailey, Edwin Wright, Practical SCADA for industry, Newnes, 2003
5. Michael Wiebe, A guide to utility automation: AMR, SCADA, and IT systems for electric Power, PennWell 1999
6. Dieter K. Hammer, Lonnie R. Welch, Dieter K. Hammer, “Engineering of Distributed Control Systems”, Nova Science Publishers, USA, 1st Edition, 2001.

ET8071 ADVANCED DIGITAL SIGNAL PROCESSING L T P C
3 0 0 3

Pre-requisites: Basics of Signal Processing, Mathematics of Transforms, Microcontroller

COURSE OBJECTIVES

- To expose the students to the fundamentals of digital signal processing in frequency domain& its application
- To teach the fundamentals of digital signal processing in time-frequency domain& its application
- To compare Architectures & features of Programmable DSprocessors
- To discuss on Application development with commercial family of DS Processors
- To design & develop logical functions of DSProcessors with Re-Programmable logics &Devices

UNIT I INTRODUCTION TO DIGITAL SIGNAL PROCESSING 12

Introduction, A Digital Signal-Processing System, The Sampling Process, Discrete Time Sequences, Discrete Fourier Transform (DFT) and Fast Fourier Transform (FFT), Linear Time-Invariant Systems, Decimation and Interpolation, Digital Filters, FIR Filters, IIR Filters.

UNIT II WAVELET TRANSFORM 6

introduction to continuous wavelet transform- discrete wavelet transform -orthogonal wavelet decomposition- Multiresolution Analysis-Wavelet function-DWT,bases,orthogonal Basis-Scaling function, Wavelet coefficients- ortho normal wavelets and their relationship to filter banks- Digital filtering interpolation (i) Decomposition filters, (ii) reconstruction, the signal- Example MRA- Haar & Daubechies wavelet.

UNIT III ARCHITECTURES OF COMMERCIAL DIGITAL SIGNAL PROCESSORS 12

Introduction, catogorisation of DSP Processors, Fixed Point (Blackfin),Floating Point (SHARC),TI TMS 320c6xxx & OMAP processors TMS320C54X & 54xx on Basic Architecture – comparison : of functional variations of Computational building blocks, MAC, Bus Architecture and memory, Data Addressing, Parallelism and pipelining, Parallel I/O interface,Memory Interface, Interrupt, DMA (one example Architecture in each of these case studies).

UNIT IV INTERFACING I/O PERIPHERALS FOR DSP BASED APPLICATIONS 6

Introduction, External Bus Interfacing Signals, Memory Interface, Parallel I/O Interface, Programmed I/O, Interrupts and I / O Direct Memory Access (DMA).**-**Introduction, Design of Decimation and Interpolation Filter, FFT Algorithm, PID Controller ,Application for Serial Interfacing, DSP based Power Meter, Position control , CODEC Interface .

UNIT V VLSI IMPLEMENTATION **9**

Low power Design-need for Low power VLSI chips-Basics of DSP system architecture design using VHDL programming, Mapping of DSP algorithm onto hardware, Realisation of MAC & Filter structure.

TOTAL:45 PERIODS

REFERENCES:

1. John G. Proaks, Dimitris G. Manolakis, "Digital Signal Processing", Pearson Education 2002.
2. Avatar Sing, S. Srinivasan, "Digital Signal Processing- Implementation using DSP Microprocessors with Examples from TMS320C54xx", Thomson India,2004.
3. Lars Wanhammer, "DSP Integrated Circuits", Academic press, 1999,NewYork.
4. Lyla B Das," Embedded Systems-An Integrated Approach",Pearson2013
5. Ashok Ambardar,"Digital Signal Processing: A Modern Introduction",Thomson India edition, 2007.
6. Raghuveer M.Rao and Ajit S. Bapardikar, Wavelet transforms- Introduction to theory and applications, Pearson Education, 2000.
7. K.P. Soman and K.L. Ramchandran,Insight into WAVELETS from theory to practice,
   Eastern Economy Edition, 2008
8. Ifeachor E. C., Jervis B. W ,"Digital Signal Processing: A practical approach, Pearson-Education, PHI/ 2002
9. B Venkataramani and M Bhaskar **"**Digital Signal Processors**"**, TMH, 2nd, 2010
10. Peter Pirsch **"**Architectures for Digital Signal Processing", John Weily, 2007
11. Vinay K.Ingle,John G.Proakis,"DSP-A Matlab Based Approach",Cengage Learning,2010
12. Taan S.Elali,"Discrete Systems and Digital Signal Processing with Matlab",CRC Press2009.

ET8072 **MEMS TECHNOLOGY** **L T P C**
3 0 0 3

Pre-requisites: Basic Instrumentation ,Material Science,Programming

COURSE OBJECTIVES

- To teach the students properties of materials ,microstructure and fabrication methods.
- To teach the design and modeling of Electrostatic sensors and actuators.
- To teach the characterizing thermal sensors and actuators through design and modeling
- To teach the fundamentals of piezoelectric sensors and actuators
- To give exposure to different MEMS and NEMS devices.

UNIT I MEMS:MICRO-FABRICATION, MATERIALS AND ELECTRO-MECHANICAL CONEEPTS 9

Overview of micro fabrication – Silicon and other material based fabrication processes – Concepts: Conductivity of semiconductors-Crystal planes and orientation-stress and strain-flexural beam bending analysis-torsional deflections-Intrinsic stress- resonant frequency and quality factor.

UNIT II ELECTROSTATIC SENSORS AND ACTUATION 9

Principle, material, design and fabrication of parallel plate capacitors as electrostatic sensors and actuators-Applications

UNIT III THERMAL SENSING AND ACTUATION 9

Principle, material, design and fabrication of thermal couples, thermal bimorph sensors, thermal resistor sensors-Applications.

UNIT IV PIEZOELECTRIC SENSING AND ACTUATION 9

Piezoelectric effect-cantilever piezo electric actuator model-properties of piezoelectric materials-Applications.

UNIT V CASE STUDIES 9

Piezoresistive sensors, Magnetic actuation, Micro fluidics applications, Medical applications, Optical MEMS.-NEMS

TOTAL : 45 PERIODS

REFERENCES

1. Chang Liu, “Foundations of MEMS”, Pearson International Edition, 2006.
2. Marc Madou , “Fundamentals of microfabrication”,CRC Press, 1997.
3. Boston , “Micromachined Transducers Sourcebook”,WCB McGraw Hill, 1998.
4. M.H.Bao “Micromechanical transducers :Pressure sensors, accelerometers and gyroscopes”, Elsevier, Newyork, 2000.

ET8151 ADVANCED DIGITAL PRINCIPLES AND DESIGN LT P C 3 1 0 4

Pre-requisites: Digital logic Devices, Circuits, Boolean Algebra

OBJECTIVES

- To expose the students to the fundamentals of sequential system design, modelling
- To teach the fundamentals of Asynchronous circuits, switching errors
- To study on Fault identification in digital switching circuits
- To introduce logics for design of Programmable Devices
- To comparatively study the classification of commercial family of Programmable Devices

UNIT I SEQUENTIAL CIRCUIT DESIGN 9

Analysis of Clocked Synchronous Sequential Networks (CSSN) Modelling of CSSN – State Stable Assignment and Reduction – Design of CSSN – Design of Iterative Circuits – ASM Chart – ASM Realization.

UNIT II ASYNCHRONOUS SEQUENTIAL CIRCUIT DESIGN 9

Analysis of Asynchronous Sequential Circuit (ASC) – Flow Table Reduction – Races in ASC – State Assignment Problem and the Transition Table – Design of ASC – Static and Dynamic Hazards – Essential Hazards – Data Synchronizers – Designing Vending Machine Controller – Mixed Operating Mode Asynchronous Circuits.

UNIT III FAULT DIAGNOSIS AND TESTABILITY ALGORITHMS 9

Fault Table Method – Path Sensitization Method – Boolean Difference Method – Kohavi Algorithm – Tolerance Techniques – The Compact Algorithm – Practical PLA's – Fault in PLA – Test Generation – Masking Cycle – DFT Schemes – Built-in Self Test.

UNIT IV SYNCHRONOUS DESIGN USING PROGRAMMABLE DEVICES 9

Programming Techniques -Re-Programmable Devices Architecture- Function blocks, I/Oblocks, Interconnects, Realize combinational, Arithmetic, Sequential Circuit with Programmable Array Logic; Architecture and application of Field Programmable Logic Sequence.

UNIT V ARCHITECTURES AND PROGRAMMING PROGRAMMABLE LOGIC DEVICES 9

Architecture with EPLD, PEEL – Realization State machine using PLD – FPGA-Aptix Field Programmable Interconnect – Xilinx FPGA – Xilinx 2000 - Xilinx 4000 family.VHDL based Designing with PLD-ROM,PAL,PLA,Sequential PLDs,Case study –Keypad Scanner

LOGIC SYNTHESIS AND SIMULATION Overview of digital design with VHDL, hierarchical modelling concepts, modules and port definitions, gate level modelling, data flow modelling, behavioural modelling, task & functions, logic synthesis-simulation-Design examples,Ripple carry Adders, Carry Look ahead adders, Design of Arithmetic circuits for Fast adder, Array Multiplier, ALU, Shift Registers, Multiplexer,Comparator/other examples on Test Bench.

L:45 +T: 15 TOTAL: 60 PERIODS

REFERENCES:

1. Donald G. Givone, "Digital principles and Design", Tata McGraw Hill 2002.
2. Stephen Brown and Zvonk Vranesic, "Fundamentals of Digital Logic with VHDL Deisgn", Tata McGraw Hill, 2002
3. Charles H. Roth Jr., "Digital Systems design using VHDL", Cengage Learning, 2010.
4. Mark Zwolinski, "Digital System Design with VHDL", Pearson Education, 2004
5. Parag K Lala, "Digital System design using PLD", BS Publications, 2003
6. John M Yarbrough, "Digital Logic applications and Design", Thomson Learning,2001
7. Nripendra N Biswas, "Logic Design Theory", Prentice Hall of India, 2001
8. Charles H. Roth Jr., "Fundamentals of Logic design", Thomson Learning, 2004.
9. John V.Oldfeild,Richard C.Dorf,"Field Programmable Gate Arrays",Wiley India Edition,2008

ET8152 MICROCONTROLLER BASED SYSTEM DESIGN LT P C
3 0 0 3

Pre-requisites: Basics of Processor Architecture & Programming in 8085/8051

COURSE OBJECTIVES

- To expose the students to the fundamentals of microcontroller based system design.
- To teach I/O and RTOS role on microcontroller.
- To impart knowledge on
- PIC Microcontroller based system design.
- To introduce Microchip PIC 8 bit peripheral system Design
- To give case study experiences for microcontroller based applications.

UNIT I 8051 ARCHITECTURE 9

Architecture – memory organization – addressing modes – instruction set – Timers - Interrupts - I/O ports, Interfacing I/O Devices – Serial Communication.

UNIT II 8051 PROGRAMMING 9

Assembly language programming – Arithmetic Instructions – Logical Instructions –Single bit Instructions – Timer Counter Programming – Serial Communication Programming Interrupt Programming – RTOS for 8051 – RTOSLite – FullRTOS – Task creation and run – LCD digital clock/thermometer using FullRTOS

UNIT III PIC MICROCONTROLLER 9

Architecture – memory organization – addressing modes – instruction set – PIC progrmming in Assembly & C –I/O port, Data Conversion, RAM & ROM Allocation, Timer programming, MP-LAB.

UNIT IV PERIPHERAL OF PIC MICROCONTROLLER 9

Timers – Interrupts, I/O ports- I2C bus-A/D converter-UART- CCP modules -ADC, DAC and Sensor Interfacing –Flash and EEPROM memories.

UNIT V SYSTEM DESIGN – CASE STUDY 9

Interfacing LCD Display – Keypad Interfacing - Generation of Gate signals for converters and Inverters - Motor Control – Controlling DC/ AC appliances – Measurement of frequency - Stand alone Data Acquisition System.

TOTAL : 45 PERIODS

REFERENCES:

1. Muhammad Ali Mazidi, Rolin D. Mckinlay, Danny Causey ' PIC Microcontroller And Embedded Systems using Assembly and C for PIC18', Pearson Education 2008
2. John Iovine, 'PIC Microcontroller Project Book ', McGraw Hill 2000
3. Myke Predko, "Programming and customizing the 8051 microcontroller", Tata McGraw Hill 2001.
4. Muhammad Ali Mazidi, Janice G. Mazidi and Rolin D. McKinlay, 'The 8051 Microcontroller and Embedded Systems' Prentice Hall, 2005.

ET8251 REAL TIME OPERATING SYSTEM LT P C
3 0 0 3

Pre-requisites: Processor architecture, operating systems.

OBJECTIVES

- To expose the students to the fundamentals of interaction of OS with a computer and User computation.
- To teach the fundamental concepts of how process are created and controlled with OS.
- To study on programming logic of modeling Process based on range of OS features
- To compare types and Functionalities in commercial OS
- To discuss the application development using RTOS

UNIT I REVIEW OF OPERATING SYSTEMS 15

Basic Principles - Operating System structures – System Calls – Files – Processes – Design and Implementation of processes – Communication between processes – Introduction to Distributed operating system – issues in distributed system:states,events,clocks-Distributed scheduling-Fault &recovery.

UNIT II OVERVIEW OF RTOS 9

RTOS Task and Task state –Multithreaded Premptive scheduler- Process Synchronisation- Message queues– Mail boxes -pipes – Critical section – Semaphores – Classical synchronisation problem – Deadlocks

UNIT III REAL TIME MODELS AND LANGUAGES 6

Event Based – Process Based and Graph based Models – Real Time Languages – RTOS Tasks – RT scheduling - Interrupt processing – Synchronization – Control Blocks – Memory Requirements.

UNIT IV REAL TIME KERNEL 6

Principles – Design issues – Polled Loop Systems – RTOS Porting to a Target – Comparison and Basic study of various RTOS like – VX works – Linux supportive RTOS – C Executive.

UNIT V RTOS APPLICATION DOMAINS 9

Case studies-RTOS for Image Processing – Embedded RTOS for Network communication – RTOS for fault-Tolerant Applications – RTOS for Control Systems.

TOTAL:45 PERIODS

REFERENCES:

1. Silberschatz,Galvin,Gagne" Operating System Concepts,6th ed,John Wiley,2003
2. D.M.Dhamdhere," Operating Systems,A Concept-Based Approch,TMH,2008
3. Raj Kamal, "Embedded Systems- Architecture, Programming and Design" Tata McGraw Hill, 2006.
4. Herma K., "Real Time Systems – Design for distributed Embedded Applications", Kluwer Academic, 1997.
5. Charles Crowley, "Operating Systems-A Design Oriented approach" McGraw Hill 1997.

6. C.M. Krishna, Kang, G.Shin, “Real Time Systems”, McGraw Hill, 1997.
7. Raymond J.A.Bhur, Donald L.Bailey, “An Introduction to Real Time Systems”, PHI 1999.
8. Mukesh Sighal and N G Shi “Advanced Concepts in Operating System”, McGraw Hill 2000.

ET8252 SOFTWARE FOR EMBEDDED SYSTEMS L T P C
3 1 0 4

Pre-requisites: Basics in Programming, Embedded System & operating systems

COURSE OBJECTIVES

- To expose the students to the fundamentals of embedded Programming.
- To Introduce the GNU C Programming Tool Chain in Linux.
- To study the basic concepts of embedded C and Embedded OS
- To introduce time driven architecture, Serial Interface with a case study.
- To introduce the concept of embedded Java for Web Enabling of systems.

UNIT I EMBEDDED PROGRAMMING 9

C and Assembly - Programming Style - Declarations and Expressions - Arrays, Qualifiers and Reading Numbers - Decision and Control Statements - Programming Process - More Control Statements - Variable Scope and Functions - C Preprocessor - Advanced Types - Simple Pointers - Debugging and Optimization – In-line Assembly.

UNIT II C PROGRAMMING TOOLCHAIN IN LINUX 12

C preprocessor - Stages of Compilation - Introduction to GCC - Debugging with GDB - The Make utility - GNU Configure and Build System - GNU Binary utilities - Profiling - using *gprof* - Memory Leak Detection with *valgrind* - Introduction to GNU C Library

UNIT III EMBEDDED C AND EMBEDDED OS 9

Adding Structure to ‘C’ Code: Object oriented programming with C, Header files for Project and Port, Examples. Meeting Real-time constraints: Creating hardware delays - Need for timeout mechanism - Creating loop timeouts - Creating hardware timeouts. Creating embedded operating system: Basis of a simple embedded OS, Introduction to sEOS, Using Timer 0 and Timer 1, Portability issue, Alternative system architecture, Important design considerations when using sEOS.

UNIT IV TIME-DRIVEN MULTI-STATE ARCHITECTURE AND HARDWARE 9

Multi-State systems and function sequences: Implementing multi-state (Timed) system - Implementing a Multi-state (Input/Timed) system. Using the Serial Interface: RS232 - The Basic RS-232 Protocol - Asynchronous data transmission and baud rates - Flow control - Software architecture - Using on-chip UART for RS-232 communication - Memory requirements - The serial menu architecture - Examples. Case study: Intruder alarm system.

UNIT V EMBEDDED JAVA **9**

Introduction to Embedded Java and J2ME – Smart Card basics – Java card technology overview – Java card objects – Java card applets – working with APDUs – Web Technology for Embedded Systems.

TUTORIAL: **12**

Program Development and practice in C, C++ and Java

TOTAL : 60 PERIODS

REFERENCES

1. Steve Oualline, 'Practical C Programming 3rd Edition', O'Reilly Media, Inc, 2006.
2. Stephen Kochan, "Programming in C", 3rd Edition, Sams Publishing, 2009.
3. Michael J Pont, "Embedded C", Pearson Education, 2007.
4. Zhiqun Chen, 'Java Card Technology for Smart Cards: Architecture and Programmer's Guide', Addison-Wesley Professional, 2000.

ET8253 VLSI BASED DESIGN METHODOLOGIES **L T PC**
3 1 0 4

Pre-requisites: Logic design, programmable devices**,** programming

OBJECTIVES

- To give an insight to the students about the significance of CMOS technology and fabrication process.
- To teach the importance and architectural features of programmable logic devices.
- To introduce the ASIC construction and design algorithms
- To teach the basic analog VLSI design techniques.
- To study the Logic synthesis and simulation of digital system with Verilog HDL.

UNIT I CMOS DESIGN **9**

Overview of l VLSI design Methodologies- Logic design with CMOS-transmission gate circuits-Clocked CMOS-dynamic CMOS circuits, Bi-CMOS circuits- Layout diagram, Stick diagram-IC fabrications – Low Power VLSI techniques-Trends in IC technology.

UNIT II PROGRAMABLE LOGIC DEVICES **12**

Programming Techniques-Anti fuse-SRAM-EPROM and EEPROM technology –Re-Programmable Devices Architecture- Logical blocks, I/O blocks, Interconnects, Xilinx-XC9500,Cool Runner -XC5200, SPARTAN, Virtex - Altera MAX 7000-Flex 10K-Cyclone,Stratix.

UNIT III BASIC CONSTRUCTION, FLOOR PLANNING, PLACEMENT AND ROUTING 6

System partition – FPGA partitioning – Partitioning methods- floor planning – placement-physical design flow – global routing – detailed routing – special routing- circuit extraction – DRC.

UNIY IV ANALOG VLSI DESIGN 6

Introduction to analog VLSI- Design of CMOS 2stage-3 stage Op-Amp –High Speed and High frequency op-amps-Super MOS- Analog primitive cells-realization of neural networks- Introduction to FPAA.

UNIT V LOGIC SYNTHESIS AND SIMULATION 12

Overview of digital design with Verilog HDL, hierarchical modelling concepts, modules and port definitions, gate level modelling, data flow modelling, behavioural modelling, task & functions, Verilog and logic synthesis-simulation-Design examples,Ripple carry Adders, Carry Look ahead adders, Multiplier, ALU, Shift Registers, Multiplexer, Comparator, Test Bench.

TUTORIALS:

Digital design with Verilog HDL, gate level modelling, -simulation-Design examples,Ripple carry Adders, Carry Look ahead adders, Multiplier, ALU, Shift Registers, Multiplexer, Comparator, on Xilinx Platform/Processor Supported Test Bench

L: 45+T:15 = 60 PERIODS

REFERENCES:

1. M.J.S Smith, “Application Specific integrated circuits”,Addition Wesley Longman Inc.1997.
2. Kamran Eshraghian,Douglas A.pucknell and Sholeh Eshraghian,”Essentials of VLSI circuits and system”, Prentice Hall India,2005.
3. Wayne Wolf, “ Modern VLSI design “ Prentice Hall India,2006.
4. Mohamed Ismail ,Terri Fiez, “Analog VLSI Signal and information Processing”, McGraw Hill International Editions,1994.
5. Samir Palnitkar, “Veri Log HDL, A Design guide to Digital and Synthesis” 2nd Ed,Pearson,2005.

HV8071 APPLICATIONS OF HIGH ELECTRIC FIELDS **L T P C**
3 0 0 3

OBJECTIVES:

To impart knowledge on,

- different HV applications in industry and food preservation.
- different HV applications in cancer treatments and microbial inactivation.
- the awareness on safety and hazard issues.

UNIT I APPLICATION IN INDUSTRY **9**

Introduction – electrostatic applications- electrostatic precipitation, separation , painting / coating, spraying ,imaging ,printing ,Transport of materials – Sandpaper Manufacture – Smoke particle detector – Electrostatic spinning ,pumping , propulsion – Ozone generation – Biomedical applications.

UNIT II APPLICATION IN MICROBIAL INACTIVATION **9**

Introduction-definitions, descriptions and applications-mechanisms of microbial in-activations-electrical breakdown-electroporation-inactivation models -Critical factors-analysis of process, product and microbial factors-pulse generators and treatment chamber design-Research needs.

UNIT III APPLICATION IN FOOD PRESERVATION **9**

Processing of juices, milk, egg, meat and fish products- Processing of water and waste – Industrial feasibility, cost and efficiency analysis.

UNIT IV APPLICATION IN CANCER TREATMENT **9**

Different types of cancer – Different types of treatments, anti-cancer drugs – Electro-chemotherapy – Electric fields in cancer tissues – Modeling, analysis of cancer tissues.

UNIT V SAFETY AND ELECTROSTATIC HAZARDS **9**

Introduction – Nature of static electricity – Triboelectric series – Basic laws of Electrostatic electricity– materials and static electricity – Electrostatic discharges (ESD) – Static electricity problems – Hazards of Electrostatic electricity in industry – Hazards from electrical equipment and installations – Static eliminators and charge neutralizers – Lightning protection.

TOTAL : 45 PERIODS

REFERENCES

1. N.H.Malik, A.A.Ai-Arainy, M.I.Qureshi, “Electrical Insulation in power systems”, Marcel Dekker, inc., 1998.
2. Mazen Abdel-Salam, Hussien Anis, Ahdab EI-Morshedy, “High Voltage Engineering”, Second Edition, Theory and Practice, Marcel Dekker, Inc. 2000,
3. John D.Kraus, Daniel A.Fleisch, “Electromagnetics with Applications” McGraw Hill International Editions, 1992.
4. Shoait Khan, “ Industrial Power System”, CRC Press, Taylor & Francis group, 2008.
5. G.V. Barbosa –Canovas , “Pulsed electric fields in food processing:Fundamental aspects and applications” CRC Publisher Edition March 1 2001.

6. H L M Lelieveld and Notermans.S,et.al., "Food preservation by pulsed electric fields: From research to application", Woodhead Publishing Ltd. October 2007.

HV8072 ELECTROMAGNETIC INTERFERENCE AND COMPATIBILITY LT P C
3 0 0 3

OBJECTIVES:

- To provide fundamental knowledge on electromagnetic interference and electromagnetic compatibility.
- To study the important techniques to control EMI and EMC.
- To expose the knowledge on testing techniques as per different Indian and international standards in EMI measurement.

UNIT I INTRODUCTION 9

Definitions of EMI/EMC -Sources of EMI- Intersystems and Intrasystem- Conducted and radiated interference- Characteristics - Designing for electromagnetic compatibility (EMC)- EMC regulation- typical noise path- EMI predictions and modeling, Cross talk - Methods of eliminating interferences.

UNIT II GROUNDING AND CABLING 9

Cabling- types of cables, mechanism of EMI emission / coupling in cables –capacitive coupling- inductive coupling- shielding to prevent magnetic radiation- shield transfer impedance, Grounding – safety grounds – signal grounds- single point and multipoint ground systems- hybrid grounds- functional ground layout –grounding of cable shields- - guard shields- isolation, neutralizing transformers, shield grounding at high frequencies, digital grounding- Earth measurement Methods.

UNIT III BALANCING, FILTERING AND SHIELDING 9

Power supply decoupling- decoupling filters-amplifier filtering –high frequency filtering- EMI filters characteristics of LPF, HPF, BPF, BEF and power line filter design -Choice of capacitors, inductors, transformers and resistors, EMC design components -shielding – near and far fields- shielding effectiveness- absorption and reflection loss- magnetic materials as a shield, shield discontinuities, slots and holes, seams and joints, conductive gaskets-windows and coatings- grounding of shields.

UNIT IV EMI IN ELEMENTS AND CIRCUITS 9

Electromagnetic emissions, noise from relays and switches, non-linearities in circuits, passive inter modulation, transients in power supply lines, EMI from power electronic equipment, EMI as combination of radiation and conduction.

UNIT V ELECTROSTATIC DISCHARGE, STANDARDS AND TESTING TECHNIQUES 9

Static Generation- human body model- static discharges- ESD versus EMC, ESD protection in equipments- standards – FCC requirements – EMI measurements – Open

area test site measurements and precautions- Radiated and conducted interference measurements, Control requirements and testing methods.

TOTAL : 45 PERIODS

REFERENCES

1. V.P. Kodali, “Engineering Electromagnetic Compatibility”, S. Chand, 1996.
2. Henry W.Ott, “ Noise reduction techniques in electronic systems”, John Wiley & Sons, 1989.
3. Bernhard Keiser, “Principles of Electro-magnetic Compatibility”, Artech House, Inc. (685 canton street, Norwood, MA 020062 USA) 1987.
4. Bridges, J.E Milleta J. and Ricketts.L.W., “EMP Radiation and Protective techniques”, John Wiley and sons, USA 1976.
5. William Duff G., & Donald White R. J, “Series on Electromagnetic Interference and Compatibility”, Vol.
6. Weston David A., “Electromagnetic Compatibility, Principles and Applications”, 1991.

IN8251 APPLIED INDUSTRIAL INSTRUMENTATION L T P C
3 0 0 3

OURSE OBJECTIVES

To enable students

- To acquire knowledge about the various techniques used for the measurement of primary industrial parameters like flow, level, temperature and pressure.
- understand the important parameters to be monitored and analyzed in Thermal power Plant
- To get an exposure on the important parameters to be monitored and analyzed in Petrochemical Industry
- To learn about the hazardous zone classification and intrinsic safety techniques to the adapted in industries.
- Learn about other special purpose instruments like Nuclear radiation detection techniques, fibre optic sensors, Instrumentation for NDT applications etc

COURSE OUTCOMES

On completion of this course, students will be able to

- understand the instrumentation behind flow, level, temperature and pressure measurement
- Acquire basic knowledge on the important measurement parameters and required analyzers with respect to Boilers in Thermal power plant,
- know about the working principle of instruments used in different operations in petrochemical industry
- explain about the necessary safety techniques to be adopted in a typical Process industry
- Understand about the Instrumentation used in Nuclear Radiation Detection, corrosion monitoring and to have an exposure on NDT analysis.

UNIT I REVIEW OF INDUSTRIAL INSTRUMENTATION 9

Overview of Measurement of Flow, level, Temperature and Pressure

UNIT II MEASUREMENT IN THERMAL POWER PLANT (BOILERS) 9

Selection and Installation of instruments used for the Measurement of fuel flow, Air flow, Drum level, Steam pressure, Steam temperature – Feed water quality measurement- Flue gas Oxygen Analyzers- Coal Analyzer.

UNIT III MEASUREMENT IN PETROLEUM REFINERY 9

Parameters to be measured in petroleum industry:-Flow, Level, Temperature and Pressure measurement in Distillation, Pyrolysis, catalytic cracking and reforming process-Hydrocarbon analyzers-oil in or on water-sulphur in oil Analyzer.

UNIT IV INSTRUMENTATION FOR INDUSTRIAL SAFETY 9

Electrical and Intrinsic Safety - Explosion Suppression and Deluge systems -Conservation and emergency vents - Flame, fire and smoke detectors - Leak Detectors - Metal Detectors.

UNIT V SPECIAL PURPOSE INSTRUMENTATION 9

Detection of Nuclear Radiation – Corrosion monitoring – Fibre optic sensors-Instrumentation in weather stations -Instrumentation for NDT applications-Image processing Technique for measurements.

TOTAL : 45 PERIODS

REFERENCE BOOKS

1 B.G.Liptak, “Instrumentation Engineers Handbook (Process Measurement & Analysis)”, Fourth Edition, Chilton Book Co, 2003.

2 K.Krishnaswamy and M.Ponnibala, “Power Plant Instrumentation”, PHI Learning Pvt Ltd, 2011.

3 John G Webster, “The Measurement, Instrumentation, and Sensors Handbook”, CRC and IEEE Press, 1999.

4 Håvard Devold, “Oil and Gas Production Handbook - An Introduction to Oil and Gas Production”, ABB ATPA oil and gas, 2006

5 M.Arumugam, “Optical Fibre Communication and Sensors”, Anuradha Agencies, 2002.

6 Paul E. Mix, “Introduction to Nondestructive Testing”, John Wiley and Sons, 2005.

PE8152 ANALYSIS OF ELECTRICAL MACHINES LT P C
3 0 0 3

OBJECTIVES:

- To provide knowledge about the fundamentals of magnetic circuits, energy, force and torque of multi-excited systems.
- To analyze the steady state and dynamic state operation of DC machine through
- mathematical modeling and simulation in digital computer.
- To provide the knowledge of theory of transformation of three phase variables to two phase variables.
- To analyze the steady state and dynamic state operation of three-phase inductiomachines using transformation theory based mathematical modeling and digital computer simulation.
- To analyze the steady state and dynamic state operation of three-phase synchronous machines using transformation theory based mathematical modeling and digital computer simulation.

UNIT I PRINCIPLES OF ELECTROMAGNETIC ENERGY CONVERSION 9

Magnetic circuits, permanent magnet, stored magnetic energy, co-energy - force and torque in singly and doubly excited systems – machine windings and air gap mmf - winding inductances and voltage equations.

UNIT II DC MACHINES 9

Elementary DC machine and analysis of steady state operation - Voltage and torque equations – dynamic characteristics of permanent magnet and shunt d.c. motors – Time domain block diagrams - solution of dynamic characteristic by Laplace transformation – digital computer simulation of permanent magnet and shunt d.c. machines.

UNIT III REFERENCE FRAME THEORY 9

Historical background – phase transformation and commutator transformation – transformation of variables from stationary to arbitrary reference frame - variables observed from several frames of reference.

UNIT IV INDUCTION MACHINES 9

Three phase induction machine, equivalent circuit and analysis of steady state operation – free acceleration characteristics – voltage and torque equations in machine variables and arbitrary reference frame variables – analysis of dynamic performance for load torque variations – digital computer simulation.

UNIT V SYNCHRONOUS MACHINES 9

Three phase synchronous machine and analysis of steady state operation - voltage and torque equations in machine variables and rotor reference frame variables (Park's equations) – analysis of dynamic performance for load torque variations – digital computer simulation.

TOTAL : 45 PERIODS

TEXT BOOKS

1.Paul C.Krause, Oleg Wasyzczuk, Scott S, Sudhoff, "Analysis of Electric Machinery and Drive Systems", John Wiley, Second Edition, 2010.

REFERENCES

1.P S Bimbhra, "Generalized Theory of Electrical Machines", Khanna Publishers, 2008.
2.A.E, Fitzgerald, Charles Kingsley, Jr, and Stephan D, Umanx, " Electric Machinery", Tata McGraw Hill, 5th Edition, 1992

PE8153 ANALYSIS OF POWER CONVERTERS L T P C
3 0 0 3

OBJECTIVES :

- To provide the electrical circuit concepts behind the different working modes of power converters so as to enable deep understanding of their operation.
- To equip with required skills to derive the criteria for the design of power converters starting from basic fundamentals.
- To analyze and comprehend the various operating modes of different configurations of power converters.
- To design different power converters namely AC to DC, DC to DC and AC to AC converters.

UNIT I SINGLE PHASE AC-DC CONVERTER 9

Static Characteristics of power diode, SCR and GTO, half controlled and fully controlled converters with R-L, R-L-E loads and free wheeling diodes – continuous and discontinuous modes of operation - inverter operation –Sequence control of converters – performance parameters: harmonics, ripple, distortion, power factor – effect of source impedance and overlap-reactive power and power balance in converter circuits

UNIT II THREE PHASE AC-DC CONVERTER 9

Semi and fully controlled converter with R, R-L, R-L-E - loads and free wheeling diodes – inverter operation and its limit – performance parameters – effect of source impedance and over lap – 12 pulse converter.

UNIT III DC-DC CONVERTERS 9

Principles of step-down and step-up converters – Analysis of buck, boost, buck-boost and Cuk converters – time ratio and current limit control – Full bridge converter – Resonant and quasi – resonant converters.

UNIT IV AC VOLTAGE CONTROLLERS 9

Static Characteristics of TRIAC- Principle of phase control: single phase and three phase controllers – various configurations – analysis with R and R-L loads.

UNIT V CYCLOCONVERTERS 9

Principle of operation – Single phase and Three-phase Dual converters - Single phase and three phase cyclo-converters – power factor Control – Introduction to matrix converters.

TOTAL : 45 PERIODS

TEXT BOOKS

1.Ned Mohan,T.M Undeland and W.P Robbin, “Power Electronics: converters, Application and design” John Wiley and sons.Wiley India edition, 2006.
2. Rashid M.H., “Power Electronics Circuits, Devices and Applications ", Pierson Prentice Hall India, New Delhi, 2004.
3. Cyril W.Lander, “power electronics”, Third Edition McGraw hill-1993

REFERENCES

1. P.C Sen.," Modern Power Electronics ", Wheeler publishing Co, First Edition, New Delhi-1998.
2.P.S.Bimbra, “Power Electronics”, Khanna Publishers, Eleventh Edition, 2003.
3.Power Electronics by Vedam Subramanyam, New Age International publishers, New Delhi Second Edition, 2006

PE8251 SOLID STATE DC DRIVES L T P C
3 0 0 3

OBJECTIVES:

- To understand steady state operation and transient dynamics of a motor load system
- To study and analyze the operation of the converter / chopper fed DC drive, both qualitatively and quantitatively.
- To analyze and design the current and speed controllers for a closed loop solid state DC motor drive.
- To understand the implementation of control algorithms using microcontrollers and phase locked loop.

UNIT I DC MOTORS FUNDAMENTALS AND MECHANICAL SYSTEMS 9

DC motor- Types, induced emf, speed-torque relations; Speed control – Armature and field speed control; Ward Leonard control – Constant torque and constant horse power operation - Introduction to high speed drives and modern drives.

Characteristics of mechanical system – dynamic equations, components of torque, types of load; Requirements of drives characteristics - stability of drives – multi-quadrant operation; Drive elements, types of motor duty and selection of motor rating.

UNIT II CONVERTER CONTROL 9

Principle of phase control – Fundamental relations; Analysis of series and separately excited DC motor with single-phase and three-phase converters – waveforms, performance parameters, performance characteristics.

Continuous and discontinuous armature current operations; Current ripple and its effect on performance; Operation with free wheeling diode; Implementation of braking schemes; Drive employing dual converter.

UNIT III CHOPPER CONTROL 9

Introduction to time ratio control and frequency modulation; Class A, B, C, D and E chopper controlled DC motor – performance analysis, multi-quadrant control - Chopper based implementation of braking schemes; Multi-phase chopper; Related problems.

UNIT IV CLOSED LOOP CONTROL 9

Modeling of drive elements – Equivalent circuit, transfer function of self, separately excited DC motors; Linear Transfer function model of power converters; Sensing and feeds back elements - Closed loop speed control – current and speed loops, P, PI and PID controllers – response comparison. Simulation of converter and chopper fed d.c drive.

UNIT V DIGITAL CONTROL OF D.C DRIVE 9

Phase Locked Loop and micro-computer control of DC drives – Program flow chart for constant horse power and load disturbed operations; Speed detection and current sensing circuits.

TOTAL : 45 PERIODS

TEXT BOOKS

1.Gopal K Dubey, “Power Semiconductor controlled Drives”, Prentice Hall Inc., New Yersy, 1989.
2.R.Krishnan, “Electric Motor Drives – Modeling, Analysis and Control”, Prentice-Hall of India Pvt. Ltd., New Delhi, 2010.

REFERENCES

1.Gobal K.Dubey, “Fundamentals of Electrical Drives”, Narosal Publishing House, New Delhi, Second Edition ,2009
2. Vedam Subramanyam, “Electric Drives – Concepts and Applications”, Tata McGraw-Hill publishing company Ltd., New Delhi, 2002.
3. P.C Sen “Thyristor DC Drives”, John wiely and sons, New York, 1981

PE8252 SPECIAL ELECTRICAL MACHINES L T P C
3 0 0 3

OBJECTIVES

- To review the fundamental concepts of permanent magnets and the
- operation of permanent magnet brushless DC motors.
- To introduce the concepts of permanent magnet brushless synchronous motors and synchronous reluctance motors.
- To develop the control methods and operating principles of switched reluctance motors.
- To introduce the concepts of stepper motors and its applications.
- To understand the basic concepts of other special machines.

UNIT I PERMANENT MAGNET BRUSHLESS DC MOTORS 9

Fundamentals of Permanent Magnets- Types- Principle of operation- Magnetic circuit analysis-EMF and Torque equations- Characteristics and control

UNITII PERMANENT MAGNET SYNCHROUNOUS MOTORS 9

Principle of operation – EMF and Torque equations - Phasor diagram - Power controllers – Torque speed characteristics – Digital controllers – Constructional features, operating principle and characteristics of synchronous reluctance motor.

UNIT III SWITCHED RELUCTANCE MOTORS 9

Constructional features –Principle of operation- Torque prediction–Characteristics Power controllers – Control of SRM drive- Sensorless operation of SRM – Applications.

UNIT IV STEPPER MOTORS 9

Constructional features –Principle of operation –Types – Torque predictions – Linear and Non-linear analysis – Characteristics – Drive circuits – Closed loop control – Applications.

UNIT V OTHER SPECIAL MACHINES 9

Principle of operation and characteristics of Hysteresis motor – AC series motors – Linear motor – Applications.

TOTAL: 45 PERIODS

TEXT BOOKS:

1. T.J.E. Miller, 'Brushless magnet and Reluctance motor drives', Claredon press, London, 1989.
2. R.Krishnan, ' Switched Reluctance motor drives' , CRC press, 2001.
3. T.Kenjo, ' Stepping motors and their microprocessor controls', Oxford University press, New Delhi, 2000.

REFERENCES:

1. T.Kenjo and S.Nagamori, 'Permanent magnet and Brushless DC motors', Clarendon press, London, 1988.
2. R.Krishnan, ' Electric motor drives' , Prentice hall of India,2002.
3. D.P.Kothari and I.J.Nagrath, ' Electric machines', Tata Mc Graw hill publishing company, New Delhi, Third Edition, 2004.
4. Irving L.Kosow, "Electric Machinery and Transformers" Pearson Education, Second Edition, 2007.

PE8351 POWER ELECTRONICS FOR RENEWABLE ENERGY SYSTEMS LT P C
3 0 0 3

OBJECTIVES :

- To Provide knowledge about the stand alone and grid connected renewable energy systems.
- To equip with required skills to derive the criteria for the design of power converters for renewable energy applications.
- To analyse and comprehend the various operating modes of wind electrical generators and solar energy systems.
- To design different power converters namely AC to DC, DC to DC and AC to AC converters for renewable energy systems.
- To develop maximum power point tracking algorithms.

UNITI INTRODUCTION 9

Environmental aspects of electric energy conversion: impacts of renewable energy generation on environment (cost-GHG Emission) - Qualitative study of different renewable energy resources ocean, Biomass, Hydrogen energy systems : operating principles and characteristics of: Solar PV, Fuel cells, wind electrical systems-control strategy, operating area.

UNIT II ELECTRICAL MACHINES FOR RENEWABLE ENERGY CONVERSION 9

Review of reference theory fundamentals-principle of operation and analysis: IG, PMSG, SCIG and DFIG.

UNIT III POWER CONVERTERS 9

Solar: Block diagram of solar photo voltaic system : line commutated converters (inversion-mode) - Boost and buck-boost converters- selection Of inverter, battery sizing, array sizing.

Wind: three phase AC voltage controllers- AC-DC-AC converters: uncontrolled rectifiers, PWM Inverters, Grid Interactive Inverters-matrix converters.

UNIT IV ANALYSIS OF WIND AND PV SYSTEMS 9

Stand alone operation of fixed and variable speed wind energy conversion systems and solar system-Grid connection Issues -Grid integrated PMSG and SCIG Based WECS-Grid Integrated solar system

UNIT V HYBRID RENEWABLE ENERGY SYSTEMS 9

Need for Hybrid Systems- Range and type of Hybrid systems- Case studies of Wind-PV-Maximum Power Point Tracking (MPPT).

TOTAL : 45 PERIODS

TEXT BOOK

1. S.N.Bhadra, D. Kastha, & S. Banerjee "Wind Electricaal Systems", Oxford University Press, 2009

REFERENCES:

1**.** Rashid .M. H "power electronics Hand book", Academic press, 2001.

2. Rai. G.D, “Non conventional energy sources”, Khanna publishes, 1993.
3. Rai. G.D,” Solar energy utilization”, Khanna publishes, 1993.
4. Gray, L. Johnson, “Wind energy system”, prentice hall linc, 1995.
5. Non-conventional Energy sources B.H.Khan Tata McGraw-hill Publishing Company, New Delhi.

HV8073 DESIGN OF SUBSTATIONS L T P C
3 0 0 3

OBJECTIVES:

- To provide in-depth knowledge on design criteria of Air Insulated Substation (AIS) and Gas Insulated Substation (GIS).
- To study the substation insulation co-ordination and protection scheme.
- To study the source and effect of fast transients in AIS and GIS.

UNIT I INTRODUCTION TO AIS AND GIS 9

Introduction – characteristics – comparison of Air Insulated Substation (AIS) and Gas Insulated Substation (GIS) – main features of substations, Environmental considerations, Planning and installation.

UNIT II MAJOR EQUIPMENT AND LAYOUT OF AIS AND GIS 9

Major equipment – design features – equipment specification, types of electrical stresses, mechanical aspects of substation design.

UNIT III INSULATION COORDINATION OF AIS AND GIS 9

Introduction – stress at the equipment – insulation strength and its selection – standard BILs – Application of simplified method – Comparison with IEEE and IEC guides.

UNIT IV GROUNDING AND SHIELDING 9

Definitions – soil resistivity measurement – ground fault currents – ground conductor – design of substation grounding system – shielding of substations – Shielding by wires and masts.

UNIT V FAST TRANSIENTS PHENOMENON IN AIS AND GIS 9

Introduction – Disconnector switching in relation to very fast transients – origin of VFTO – propagation and mechanism of VFTO – VFTO characteristics – Effects of VFTO.

TOTAL : 45 PERIODS

REFERENCES

1. Andrew R. Hileman, “Insulation coordination for power systems”, Taylor and Francis, 1999.

2. M.S. Naidu, “Gas Insulation Substations”, I.K. International Publishing House Private Limited, 2008.
3. Klaus Ragallar, “Surges in high voltage networks” Plenum Press,New York, 1980. “Power Engineer’s handbook”, TNEB Association.
4. Pritindra Chowdhuri, “Electromagnetic transients in power systems”, PHI Learning Private Limited, New Delhi, Second edition, 2004.
5. “Design guide for rural substation”, United States Department of Agriculture, RUS Bulletin, 1724E-300, June 2001.

PS8075 OPTIMISATION TECHNIQUES L T P C
3 0 0 3

COURSE OBJECTIVES

- To introduce the different optimization problems and techniques
- To study the fundamentals of the linear and non-linear programming problem.
- To understand the concept of dynamic programming and genetic algorithm technique

UNIT I INTRODUCTION 9

Definition, Classification of optimization problems, Classical Optimization Techniques, Single and Multiple Optimization with and without inequality constraints.

UNIT II LINEAR PROGRAMMING (LP) 9

Simplex method of solving LPP, revised simplex method, duality, Constrained optimization, Theorems and procedure, Linear programming, mathematical model, solution technique, duality.

UNIT III NON LINEAR PROGRAMMING 9

Steepest descent method, conjugates gradient method, Newton’s Method, Sequential quadratic programming, Penalty function method, augmented Lagrange multiplier method.,

UNIT IV DYNAMIC PROGRAMMING (DP) 9

Multistage decision processes, concept of sub-optimization and principle of optimality, Recursive relations, Integer Linear programming, Branch and bound algorithm

UNIT V GENETIC ALGORITHM 9

Introduction to genetic Algorithm, working principle, coding of variables, fitness function, GA operators; Similarities and differences between Gas and traditional methods; Unconstrained and constrained optimization using genetic Algorithm, real coded gas, Advanced Gas, global optimization using GA, Applications to power system.

TOTAL : 45 PERIODS

TEXT BOOKS:

1.S.S. Rao ,"Optimization – Theory and Applications", Wiley-Eastern Limited, 1984.
2.G.Luenberger," Introduction of Linear and Non-Linear Programming",Wesley Publishing Company, 2011.

REFERENCES:

1.Computational methods in Optimization, Polak , Academic Press,1971.
2.Optimization Theory with applications, Pierre D.A., Wiley Publications,1969.
3.Taha, H. A., Operations Research: An Introduction, Seventh Edition, Pearson Education Edition, Asia, New Delhi ,2002.

PS8076 SOLAR AND ENERGY STORAGE SYSTEM L T P C
3 0 0 3

COURSE OBJECTIVES

- To Study about solar modules and PV system design and their applications
- To Deal with grid connected PV systems
- To Discuss about different energy storage systems

UNIT I INTRODUCTION 9

Characteristics of sunlight – semiconductors and P-N junctions –behavior of solar cells – cell properties – PV cell interconnection

UNIT II STAND ALONE PV SYSTEM 9

Solar modules – storage systems – power conditioning and regulation - protection – stand alone PV systems design – sizing

UNIT III GRID CONNECTED PV SYSTEMS 9

PV systems in buildings – design issues for central power stations – safety – Economic aspect – Efficiency and performance - International PV programs

UNIT IV ENERGY STORAGE SYSTEMS 9

Impact of intermittent generation – Battery energy storage – solar thermal energy storage – pumped hydroelectric energy storage

UNIT V APPLICATIONS 9

Water pumping – battery chargers – solar car – direct-drive applications –Space – Telecommunications.

TOTAL : 45 PERIODS

TEXT BOOKS:

1.Eduardo Lorenzo G. Araujo, Solar electricity engineering of photovoltaic systems, Progensa,1994.
2.Stuart R.Wenham, Martin A.Green, Muriel E. Watt and Richard Corkish, Applied Photovoltaics, 2007,Earthscan, UK.

REFERENCES:

1. Frank S. Barnes & Jonah G. Levine, Large Energy storage Systems Handbook , CRC Press, 2011.
2. Solar & Wind energy Technologies – McNeils, Frenkel, Desai, Wiley Eastern, 1990
3. Solar Energy – S.P. Sukhatme, Tata McGraw Hill,1987.

PS8255	SMART GRIDS	L T P C
		3 0 0 3

COURSE OBJECTIVES

- To Study about Smart Grid technologies, different smart meters and advanced metering infrastructure.
- To familiarize the power quality management issues in Smart Grid.
- To familiarize the high performance computing for Smart Grid applications

UNIT I INTRODUCTION TO SMART GRID 9

Evolution of Electric Grid, Concept, Definitions and Need for Smart Grid, Smart grid drivers, functions, opportunities, challenges and benefits, Difference between conventional & Smart Grid, Concept of Resilient & Self Healing Grid, Present development & International policies in Smart Grid, Diverse perspectives from experts and global Smart Grid initiatives.

UNIT II SMART GRID TECHNOLOGIES 9

Technology Drivers, Smart energy resources,Smart substations, Substation Automation, Feeder Automation ,Transmission systems: EMS, FACTS and HVDC, Wide area monitoring, Protection and control, Distribution systems: DMS, Volt/VAr control,Fault Detection, Isolation and service restoration, Outage management,High-Efficiency Distribution Transformers, Phase Shifting Transformers, Plug in Hybrid Electric Vehicles (PHEV).

UNIT III SMART METERS AND ADVANCED METERING INFRASTRUCTURE 9

Introduction to Smart Meters, Advanced Metering infrastructure (AMI) drivers and benefits,AMI protocols, standards and initiatives, AMI needs in the smart grid, Phasor Measurement Unit(PMU), Intelligent Electronic Devices(IED) & their application for monitoring & protection.

UNIT IV POWER QUALITY MANAGEMENT IN SMART GRID 9

Power Quality & EMC in Smart Grid, Power Quality issues of Grid connected Renewable Energy Sources, Power Quality Conditioners for Smart Grid, Web based Power Quality monitoring, Power Quality Audit.

UNIT V HIGH PERFORMANCE COMPUTING FOR SMART GRID APPLICATIONS 9

Local Area Network (LAN), House Area Network (HAN), Wide Area Network (WAN), Broadband over Power line (BPL), IP based Protocols, Basics of Web Service and CLOUD Computing to make Smart Grids smarter, Cyber Security for Smart Grid.

TOTAL : 45 PERIODS

TEXT BOOKS *:*

1. Stuart Borlase “Smart Grid :Infrastructure, Technology and Solutions”,CRC Press 2012.
2. Janaka Ekanayake, Nick Jenkins, KithsiriLiyanage, Jianzhong Wu, Akihiko Yokoyama, “Smart Grid: Technology and Applications”, Wiley

REFERENCES*:*

1. Vehbi C. Güngör, DilanSahin, TaskinKocak, Salih Ergüt, Concettina Buccella, Carlo Cecati, and Gerhard P. Hancke, Smart Grid Technologies: Communication Technologies and Standards IEEE Transactions On Industrial Informatics, Vol. 7, No. 4, November 2011.
2. Xi Fang, Satyajayant Misra, Guoliang Xue, and Dejun Yang “Smart Grid – The New and Improved Power Grid: A Survey” , IEEE Transaction on Smart Grids,