

**Chapter 1 : Introduction to Control Systems**  
**1-1 to 1-10**

✓ **Syllabus Topic** : Basic Concepts of Control System ..... 1-1

1.1 Introduction ..... 1-1

1.2 Important Definitions ..... 1-1

✓ **Syllabus Topic** : Classification / Types of Control System ..... 1-2

1.3 Open Loop System (**Feb. 2016**) ..... 1-2

1.3.1 Open Loop Examples ..... 1-2

1.3.2 Advantages and Disadvantages of Open Loop Systems ..... 1-2

✓ **Syllabus Topic** : Feedback, Tracking, Regulator System ..... 1-3

1.4 Closed Loop System (**Dec. 2015, Feb. 2016**) ..... 1-3

1.4.1 Closed Loop Examples ..... 1-3

1.4.2 Advantages and Disadvantages of Closed Loop System ..... 1-4

1.5 How Does One Convert an Open Loop System to a Closed Loop System ? ..... 1-5

1.5.1 Comparison of Open and Closed Loop Systems (**May 2016, Dec. 2016**) ..... 1-5

1.6 Servo Mechanisms ..... 1-5

1.6.1 Requirements of a Good Control System ..... 1-5

✓ **Syllabus Topic** : Feed Forward System ..... 1-6

1.7 Feed Forward Systems (**Dec. 2015**) ..... 1-6

1.8 Adaptive Control Systems ..... 1-7

1.9 Solved Examples ..... 1-7

1.10 The Design Process ..... 1-9

1.11 Exam Pack (University and Review Questions) ..... 1-9

**Chapter 2 : Transfer Function and Mathematical Modelling**  
**2-1 to 2-34**

2.1 Introduction ..... 2-1

✓ **Syllabus Topic** : Transfer Function ..... 2-1

2.2 Transfer Function (**May 2015, Dec. 2015**) ..... 2-1

✓ **Syllabus Topic** : Pole and Zero Concept ..... 2-5

2.3 Poles and Zeros of a Transfer Function ..... 2-5

2.4 Properties of Transfer Function (T.F.) ..... 2-7

2.5 Proper and Improper Transfer Functions ..... 2-7

2.6 Advantages and Disadvantages of Transfer Function ..... 2-7

2.7 Impulse Response ..... 2-8

2.7.1 Impulse Response of a System ..... 2-8

2.8 Transfer Functions of Basic Devices ..... 2-9

2.9 Solved Examples on Transfer Functions ..... 2-12

✓ **Syllabus Topic** : Modeling and Representation of Control System - Basic Concept, Mechanical, Electrical and Equivalent System ..... 2-18

2.10 Mathematical Modeling of Mechanical and Electrical Systems ..... 2-18

2.10.1 Translational Motion ..... 2-18

2.10.2 Rotational Motion ..... 2-20

2.10.3 Electrical Systems ..... 2-21

✓ **Syllabus Topic** : Electromechanical ..... 2-21

2.11 Analogous Systems ..... 2-21

2.11.1 Force - Voltage Analogy (**Dec. 2015, Feb. 2016, May 2017**) ..... 2-22

2.11.2 Force - Current Analogy (**May 2017**) ..... 2-22

2.11.3 Advantages of Analogous Systems ..... 2-23

2.12 Representation by Nodal Method ..... 2-23

2.13 Solved Examples on Mathematical Modeling ..... 2-23

2.14 Exam Pack (University and Review Questions) ..... 2-33

**Chapter 3 : Block Diagram Representation**  
**3-1 to 3-28**

✓ **Syllabus Topic** : Block Diagram Algebra ..... 3-1

3.1 Introduction ..... 3-1

3.1.1 How to Draw a Block Diagram ? ..... 3-1

3.2 Block Diagram Definitions ..... 3-1

3.3 Generating a Block Diagram from a Physical System ..... 3-2

3.4 Block Diagram Reduction ..... 3-3

3.4.1 Derivation of Closed Loop (Feedback) Transfer Function (**May 2015**) ..... 3-3

3.4.2 Advantages of Block Diagram ..... 3-4

3.4.3 Disadvantages of Block Diagram ..... 3-4

3.5 Rules for Block Diagram Reduction ..... 3-4

3.6 Solved Examples ..... 3-10

3.7 Exam Pack (University and Review Questions) ..... 3-28

**Chapter 4 : Signal Flow Graph**  
**4-1 to 4-26**

✓ **Syllabus Topic** : Signal Flow Graph ..... 4-1

4.1 Introduction ..... 4-1

4.1.1 How to Draw a Signal Flow Graph ? ..... 4-1

4.2 Method to Draw SFG from System Equations ..... 4-1

4.3 Method to Draw SFG from Block Diagrams ..... 4-2

4.4 Some Important Signal Flow Graph Terms ..... 4-3



4.5	Properties of SFG.....	4-5		Coefficient Method.....	5-10	
4.5.1	Comparison of Block Diagram and SFG Methods .....	4-5		5.6.5	Dynamic Error Coefficients .....	5-10
✓	<b>Syllabus Topic</b> : Mason's Gain Formula.....	4-5		5.6.6	Examples on Steady State Response .....	5-11
4.6	Mason's Gain Formula ( <b>Feb. 2016, Dec. 2016</b> ).....	4-5		5.7	Transient Response.....	5-18
4.6.1	Mason's Gain Equation .....	4-5	✓	<b>Syllabus Topic</b> : Time Response of		
4.7	Steps for Solving S.F.G. using Mason's			First Order System to Unit Step Input.....	5-19	
	Gain Formula.....	4-5		5.7.1	Analysis of First Order Systems ( <b>May 2017</b> ) .....	5-19
4.7.1	Solved Examples.....	4-6		5.7.2	Analysis of Second Order System .....	5-21
4.8	Solving SFG When Equations are Given .....	4-22		5.7.2.1	Damping Factor .....	5-21
4.8.1	Solved Examples.....	4-22		5.7.2.2	Natural Frequency of Oscillation ( $\omega_n$ ) .....	5-21
4.9	Use of Mason's Gain Formula for			5.7.2.3	Position of Poles in a 2 <sup>nd</sup> Order System .....	5-21
	Electrical Network.....	4-24		5.7.3	Effect of $\xi$ on the Position of	
4.10	Exam Pack (University and Review Questions).....	4-26		Closed Loop Poles.....	5-23	
<b>Chapter 5 : Time Domain Analysis</b>		<b>5-1 to 5-41</b>	✓	<b>Syllabus Topic</b> : Time Response of Second		
5.1	Introduction.....	5-1		Order System to Unit Step Input.....	5-23	
5.1.1	Time Response .....	5-1		5.7.4	Unit Step Response of a 2 <sup>nd</sup> Order System .....	
✓	<b>Syllabus Topic</b> : Standard Test Signal - Step, Ramp,			( <b>May 2015</b> ).....	5-23	
	Parabolic and Impulse Signal.....	5-2		5.7.5	Time Response of a Second Order	
5.2	Inputs Supplied to a System ( <b>Feb. 2016</b> ).....	5-2		System with $0 < \xi < 1$ .....	5-26	
✓	<b>Syllabus Topic</b> : Steady State Errors - Static Error		✓	<b>Syllabus Topic</b> : Time Response of Second		
	Coefficients.....	5-4		Order System to Unit Impulse Input.....	5-26	
5.3	Steady State Response.....	5-4		5.7.5.1	Derivation of Unit Impulse Response of	
5.3.1	Effect of Input R (s) on Steady State Error .....			a 2 <sup>nd</sup> Order Underdamped System .....	5-26	
	( <b>May 2016</b> ) .....	5-4		5.7.5.2	Derivation of Unit Step Response of a	
✓	<b>Syllabus Topic</b> : Type and Order of Control System ..	5-6		2 <sup>nd</sup> Order Underdamped System .....	5-27	
5.3.2	Effect of Open Loop Transfer Function G(s) H(s) on		✓	<b>Syllabus Topic</b> : Time Domain Specifications		
	Steady State Error $e_{ss}$ ( <b>May 2015, May 2017</b> ) .....	5-6		of Second Order Systems.....	5-29	
5.4	Subjecting a Type 0 System to a Step, Ramp and			5.8	Transient Response Specifications	
	Parabolic Input ( <b>May 2015, May 2017</b> ) .....	5-7		( <b>Feb. 2016, Dec. 2016</b> ) .....	5-29	
5.4.1	Step Input to a Type 0 System .....	5-7	✓	<b>Syllabus Topic</b> : Derivation of Time Domain		
5.4.2	Ramp Input to a Type 0 System.....	5-7		Specifications for Second- Order Under-damped		
5.4.3	Parabolic Input to a Type 0 System .....	5-7		System for Unit Step Input.....	5-30	
5.5	Subjecting a Type 1 System to a Step, Ramp and			5.8.1	Derivation of Rise Time ( $T_r$ ).....	5-30
	Parabolic Input ( <b>May 2015, May 2017</b> ) .....	5-8		5.8.2	Derivation of Peak Time ( $T_p$ ).....	5-30
5.5.1	Step Input to a Type 1 System .....	5-8		5.8.3	Derivation of Peak Overshoot ( $M_p$ ) .....	5-31
5.5.2	Ramp Input to a Type 1 System.....	5-8		5.8.4	Derivation of Settling Time ( $T_s$ ).....	5-32
5.5.3	Parabolic Input to a Type 1 System .....	5-8		5.9	Solved Problems on Transient Response .....	5-32
5.6	Subjecting a Type 2 System to a Step, Ramp and			5.10	Exam Pack (University and Review Questions) .....	5-41
	Parabolic Input ( <b>May 2015, May 2017</b> ) .....	5-9		<b>Chapter 6 : Stability Analysis</b>		
5.6.1	Step Input to a Type 2 System .....	5-9		<b>6-1 to 6-23</b>		
5.6.2	Ramp Input to Type 2 System.....	5-9	✓	<b>Syllabus Topic</b> : Concept of Stability - Absolute,		
5.6.3	Parabolic Input to Type 2 System .....	5-9		Asymptotic, Relative and Marginal .....	6-1	
5.6.4	Disadvantages of Static Error			6.1	Introduction .....	6-1
				6.1.1	Stable System.....	6-1



6.1.2	Unstable System .....	6-1
6.1.3	Marginally Stable System .....	6-2
✓	<b>Syllabus Topic</b> : Importance of Dominant Closed Loop Poles of Higher Order Systems, Nature of System Response for Various Locations of Roots in s-plane of characteristics Equation .....	6-2
6.2	Time Response of Poles .....	6-2
6.2.1	Stability and Necessary Condition for Stability (May 2017) .....	6-6
✓	<b>Syllabus Topic</b> : Routh's - Hurwitz Criterion .....	6-6
6.3	Hurwitz Stability Criterion .....	6-6
6.3.1	Disadvantages of the Hurwitz Criterion .....	6-8
6.4	Routh Stability Criterion (May 2015, Dec. 2015, May 2016, Dec. 2016) .....	6-8
6.5	Routh Criterion Special Cases .....	6-10
6.5.1	Special Case 1 .....	6-10
6.5.2	Special Case 2 (Dec. 2015) .....	6-12
6.6	Relative Stability .....	6-15
6.7	Application of Routh's Criterion .....	6-16
6.8	Solved Examples .....	6-17
6.9	Exam Pack (University and Review Questions) .....	6-22

### Chapter 7 : Root Locus 7-1 to 7-37

✓	<b>Syllabus Topic</b> : Basic Properties of Root Locus .....	7-1
7.1	Introduction .....	7-1
✓	<b>Syllabus Topic</b> : Angle and Magnitude Condition .....	7-2
7.2	Angle and Magnitude Condition (May 2015) .....	7-2
✓	<b>Syllabus Topic</b> : Construction of Root Locus .....	7-3
7.3	Construction of Root Locus .....	7-3
7.3.1	General Method for Drawing Root Locus (May 2015, Dec. 2015, May 2016, May 2017) .....	7-3
7.4	Determining the Value of k from the Damping Ratio ....	7-7
7.5	Steps for Solving Problems on Root Locus .....	7-7
7.6	Solved Examples .....	7-7
7.7	Some Additional Important Points .....	7-36
7.7.1	More Zeros and Less Poles .....	7-36
7.7.2	Value of Gain Margin .....	7-36
7.7.3	Phase Margin from Root Locus .....	7-36
7.8	Effect of Addition of Poles and Zeros on Root Locus .....	7-36
7.8.1	Effect of Addition of Poles .....	7-36
7.8.2	Effect of Addition of Zeros .....	7-36
7.9	Exam Pack (University and Review Questions) .....	7-37

### Chapter 8 : Frequency Domain Analysis 8-1 to 8-14

✓	<b>Syllabus Topic</b> : Introduction .....	8-1
8.1	Introduction .....	8-1
8.2	Frequency Response .....	8-1
8.2.1	Sinusoidal Response of a Linear System .....	8-1
8.2.2	Methods used in Frequency Response .....	8-2
8.2.3	Advantages of Frequency Response Analysis .....	8-3
8.2.4	Time Response and Frequency Response Analysis .....	8-3
8.2.5	Disadvantages of Frequency Response Methods .....	8-3
8.3	Transfer Function and Frequency Response .....	8-3
8.3.1	Transfer Function and Frequency Response of a R - C Circuit .....	8-3
✓	<b>Syllabus Topic</b> : Frequency Domain Specifications .....	8-5
8.4	Frequency Domain Specifications .....	8-5
✓	<b>Syllabus Topic</b> : Relation between Time and Frequency Response for Second Order System .....	8-5
8.5	Co-relation between Time and Frequency Domain (May 2015, Dec. 2015) .....	8-5
8.5.1	Derivation of $\omega_r$ and $M_r$ .....	8-5
8.5.2	Relationship between Frequency Domain Specifications and Time Domain Specifications .....	8-6
8.6	Bandwidth .....	8-7
8.7	Solved Examples .....	8-8
8.8	Exam Pack (University and Review Questions) .....	8-14

### Chapter 9 : Bode Plots 9-1 to 9-54

✓	<b>Syllabus Topic</b> : Introduction to Bode Plot .....	9-1
9.1	Introduction .....	9-1
9.2	Log-Scales .....	9-2
9.2.1	Why Do We Use the Log Scales on the X-axis ? .....	9-2
9.2.2	What are Log-Scales ? .....	9-2
9.2.3	Scale Marking .....	9-3
9.3	Standard Form for GH ( $j\omega$ ) .....	9-3
✓	<b>Syllabus Topic</b> : Asymptotic Approximation : Sketching of Bode Plot .....	9-4
9.4	Bode Plots of Standard Factors .....	9-4
9.4.1	Bode Gain Factor $K_1$ .....	9-4
9.4.2	Poles at Origin or Integral Factor $\left(\frac{1}{j\omega}\right)^k$ .....	9-4
9.4.3	Zeros at Origin or Derivative Factor $(j\omega)^g$ .....	9-5



9.4.4	First Order Poles $\frac{1}{(1 + j\frac{\omega}{p_1})}$ .....	9-6	✓	<b>Syllabus Topic :</b> Nyquist Plot .....	10-15
9.4.5	First Order Zeros $(1 + j\frac{\omega}{z_1})$ .....	9-7	✓	<b>Syllabus Topic :</b> Stability Analysis using Nyquist Plot.....	10-16
9.4.6	Second Order Poles .....	9-8			
9.4.7	Second Order Zeros .....	9-9			
✓	<b>Syllabus Topic :</b> Stability .....	9-10			
9.5	Frequency Domain Specifications <b>(Dec. 2016, May 2017)</b> .....	9-10			
9.5.1	Gain Margin (G.M.) <b>(May 2016, May 2017)</b> .....	9-10			
9.5.2	Phase Margin ( $\phi_{pm}$ ) <b>(May 2016, May 2017)</b> .....	9-11			
9.5.3	Bandwidth.....	9-11			
9.5.4	Cut-off Frequency ( $\omega_c$ ).....	9-11			
9.5.5	Cut-off Rate .....	9-11			
9.5.6	Resonance Peak Frequency ( $M_p$ ) .....	9-11			
9.5.7	Resonant Frequency ( $\omega_p$ ).....	9-11			
9.5.8	Gain Crossover Frequency ( $\omega_{gc}$ ) .....	9-11			
9.5.9	Phase Margin Angle ( $\gamma$ ) .....	9-11			
9.5.10	Phase Crossover Frequency ( $\omega_{pc}$ ).....	9-11			
✓	<b>Syllabus Topic :</b> Stability Analysis using Bode Plot.....	9-11			
9.6	Relative Stability.....	9-11			
9.7	Steps for Solving Bode Plots.....	9-12			
9.8	Summary of Bode Magnitude and Phase Plots of Various Terms .....	9-13			
9.9	How to Draw Lines of 20, 40, 60 dB/dec ?.....	9-14			
9.10	Advantages of Bode Plots .....	9-16			
9.11	Solved Examples.....	9-16			
9.12	Other Terms in Bode Plots .....	9-51			
9.12.1	Bode Plot for Transportation Lag .....	9-51			
9.13	Exam Pack (University and Review Questions).....	9-54			
<b>Chapter 10 : Polar and Nyquist Plots</b>		<b>10-1 to 10-41</b>			
10.1	Introduction.....	10-1	✓	<b>Syllabus Topic :</b> Nyquist Plot .....	10-15
✓	<b>Syllabus Topic :</b> Polar Plot .....	10-1			
10.2	Polar Plots .....	10-1			
10.2.1	Advantages of Polar Plots .....	10-1			
10.2.2	Polar Plot of a 1st Order Pole $(\frac{1}{s+p})$ .....	10-2			
10.3	Effect of Adding More Simple Poles.....	10-3			
10.4	Effect of Adding Pole at Origin .....	10-5			
10.5	Stability on Polar Plots .....	10-10			
10.5.1	A Simple Way to Check Stability on Polar Plots.....	10-14			
10.6	Nyquist Analysis - Mapping .....	10-15	✓	<b>Syllabus Topic :</b> Stability Analysis using Nyquist Plot.....	10-16
10.7	Nyquist Stability Criterion <b>(May 2015, Dec. 2015, May 2016, Dec. 2016, May 2017)</b> .....	10-16			
10.7.1	Actual Encirclement .....	10-17			
10.7.2	Modified Nyquist Contour .....	10-18			
10.7.3	Advantages of Nyquist Plot.....	10-18			
10.8	Relative Stability <b>(May 2016)</b> .....	10-18			
10.9	Solved Examples .....	10-18			
10.10	Exam Pack (University and Review Questions) .....	10-41			
<b>Chapter 11 : Controllers</b>		<b>11-1 to 11-17</b>			
11.1	Introduction to Controllers.....	11-1			
11.2	Types of Controllers.....	11-1			
11.2.1	ON-OFF Controllers.....	11-1			
✓	<b>Syllabus Topic :</b> Basic Concept of P.....	11-2			
11.2.2	Proportional Controller (P-Controller) <b>(May 2015, May 2016, May 2017)</b> .....	11-2			
✓	<b>Syllabus Topic :</b> Basic Concept of PI.....	11-3			
11.2.3	Proportional + Integral Controller (P-I Controller) <b>(May 2015, Dec. 2015, May 2016, May 2017)</b> .....	11-3			
11.2.4	Proportional + Derivative Controller (P-D Controller) <b>(Dec. 2015)</b> .....	11-4			
✓	<b>Syllabus Topic :</b> PID Controller.....	11-5			
11.2.5	Proportional-Integral-Derivative Controller (P-I-D Controller) <b>(May 2015, Dec. 2016, May 2017)</b> .....	11-5			
✓	<b>Syllabus Topic :</b> Design Specifications in Time Domain and Frequency Domain.....	11-6			
11.3	Effect of Proportional, Integral and Derivative Control on the Time Response of the System <b>(Dec. 2016)</b> .....	11-6			
✓	<b>Syllabus Topic :</b> Tuning of PID Controllers : Ziegler - Nichol Method.....	11-6			
11.4	PID Tuning using Ziegler-Nichols Method <b>(May 2015, Dec. 2015, May 2016, Dec. 2016, May 2017)</b> .....	11-6			
✓	<b>Syllabus Topic :</b> Design of PID Controller using Root-Locus.....	11-7			
11.5	Design of PID Controller using Root Locus .....	11-7			
11.6	Solved Examples .....	11-8			
11.7	Exam Pack (University and Review Questions) .....	11-16			



<b>Chapter 12 : Compensator Design and Control System Components</b>		<b>12-1 to 12-15</b>	
12.1	Standard Compensators.....	12-1	
✓	<b>Syllabus Topic</b> : Working Principle and Transfer Function of Lead Network.....	12-2	
12.2	Lead Compensator ( <b>May 2016</b> ).....	12-2	
✓	<b>Syllabus Topic</b> : Working Principle and Transfer Function of Lag Network.....	12-3	
12.3	Lag Compensators .....	12-3	
12.4	Design Difference between Phase Lead and Lag Compensation .....	12-4	
12.5	Lag - lead Compensator .....	12-4	
12.6	Servopotentiometers .....	12-5	
✓	<b>Syllabus Topic</b> : AC and DC Servomotors .....	12-6	
12.7	Servomotors.....	12-6	
12.7.1	A.C. Servomotors.....	12-6	
12.7.2	D.C. Servomotor ( <b>Feb. 2016, May 2016</b> ).....	12-7	
12.7.3	Armature Controlled D.C. Motor ( <b>May 2017</b> ) .....	12-8	
12.7.4	Field Controlled D.C. Motor .....	12-9	
12.8	Tachogenerator ( <b>Dec. 2016</b> ) .....	12-10	
12.8.1	DC Tachometer.....	12-10	
12.8.2	Advantages and Disadvantages of DC Tachometers .....	12-11	
12.8.3	AC Tachometer .....	12-11	
✓	<b>Syllabus Topic</b> : Working Principle of Synchros.....	12-12	
12.9	Synchros .....	12-12	
12.9.1	Synchro Transmitter .....	12-12	
12.9.2	Synchro - Transmitter - Control Transformer Pair....	12-13	
12.9.3	Synchro Transmitter Receiver ( <b>May 2015</b> ) .....	12-13	
12.10	Transfer Function Blocks of D.C. Motor Position Control System .....	12-14	
12.11	Exam Pack (University and Review Questions).....	12-15	
	➤ <b>Appendix - A : Solved University Question Papers of April 2018 and May 2018 .....</b>	<b>A-1 to A-27</b>	
	➤ <b>Appendix - B : Solved University Question Papers of Dec. 2018, April 2019 &amp; May 2019.....</b>	<b>B-1 to B-17</b>	
	➤ <b>University Question Papers .....</b>	<b>Q-1 to Q-10</b>	