#### SE Electronics Engineering Semester IV Credit and Evaluation scheme Semester IV

		<u></u>						
Sub Code	Subject Name	Teach	ing Schem	e(Hrs.)		Credits As	ssigned	
		Theory	Practical	Tutorial	Theory	Practical	Tutorial	Total
EXS 401	*Applied Mathematics IV	04		01	04		01	05
EXC402	Discrete Electronic Circuits	04			04			04
EXC 403	Microprocessor and	04			04			04
	Peripherals							
EXC404	Principles of Control	04			04			04
	Systems							
EXC405	Fundamentals of	04			04			04
	Communication Engineering							
EXC406	Electrical Machines	03			03			03
EXL401	Discrete Electronics		02			01		01
	Laboratory							
EXL402	Microprocessor and		02			01		01
	Peripherals Laboratory							
EXL403	Control System and		02			01		01
	Electrical Machines							
	Laboratory							
EXL 404	Communication Engineering		02			01		01
	Laboratory							
Total		23	08	01	23	04	01	28

Subject	Subject Name			Exam	ination S	cheme			
Code			The	eory Marks		Term	Practi	Oral	Total
					-	Work	cal		
		Iı	nternal as	ssessment	End		and		
		Test	Test 2	Ave. of Test	Sem.		Oral		
		1		1 and Test 2	Exam				
EXS 401	*Applied Mathematics IV	20	20	20	80	**25			125
EXC402	Discrete Electronic Circuits	20	20	20	80				100
EXC 403	Microprocessor and	20	20	20	80				100
	Peripherals								
EXC404	Principles of Control	20	20	20	80				100
	Systems								
EXC405	Fundamentals of	20	20	20	80				100
	Communication								
	Engineering								
EXC406	Electrical Machines	15	15	15	60				75
EXL 401	Discrete Electronics					25	50		75
	Laboratory								
EXL 402	Microprocessor and					25		25	50
	Peripherals Laboratory								
EXL 403	Control Systems and					25		25	50
	Electrical Machines								
	Laboratory								
EXL 404	Communication					25	50		75
	Engineering Laboratory								
Total				115	460	125	100	50	850

\*Subject Common with EXTC \*\* Tutorial work will be assessed as Term Work

# SE Electronics Engineering Semester IV Syllabus of Theory Subjects

Subject Code	Subject Name	Те	eaching Sche	eme	Credits Assigned			
		Theory	Practical	Tutorial	Theory	Practical	Tutorial	Total
EXS 401	Applied	04		01	04		01	05
	Mathematics IV							

Subject	Subject Name		Examination Scheme							
Code			Theory Marks				Practic	Oral	Total	
		In	ternal a	ssessment	End Sem.	as Term	al			
		Test	Test	Ave. Of	Exam	Work				
		1	2	Test 1 and						
				Test 2						
EXS401	Applied	20	20	20	80	25			125	
	Mathematics IV									

## **Course Prerequisite: Applied Mathematics III**

#### **Course Objective:**

This course will present the method of calculus of variations (CoV), basic concepts of vector spaces, matrix theory, concept of ROC and residue theory with applications.

#### **Expected Outcome:**

Students in this course will apply the method of CoV to specific systems, demonstrate ability to manipulate matrices and compute eigenvalues and eigenvectors, Identify and classify zeros, singular points, residues and their applications. After completion of this course students will be:

Module	Unit	Topics	Hrs.
NO.	NO.	Calculus of noniotion	10
1.0	1.0	Calculus of variation	10
	1.1	a. Euler's Langrange equation, solution of Euler's Langrange equation	
		(only results for different cases for function) independent of a variable and	
		independent of both variables	
	1 2	h. Isoperimetric problems, several dependent veriables	
	1.2	<b>Eulering involving higher order derivatives:</b> Payloigh Ditz method	
2.0	2.0	Linear Algebra: Vostor, spaces	12
2.0	2.0	Linear Algebra: Vector spaces	14
	2.1	distance properties in n dimensional vector space. properties, dot product, norm and	
	2.2	distance properties in n-dimensional vector space.	
	2.2	Metric spaces, vector spaces over real field, properties of vector spaces over real	
	2.2	Nerros and nerrod vestor anges	
	2.3	Norms and normed vector spaces	
	2.4	Inner products and inner product spaces	
2.0	2.5	The Cauchy-Schwarz inequality, Orthogonal Subspaces, Gram-Schmidt process	1 =
3.0	3.0	Linear Algebra: Matrix Theory	15
	3.1	Characteristic equation, Eigen values and Eigen vectors, properties of Eigen	
		values and Eigen vectors	
	3.2	Cayley-Hamilton theorem, examples based on verification of Cayley-Hamilton	
		theorem	
	3.3	Similarity of matrices, Diagonalisation of matrix	
	3.4	Functions of square matrix, derogatory and non-derogatory matrices	
	3.5	Quadratic forms over real field, reduction of Quadratic form to a diagonal	
		canonical form, rank, index, signature of quadratic form, Sylvester's law of	
		inertia, value-class of a quadratic form of definite, semi- definite and indefinite	
	3.6	Singular Value Decomposition	
4.0	4.0	Complex Variables: Integration	15
	4.1	<b>Complex Integration:</b> Line Integral, Cauchy's Integral theorem for simply	
		connected regions, Cauchy's Integral formula	
	4.2	Taylor's and Laurent's series	
	4.3	Zeros, singularities, poles of f(z), residues, Cauchy's Residue theorem	
	4.4	Applications of Residue theorem to evaluate real Integrals of	
		$\int_{0}^{2\Pi} \mathcal{L}(x) dx = \int_{0}^{\infty} \mathcal{L}(x) dx$	
		$\int \int f(x) dx$ and $\int \int f(x) dx$	
		0 -∞ Totel	52
		1 Utal	J4

## **Recommended books:**

- 1. *A Text Book of Applied Mathematics* Vol. I & II by P.N.Wartilar & J.N.Wartikar, Pune, Vidyarthi Griha Prakashan., Pune
- 2. Mathematical Methods in science and Engineering, A Datta (2012)
- 3. Higher Engg. Mathematics by Dr. B.S. Grewal, Khanna Publication
- 4. Todd K.Moon and Wynn C. Stirling, *Mathematical Methods and algorithms for Signal Processing*, Pearson Education..
- 5. Kreyszig E., Advanced Engineering Mathematics, 9<sup>th</sup> edition, John Wiley, 2006.
- 6. *Linear Algebra* Hoffman & Kunze (Indian editions) 2002
- 7. Linear Algebra Anton & Torres(2012) 9<sup>th</sup> Indian Edition.
- 8. *Complex Analysis* Schaum Series.

## Internal Assessment (IA):

Two tests must be conducted which should cover at least 80% of syllabus. The average marks of both the test will be considered as final IA marks

#### **End Semester Examination:**

- 1. Question paper will comprise of 6 questions, each carrying 20 marks.
- 2. The students need to solve total 4 questions.
- 3: Question No.1 will be compulsory and based on entire syllabus.
- 4: Remaining questions (Q.2 to Q.6) will be set on all the modules.
- 5: Weightage of marks will be as per Blueprint.

#### Term Work:

At least **08** assignments covering entire syllabus must be given during the **Class Wise Tutorial.** The assignments should be students' centric and an attempt should be made to make assignments more meaningful, interesting and innovative. Term work assessment must be based on the **overall performance** of the student with **every assignment graded from time to time.** The grades should be converted into marks as per the **Credit and Grading System** manual and should be **added and averaged**. The grading and term work assessment should be done based on this scheme.

Subject Code	Subject Name	Teacl	ning Scheme	Credits Assigned				
		Theory	Pract.	Tut.	Theory	TW/Pract.	Tut.	Total
EXC 402	Discrete Electronic Circuits	04		-	04		-	04

	Subject Name	Examina	ation Sche	eme					
C1-		Theory	Pract.	Oral	Total				
Sub. Code		Internal Assessment End							
EXC 402	Discrete Electronic	Test 1	Test 2	Average of Test1 & Test2	Exam				
	Circuits	20	20	20	80				100

# **Prerequisite: FEC105 Basic Electrical & Electronics Engineering and EXC 302 Electronic Devices Course Objectives:**

- 1. To understand DC biasing needed for various applications.
- 2. To understand DC and AC models of semiconductor devices and usefulness of the devices for various applications like amplifiers, oscillators etc..
- 3. To apply concepts of DC and AC modeling of semiconductor devices for the design and analysis.
- 4. To understand theoretical concepts and verify through laboratory and simulation experiments.
- 5. To deliver the core concepts and reinforce the analytical skills learned in Electronic Devices
- 6. To motivate students to use MOS devices for designing and analyzing electronic circuits which will help them to understand the fundamentals required for further part of Engineering

# **Course Outcome:**

- 1. Students will be able to understand and the usefulness of semiconductor devices in circuit making.
- 2. Students will be Able to perform dc and ac analysis of the basic electronic circuits useful to conclude an application based on these.
- 3. They will be able to analyze and design multistage electronic circuits.
- 4. Mainly understanding of discrete and integrated biasing will be understood and very useful for mixed mode designs..
- 5. They will understand the difference between small signal and large signal amplifiers.
- 6. They will be able to use these basic circuits to develop various useful applications.

Module No.	Topics	Hrs.
1.0	Bipolar device based circuit analysis	08
1.1	<b>Review of Diode Based circuits:</b> Analytical analysis of Single level clippers, Double level Clippers and clampers (both only explanation, no analytical analysis)	
1.2	<b>DC Circuit Analysis of BJT:</b> DC load line and region of Operation, Common Bipolar Transistor Configurations, Single base resistor biasing, voltage divider biasing and bias stability, Analysis and Design of biasing circuits	
1.3	AC Analysis of BJT Amplifiers: Bipolar Junction Transistor (BJT): Graphical Analysis and AC Equivalents Circuits, Small Signal hybrid-pi model (no other models), early effect, Common-Emitter Amplifiers, Common-Collector Amplifiers, Common-Base Amplifiers.	
2	Field Effect devices based circuit analysis	10
2.1	<ul> <li>DC Circuit Analysis:</li> <li>Junction Field Effect Transistor (JFET): Self bias, Voltage divider bias, Design and Analysis of Biasing Circuits</li> <li>Metal-Oxide Field Effect Transistor (MOSFET): Common-Source circuits, DC load line and region of operation, Common-MOSFETs configurations, Analysis and Design of Biasing Circuits</li> <li>AC Analysis:</li> <li>JFET Amplifiers: Small-Signal Equivalent Circuit, Small-Signal Analysis</li> <li>MOSFET Amplifiers: Graphical Analysis, load line and Small-Signal parameters, AC Equivalent Circuit, Small-Signal Model. Common-Source, Source Follower, Common- Gate</li> </ul>	
3.0	Multistage analysis and Frequency Analysis of Amplifiers	10
3.1	Multistage (CS-CS), (CS-CE) cascode (CS-CG) Amplifiers & Darlington pair.	
3.2	Effect of capacitors (coupling, bypass, load) on frequency response of JFET and MOSFET Amplifiers, High frequency hybrid-pi equivalent circuits of MOSFET, Miller Effect and Miller capacitance, unity gain bandwidth, Low and high frequency response of single stage (CS,CG, CD) and multistage (CS-CS).	
4.0	Feedback Amplifiers and Oscillators	08
4.1	Types of Negative Feedback, block diagram representation, Effect of negative feedback on Input impedance, Output impedance, Gain and Bandwidth with derivation, feedback topologies (analysis of different feedback circuits is not expected).	
4.2	Positive feedback and principle of oscillations, RC oscillators: Phase shift (no derivations), Wien bridge, LC Oscillators: Hartley, Colpitts and clapp, Tunned Oscillator (no derivations), Twin T Oscillator (no derivations), Crystal Oscillator (BJT circuits analysis).	
5.0	Differential Amplifiers	10
5.1	<b>BJT Differential Amplifier:</b> Terminology and qualitative description, DC transfer characteristics, Small signal Analysis, differential and common mode gain, CMRR,	

	differential and common mode input impedance.	
5.2	<b>MOSFET Differential Amplifiers:</b> DC Transfer characteristics, Small signal Analysis, differential and common mode gain, CMRR, differential and common mode input impedance.	
5.3	<b>Constant Current Sources:</b> Two transistor (BJT, MOSFET) current source, current relationship, output resistance. Improved three transistor (BJT, MOSFET) current source, Cascode (BJT, MOSFET) current source, Wilson and Widlar current source	
6.0	Power Amplifiers	06
6.1	Power BJTs, Power MOSFETs, Heat Sinks, Class A, Class B, Class C and Class AB operation, Power efficiency, Class AB output stage with diode biasing, VBE multiplier biasing, input buffer transistors, Darlington configuration.	
	Total	52

# **Recommended Books:**

- 1. Donald A. Neamen, "Electronic Circuit Analysis and Design", TATA McGraw Hill, 2<sup>nd</sup> Edition
- 2. Adel S. Sedra, Kenneth C. Smith and Arun N Chandorkar," *Microelectronic Circuits Theory and Applications*", International Version, OXFORD International Students Edition, Fifth Edition.
- 3. David A. Bell, "Electronic Devices and Circuits", Oxford, Fifth Edition.
- 4. S. Salivahanan, N. Suresh Kumar, "*Electronic Devices and Circuits*", Tata McGraw Hill, 3<sup>rd</sup> Edition
- 5. Jacob Millman, Christos C Halkias, and Satyabratata TIT, "Millman's Electronic Devices and Circuits", McGrawHill, 3<sup>rd</sup> Edition
- 6. Muhammad H. Rashid, "*Microelectronics Circuits Analysis and Design*", Cengage Learning, 2<sup>nd</sup> Edition

## 7. Jacob Millman and Arvin Grabel, "Mircroelectronics", Tata McGraw-Hill Second Edition

# Internal Assessment (IA):

Two tests must be conducted which should cover at least 80% of syllabus. The average marks of both the test will be considered as final IA marks

- 1. Question paper will comprise of 6 questions, each carrying 20 marks.
- 2. The students need to solve total 4 questions.
- 3: Question No.1 will be compulsory and based on entire syllabus.
- 4: Remaining question (Q.2 to Q.6) will be set from all the modules.
- 5: Weightage of marks will be as per Blueprint.

Subject Code	Subject Name	Те	aching Sche	eme	Credits Assigned			
		Theory	Practical	Tutorial	Theory	TW	Tutorial	Total
EXC 403	Microprocessor and	04			04			04
	Peripherals							

Subject	Subject Name		Examination Scheme								
Code			Т	heory Marks		Term	Practical	Oral	Total		
		Internal assessment			End	Work	and				
		Test	Test	Ave. Of Test	Sem.		Oral				
		1	2	1 and Test 2	Exam						
EXC 403	Microprocessor and	20	20	20	80			-	100		
	Peripherals										

## **Course Objective:**

To create a strong foundation by studying the basics of Microprocessors and interfacing to various peripherals which will lead to a well designed Microprocessor based System. The course is a pre-requisite for all further courses in Microcontrollers and Embedded systems.

Course Outcome:

- 1. Students will be able to understand and design Microprocessor based systems.
- 2. Students will be able to understand assembly language programming
- 3. Students will be able to learn and understand concept of interfacing of peripheral devices and their applications

Module No.	Topics	Hrs.			
	Introduction to Intel 8085 Microprocessor: Basic functions of the				
1	microprocessor, System bus, Architecture, Pin Configuration and	06			
	Programmer's model of Intel 8085 Microprocessor.				
	Intel 8086 Architecture: Major features of 8086 processor, 8086/88				
2	CPU Architecture and the pipelined operation, Programmer's Model	06			
	and Memory Segmentation				
	Instruction Set of 8086 and Programming: Instruction Set of				
	8086 microprocessor in details, Addressing modes of 8086/88,				
3	Programming the 8086 in assembly language, Mixed mode	10			
	Programming with C-language and assembly language. Assembler				
	Directives Procedures and Macros.				
4	<b>8086 Interrupts:</b> Interrupt types in 8086, Dedicated interrupts, Software	04			
	interrupts,	01			
	<b>Designing the 8086 CPU module:</b> 8086 pin description in details,				
5	Generating the 8086 System Clock and Reset Signals, 8086	10			
5	Minimum and Maximum Mode CPU Modules, Memory interfacing with	10			
	timing consideration, Minimum and Maximum Mode Timing Diagrams				
	Peripheral Controllers for 8086 family and System Design:				
	Functional Block Diagram and description, Control Word Formats,				
6	Operating Modes and Applications of the Peripheral Controller	08			
Ũ	namely 8255-PPI, , 8259- PIC and 8237-DMAC.	00			
	Interfacing of the above Peripheral Controllers. Keyword and				
	Display Interface using 8255.				
	Multiprocessor Systems:				
_	Study of Multiprocessor Configurations namely Closely Coupled	0.0			
7	System (CCS) and Loosely Coupled System (LCS), CCS with the	08			
	case study of the Maths Coprocessor, Various System Bus Arbitration				
	Schemes in LCS, and Role of the Bus Arbiter (Intel 8289) in the LCS.				
	Total	52			

## **Recommended Books:**

1) Microprocessor architecture and applications with 8085: By Ramesh Gaonkar (Penram International Publication).

2) 8086/8088 family: Design Programming and Interfacing: By John Uffenbeck (Pearson Education).

3) 8086 Microprocessor Programming and Interfacing the PC: By Kenneth Ayala

4) Microcomputer Systems: 8086/8088 family Architecture, Programming and Design: ByLiu & Gibson (PHI Publication).

5) Microprocessor and Interfacing: By Douglas Hall (TMH Publication).

## **Internal Assessment (IA):**

Two tests must be conducted which should cover at least 80% of syllabus. The average marks of both the test will be considered as final IA marks

- 1. Question paper will comprise of 6 questions, each carrying 20 marks.
- 2. The students need to solve total 4 questions.
- 3: Question No.1 will be compulsory and based on entire syllabus.
- 4: Remaining question (Q.2 to Q.6) will be set from all the modules.
- 5: Weightage of marks will be as per Blueprint.

Subject Code	Subject Name	Te	eaching Sche	eme	Credits Assigned				
		Theory	Practical	Tutorial	Theory	TW/	Tutorial	Total	
		-			-	Practical			
EXC	Principles of	04			04			04	
404	Control								
	Systems								

Subject	Subject Name		Examination Scheme									
Code			T	neory Marks		Term	Practical	Oral	Total			
		Int	Internal assessment End									
		Test	Test	Ave. Of	Sem.							
		1	2	Test 1 and	Exam							
				Test 2								
EXC	Principles of	20	20	20	80		-		100			
404	Control Systems											

# **Prerequisite Topics:**

Differential equations; Laplace transforms and Matrices.

## **Course Objectives:**

Objectives of this course are:

- 1. To study the fundamental concepts of Control systems and mathematical modeling of the system.
- 2. To study the concept of time response and frequency response of the system.
- 3. To study the basics of stability analysis of the system and design of simple controllers

## **Course Outcome:**

- 1. Students will be able to derive the mathematical model of different type of the systems.
- 2. Students will understand the basic concepts of control system.
- 3. Students will understand the analysis of systems in time and frequency domain.
- 4. Students will be able to apply the control theory to design the conventional PID controller widely used in the industries.

No.         Introduction to control system analysis         Introduction: Open loop and closed loop systems; feedback and feedforward control structure; examples of control systems.         06           1.         Introduction: Open loop and closed loop systems; feedback and feedforward control structure; examples of control systems.         06           1.3         Dynamic Response: Standard test signals; Transient and steady state behavior of first and second order systems; Steady state errors in feedback control systems and their types.         06           2         Mathematical modeling of systems         02           2.1         Transfer function models of various systems: Models of mechanical systems; Models of electrical systems; Models of thermal systems.         08           2.2         Mainputations: Block diagram reduction; Signal flow graph and the Mason's gain rule.         08           3.1         State variable models of various systems; State variable models of mechanical systems; State variable models of electrical systems; State variable models of mechanical systems; State variable models of electrical systems; State variable models of state transition matrix; Properties of state transition equation: Concept of state transition matrix; Properties of state transition equation: Concept of observability; Controllability analysis in LTI systems using Kalman approach.         12           4         Aconcept of Stability: Concept of absolute, relative and robust stability; Routo-locus: Root-locus analysis: Root-locus concepts; General rules for constructing root-locus; Root-locus analysis of control systems.         12	Module	Topics	Hrs.					
Introduction to control system analysis         1.1 Introduction: Open loop and closed loop systems; feedback and feedforward control structure; examples of control systems.         06           1.         I.Z Modeling: Types of models; Impulse response model; State variable model; Transfer function model.         06           1.3 Dynamic Response: Standard test signals; Transient and steady state behavior of first and second order systems; Steady state errors in feedback control systems and their types.         06           2         Mathematical modeling of systems         04           2.1 Transfer function models of various systems: Models of mechanical systems; Models of electrical systems; Models of thermal systems.         08           2.3 Mathematical models         State Variable Models         08           3.1 State variable models of various systems: State variable models of mechanical systems; Solution of non-homogeneous systems.         08           3         3.2 State transition equation: Concept of state transition matrix; Properties of state transition matrix; Solution of non-homogeneous systems.         12           4         1.1 Concept of Stability: Concept of controllability: Controllability analysis in time domain         14           4         1.1 expects of Stability: Concept of absolute, relative and robust stability: Routh stability criterion.         06           5         Stability analysis in frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stabilit	No.							
1.1 Introduction: Open loop and closed loop systems; feedback and feedforward control structure; examples of control systems.       06         1.2 Modeling: Types of models; Impulse response model; State variable model; Transfer function model.       06         1.3 Dynamic Response: Standard test signals; Transient and steady state behavior of first and second order systems; Steady state errors in feedback control systems and their types.       08         2.1 Transfer function models of various systems: Models of mechanical systems; Models of electrical systems; Models of thermal systems.       08         2.2 Manipulations: Block diagram reduction; Signal flow graph and the Mason's gain rule.       08         3.1 State variable models of various systems: State variable models of mechanical systems; State variable models of electrical systems; State variable models of thermal systems.       12         3.3 Controllability and observability: Concept of controllability; Controllability analysis of LTI systems; Concept of observability; Observability; analysis of LTI systems using Kalman approach.       06         4 A2 Root locus analysis: Root-locus concepts; General rules for constructing root-locus; Root-locus analysis of control systems.       06         5 Stability analysis in frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specifications; Nyquist plot; Gain and phase margins.       10         6 Gompensators and controllers       6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator; Lead compensator; Lead compensator; Lead compensator; Lead com		Introduction to control system analysis						
1.2 Modeling: Types of models; Inpulse response model; State variable model;       06         1.3 Dynamic Response: Standard test signals; Transient and steady state behavior of first and second order systems; Steady state errors in feedback control systems and their types.       06         2.1 Transfer function models of various systems: Models of mechanical systems; Models of electrical systems; Models of thermal systems.       08         2 systems; Models of electrical systems: Models of thermal systems.       08         3 State Variable Models       03.1 State variable models of various systems: State variable models of mechanical systems; State variable models of electrical systems; State variable models of mechanical systems; State variable models of thermal systems.       08         3 3.2 State transition equation: Concept of state transition matrix; Properties of state transition matrix; Solution of homogeneous systems; solution of non-homogeneous systems; State variable models of electrical systems using Kalman approach.       12         4 Rout hocus analysis of LTI systems; Concept of observability; Controllability analysis in time domain       06         4 1. Concepts of Stability: Concept of absolute, relative and robust stability; Routh stability criterion.       06         5 Stability analysis in frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability analysis tability criterions; Nyquist plot; Gain		<b>1.1 Introduction:</b> Open loop and closed loop systems; feedback and						
1.       1.2 Modeling: Types of models; impulse response model; State vanable model; Transfer function model.       06         1.3 Dynamic Response: Standard test signals; Transient and steady state behavior of first and second order systems; Steady state errors in feedback control systems and their types.       08         2       Systems; Models of electrical systems; Models of memal systems.       08         2.1 Transfer function models of various systems: Models of mechanical systems; Models of electrical systems; Models of thermal systems.       08         3.1 State variable models of various systems: State variable models of mechanical systems; State variable models of electrical systems; State variable models of thermal systems.       12         3       3.2 State transition equation: Concept of state transition matrix; Properties of state transition matrix; Solution of homogeneous systems; solution of non- homogeneous systems.       12         3.3 Controllability and observability: Concept of controllability; controllability analysis of LTI systems; Concept of observability; Controllability analysis of Stability: Concept of absolute, relative and robust stability; Routh stability criterion.       06         4       Rout locus analysis: Root-locus concepts; General rules for constructing root-locus; Root-locus analysis of control systems.       10         5       Stability analysis in frequency domain specification of system; Stability margins.       10         5       Stability margins on the Bode plots; Stability analysis using Bode plot. Stability margins on the Bode plots; Stability analysis using Bode plot. S		feedforward control structure; examples of control systems.						
1.3 Dynamic Response: Standard test signals; Transient and steady state behavior of first and second order systems; Steady state errors in feedback control systems and their types.       Mathematical modeling of systems       08         2       Systems; Models of electrical systems; Models of thermal systems.       08         2.1 Transfer function models of various systems: Models of mechanical systems; Models of electrical systems.       08         2.2 Manipulations: Block diagram reduction; Signal flow graph and the Mason's gain rule.       08         3 State Variable Models       3.1 State variable models of various systems: State variable models of mechanical systems; State variable models of electrical systems; State variable models of thermal systems.       08         3 3 3 State transition equation: Concept of state transition matrix; Properties of state transition matrix; Solution of homogeneous systems: Solution of nonhomogeneous systems.       12         3 3 Controllability and observability: Concept of controllability; Controllability; analysis of LTI systems; Concept of observability; Observability; malysis of LTI systems using Kalman approach.       10         4 Rout hability criterion.       06         5 3 Stability analysis in frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability margins.       10         5 3 Stability analysis in frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability margins.       10 <td>1.</td> <td><b>1.2 Modeling:</b> Types of models; Impulse response model; State variable model;</td> <td>06</td>	1.	<b>1.2 Modeling:</b> Types of models; Impulse response model; State variable model;	06					
1.3 Dynamic Response: Standard test signals; Franstein and steady state behavior of first and second order systems; Steady state errors in feedback control systems and their types.       Mathematical modeling of systems       08         2       3.1 Transfer function models of various systems: Models of mechanical systems; Models of electrical systems; Models of thermal systems.       08         2       3.1 Transfer function models of various systems: Models of mechanical systems; Models of electrical systems; Models of thermal systems.       08         3       3.1 State variable models of various systems: State variable models of mechanical systems; State variable models of electrical systems; State variable models of thermal systems.       08         3       3.1 State variable models of various systems; solution of nonhomogeneous systems.       12         3       3.2 State transition equation: Concept of state transition matrix; Properties of state transition matrix; Solution of nonhomogeneous systems.       12         3.3       Controllability and observability: Concept of controllability; Controllability; analysis in time domain       12         4       A.1 Concepts of Stability: Concept of absolute, relative and robust stability; Routh stability; criterion.       06         5       Stability analysis in trequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability margins.       10         5       Stability analysis or foreup plots, Nyquist stability; criterions; Nyquist plot; Gain a		Transfer function model.						
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3          3.2 State transition equation: Concept of state transition matrix; Properties of state transition matrix; Solution of homogeneous systems; solution of non-homogeneous systems.           3.3 Controllability and observability: Concept of controllability; Controllability analysis of LTI systems; Concept of observability; Observability analysis of LTI systems; Concept of observability; Observability; analysis of LTI systems; Concept of absolute, relative and robust stability; Routh stability criterion.           06          4 <b>Stability analysis in time domain</b> 06           4 <b>Stability analysis:</b> Root-locus concepts; General rules for constructing root-locus; Root-locus analysis: of control systems.             5               5               6               6               6               6             7             8             9             9             9 </td <td></td> <td>3.1 State variable models of various systems: State variable models of</td> <td></td>		3.1 State variable models of various systems: State variable models of						
3       models of thermal systems.       12         3       3.2 State transition equation: Concept of state transition matrix; Properties of state transition matrix; Solution of homogeneous systems; solution of non-homogeneous systems.       12         3.3       Controllability and observability: Concept of controllability; Controllability; analysis of LTI systems; Concept of observability; Observability analysis of LTI systems using Kalman approach.       12         4       Stability analysis in time domain       4.1 Concepts of Stability: Concept of absolute, relative and robust stability; Routh stability criterion.       06         4.2       Root locus analysis: Root-locus concepts; General rules for constructing root-locus; Root-locus analysis of control systems.       06         5       Stability analysis in frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability margins.       10         5       S.2 Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.       10         6       6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6       6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       10		mechanical systems; State variable models of electrical systems; State variable						
3       3.2 State transition equation: Concept of state transition matrix; Properties of state transition matrix; Solution of homogeneous systems; solution of non-homogeneous systems.       12         3.3       Controllability and observability: Concept of controllability; Controllability; analysis of LTI systems; Concept of observability; Observability analysis of LTI systems using Kalman approach.       12         4       Stability analysis in time domain       4.1 Concepts of Stability: Concept of absolute, relative and robust stability; Routh stability criterion.       06         4.2 Root locus analysis: Root-locus concepts; General rules for constructing root-locus; Root-locus analysis of control systems.       06         5       Stability analysis in frequency domain       10         5.1 Introduction: Frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability margins.       10         5.2 Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.       10         6       6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6       6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       10		models of thermal systems.						
5       state transition matrix; Solution of homogeneous systems; solution of non-homogeneous systems.       12         3.3       Controllability and observability: Concept of controllability; Controllability analysis of LTI systems; Concept of observability; Observability analysis of LTI systems using Kalman approach.       12         4       Stability analysis in time domain       4         4.1       Concepts of Stability: Concept of absolute, relative and robust stability; Routh stability criterion.       06         4.2       Root locus analysis: Root-locus concepts; General rules for constructing root-locus; Root-locus analysis of control systems.       06         5       Stability analysis in frequency domain       06         5.1       Introduction: Frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability margins.       10         5       5.2       Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins.       10         6       6.1       Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2       Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6       6.3       Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       10	3	<b>3.2 State transition equation:</b> Concept of state transition matrix; Properties of	12					
homogeneous systems.         3.3       Controllability and observability: Concept of controllability; Controllability analysis of LTI systems; Concept of observability; Observability analysis of LTI systems using Kalman approach.         Stability analysis in time domain       4.1         4.1       Concepts of Stability: Concept of absolute, relative and robust stability; Routh stability criterion.       06         4.2       Root locus analysis: Root-locus concepts; General rules for constructing root-locus; Root-locus analysis of control systems.       06         5       Stability analysis in frequency domain specification of system; Stability margins.       10         5.2       Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.       10         5.3       Nyquist Criterion: Polar plots, Nyquist stability criterions; Nyquist plot; Gain and phase margins.       10         6       6.1       Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.3       Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       10	5	state transition matrix; Solution of homogeneous systems; solution of non-	12					
3.3 Controllability and observability: Concept of controllability;         Controllability analysis of LTI systems; Concept of observability;         analysis of LTI systems using Kalman approach.         Stability analysis in time domain         4.1 Concepts of Stability: Concept of absolute, relative and robust stability;         Routh stability criterion.         4.2 Root locus analysis: Root-locus concepts; General rules for constructing root-locus; Root-locus analysis of control systems.         5         Stability analysis in frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability margins.         5.2 Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.         5.3 Nyquist Criterion: Polar plots, Nyquist stability criterions; Nyquist plot; Gain and phase margins.         Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.         6         6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.		homogeneous systems.						
Controllability analysis of LTI systems; Concept of observability; Observability analysis of LTI systems using Kalman approach.       Stability analysis in time domain         4       Stability analysis in time domain       4.1 Concepts of Stability: Concept of absolute, relative and robust stability; Routh stability criterion.       06         4.1 Concepts of Stability: Concept of absolute, relative and robust stability; Routh stability criterion.       06         4.2 Root locus analysis: Root-locus concepts; General rules for constructing root-locus; Root-locus analysis of control systems.       06         5 Stability analysis in frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability margins.       10         5 S.2 Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.       10         6 Compensators and controllers       6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6 G.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       Total		<b>3.3 Controllability and observability:</b> Concept of controllability;						
analysis of L11 systems using Kalman approach.       Stability analysis in time domain         4       Stability analysis in time domain       06         4       A.1 Concepts of Stability: Concept of absolute, relative and robust stability; Routh stability criterion.       06         4       Root locus analysis: Root-locus concepts; General rules for constructing root-locus; Root-locus analysis of control systems.       06         5       Stability analysis in frequency domain specification of system; Stability margins.       10         5       S.2 Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.       10         5.3 Nyquist Criterion: Polar plots, Nyquist stability criterions; Nyquist plot; Gain and phase margins.       10         6       6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       10		Controllability analysis of LTI systems; Concept of observability; Observability analysis of LTI systems using Kalman approach						
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Stability analysis of control systems.         Stability analysis in frequency domain         5.1 Introduction: Frequency domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability margins.       10         5       5.2 Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.       10         5.3 Nyquist Criterion: Polar plots, Nyquist stability criterions; Nyquist plot; Gain and phase margins.       10         6       Compensators and controllers       10         6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       Total		root-locus: Root-locus analysis. Root-locus concepts, General rules for constructing						
5       Stability margins in requercy domain specifications, Response peak and peak resonating frequency; Relationship between time and frequency domain specification of system; Stability margins.       10         5       5.2 Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.       10         5.3 Nyquist Criterion: Polar plots, Nyquist stability criterions; Nyquist plot; Gain and phase margins.       10         6       Compensators and controllers       10         6       6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       Tatal		Stability analysis in frequency domain						
5       For indication interpreting between time and frequency domain specification of system; Stability margins.       10         5       5.2 Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.       10         5.3 Nyquist Criterion: Polar plots, Nyquist stability criterions; Nyquist plot; Gain and phase margins.       10         6       Compensators and controllers       10         6       6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       Total		<b>5.1 Introduction</b> : Frequency domain specifications. Response peak and peak						
5       specification of system; Stability margins.       10         5       5.2 Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.       10         5.3 Nyquist Criterion: Polar plots, Nyquist stability criterions; Nyquist plot; Gain and phase margins.       10         6       Compensators and controllers       10         6       6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       Tatal       52		resonating frequency; Relationship between time and frequency domain						
5       5.2 Bode plot: Magnitude and phase plot; Method of plotting Bode plot; Stability margins on the Bode plots; Stability analysis using Bode plot.       10         5.3 Nyquist Criterion: Polar plots, Nyquist stability criterions; Nyquist plot; Gain and phase margins.       5.3 Nyquist Criterion: Polar plots, Nyquist stability criterions; Nyquist plot; Gain and phase margins.       10         6       6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       Total	~	specification of system; Stability margins.	10					
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5.3 Nyquist Criterion: Polar plots, Nyquist stability criterions; Nyquist plot; Gain and phase margins.         Compensators and controllers         6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.         10         6         6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.		Stability margins on the Bode plots; Stability analysis using Bode plot.						
Gain and phase margins.         Compensators and controllers         6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.         10         6         6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.		<b>5.3 Nyquist Criterion:</b> Polar plots, Nyquist stability criterions; Nyquist plot;						
Compensators and controllers         6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       Total       52		Gain and phase margins.						
6.1 Compensators: Types of compensation; Need of compensation; Lag compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       Total		Compensators and controllers						
6       compensator; Lead compensator.       10         6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.       10         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.       10		6.1 Compensators: Types of compensation; Need of compensation; Lag						
6       6.2 Controllers: Concept of ON/OFF controllers; Concept of P, PI, PD and PID Controllers.         6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.	-	compensator; Lead compensator.						
6.3 Advances in Control Systems: Introduction to Robust Control, Adaptive control and Model predictive control.      Total	6	<b>6.2 Controllers:</b> Concept of ON/OFF controllers; Concept of P, PI, PD and DID Controllers						
control and Model predictive control.		PID Controllers.						
Total 52		control and Model predictive control						
			<mark>52</mark>					

## **Recommended Books**

- 1. I. J. Nagrath, M. Gopal, Control Systems Engineering, New Age International, Fifth Edition, 2012.
- 2 Dhanesh N. Manik, Control Systems, Cengage Learning, First Edition, 2012.
- 3. M. Gopal, Control Systems: Principle and design, Tata McGraw Hill, First Edition, 1998
- 4. Richard C. Dorf and Robert H. Bishop, Modern Control System, Pearson, Eleventh Edition, 2013.
- 5. Norman S. Nice, Control Systems Engineering, John Wiley and Sons, Fifth Edition, 2010
- 6. Rajeev Gupta, Control Systems Engineering, Wiley India, First Edition, 2011.

#### **Internal Assessment (IA):**

Two tests must be conducted which should cover at least 80% of syllabus. The average marks of both the test will be considered as final IA marks

- 1. Question paper will comprise of 6 questions, each carrying 20 marks.
- 2. The students need to solve total 4 questions.
- 3: Question No.1 will be compulsory and based on entire syllabus.
- 4: Remaining question (Q.2 to Q.6) will be set from all the modules.
- 5: Weightage of marks will be as per Blueprint.

Subject Code	Subject Name	Teaching Scheme			Credits Assigned			
		Theory	Practical	Tutorial	Theory	Practical	Tutorial	Total
EXC	Fundamentals of	04			04			04
405	Communication							
	Engineering							

Subject	Subject Name				Examination	Scheme			
Code			,	Theory Marks		Term	Practical	Oral	Total
		Ir	nternal a	assessment	End Sem.	Work	And Oral		
		Tes	Test   Ave. Of		Exam				
		t 1	t1 2 Test 1 and						
				Test 2					
EXC	Fundamentals of	20	20	20	80				100
405	Communication								
	Engineering								

Prerequisite Topics: Basic Electronic Devices and Circuits and measurements

**Course Objective:** 

- 1. To understand basics of wireless communication systems.
- 2. To understand modulation and demodulation techniques.
- 3. To understand working of transmitters and receivers
- 4. To understand the basic concept of Digital communication

**Course Outcome:** 

- 1. Students will be able to understand the components of wireless communication systems
- 2. Students will be able to understand various modulation techniques and their applications
- 3. Students will be able to understand difference between analog and digital communication

Module	Unit	Topics	Hrs.
No.	No.		
1.0		Elements of Communication System :	08
	1.1	Electromagnetic Waves Propagation: Maxwell's equations for static and time	
		varying fields, wave equation for free space and dielectric mediums, propagation	
		terms and definition, electromagnetic frequency spectrum,	
	1.2	Basic communication system: Block diagram representation	
	1.3	Concept of Modulation and Demodulation: Signal representation, noise in	
		communication signals and channels, signal-to-noise ratio, noise factor and noise	
		figure, equivalent noise temperature	
2.0		Amplitude Modulation	10
	2.1	Principles of DSB Full Carrier AM	
	2.2	Different types of AM : DSB-SC , SSB-SC , VSB, ISB	
	2.3	Practical diode detector	
3.0		Angle modulation	10
	3.1	Principles of Frequency Modulation and Phase Modulation	
	3.2	FM Modulators: Narrow band FM and wide band FM, FM transmitter, noise	
		triangle, Pre-emphasis and De-emphasis circuits	
	3.3	FM Detection: frequency discriminator and phase discriminator	
4.0		Radio Receivers	06
	4.1	Receiver Characteristics, TRF Receivers, and Super heterodyne, Receivers,	
		Choice of IF, AGC, AFC in AM and FM receivers	
5.0		Analog Pulse Modulation	08
	5.1	Sampling: Theorem, aliasing error and sampling techniques	
	5.2	Demodulation and spectrum of PAM, PWM, PPM	
6.0		Digital Pulse Modulation(only concepts and no numerical problems)	10
	6.1	Comparison of digital signal transmission and analog signal transmission	
	6.2	Pulse- code modulation (PCM) : sampling ,quantizing ,encoding technique, PCM bandwidth	
	6.3	Concept of Delta modulation (DM) and Adaptive Delta Modulation(ADM)	
	6.4	Multiplexing: TDM, FDM- Principles & applications	
		Total	52

## **Recommended Books:**

- 1. Wayne Tomasi "Electronics communication systems" Pearson education, Third edition, 2001.
- 2. Kennedy and Davis "Electronics communication system", Tata McGraw Hill
- 3. R.P. Sing and S.D. Sapre, "Communication systems Analog and Digital", Tata McGraw Hill
- 4. Taub and Schilling "Principles of communication systems", Tata McGraw Hill
- 5. Roy Blake, "Electronics communication system", Thomson learning, second edition.
- 6. B.P. Lathi "Modern Digital and analog Communication system" Third edition, OXFORD
- 7. Robert J. Schoenbeck "Electronics communications modulation and transmission".
- 8. Lean W couch "Digital and Analog communication system", Pearson education, Sixth edition.
- 9. Roddy Coolen, "Electronic Communications" PHI

## Term Work<mark>:</mark>

At least 10 experiments based on the entire syllabus should be set to have well predefined inference and conclusion. The experiments should be students' centric and attempt should be made to make experiments more meaningful, interesting and innovative. Term work assessment must be based on the **overall performance** of the student with **every experiment graded from time to time.** The grades should be converted into marks as per the **Credit and Grading System** manual and should be **added and averaged**. The grading and term work assessment should be done based on this scheme.

#### Internal Assessment (IA):

Two tests must be conducted which should cover at least 80% of syllabus. The average marks of both the test will be considered as final IA marks

- 1. Question paper will comprise of 6 questions, each carrying 20 marks.
- 2. The students need to solve total 4 questions.
- 3: Question No.1 will be compulsory and based on entire syllabus.
- 4: Remaining question (Q.2 to Q.6) will be selected from all the modules.
- 5: Weightage of marks will be as per Blueprint.

Subject Code	Subject Name	Teach	ning Schem	e (Hrs)		Credits A	Credits Assigned Practical Tutorial To 0		
		Theory	Practical	Tutorial	Theory	Practical	Tutorial	Total	
EXC 406	Electrical	3			3			03	
	Machines								

Subject	Subject Name		Examination Scheme								
Code			Т	heory Marks		Term	Practical	Oral	Total		
		Inte	Internal assessment End Sem.								
		Test 1	est 1 Test Ave. Of Exam								
			2 Test 1 and								
				Test 2							
EXC 406	Electrical	15	15	15	60		-	_	75		
	Machines										

Course Objective: To understand performance, working of Electrical Machines and their characteristics etc.

**Expected Outcome:** 

- 5. Students will be able to understand electrical motors and their working principles
- 6. Students will be able to understand brushless drives
- 7. Students will be able to understand special types of motors such as stepper motor and applications

Module	Unit	Contents	Hrs.
No.	No.		
1.0		DC Machines	08
	1.1	Construction: principle of working, MMF and flux density waveforms,	
		significance of commutator and brushes in DC machine,	
	1.2	EMF equation: and Torque equation, characteristics of DC Motors,	
	1.3	Starters for shunt and series motors	
	1.4	Speed Control (Armature voltage control and field control using block diagrams)	
2.0		Three phase Induction Motor	08
	2.1	Construction: Working principle of squirrel cage induction motor,	
	2.2	Equivalent circuit: Equivalent circuit development, torque speed characteristics,	
		power stages, no load and blocked rotor test	
	2.3	Speed control: Classify different methods, stator voltage control using Triac,	
		V/f control using converter inverter scheme (only block diagram)	
	2.4	Starting methods: Classification and working of different methods, high torque	
		motors	
3.0		Single phase Induction Motor	04
	3.1	Working Principle: Double field revolving theory	
	3.2	Staring methods: Split phase, capacitor start, capacitor start and run, shaded pole,	
	3.3	Equivalent circuit: Determination of equivalent circuit parameters by no load and	
		block rotor test.	
4.0		Permanent Magnet Synchronous Motors	04
	4.1	Working principle, EMF and torque equations	
5.0		Brushless DC Motors	04
	5.1	Unipolar brushless DC motor, Bipolar brushless DC motor, speed control,	
		important features and applications	
6.0		Stepper Motors:	06
	6.1	Constructional features, working principle	
	6.2	Variable reluctance motor: Single and multi-stack configurations, characteristics,	
7.0		Switched Reluctance Motors:	04
7.0	71	Constructional features, working principle, operation and control requirements	04
	/•1	Constructional realties, working principle, operation and control requirements	
		Total	38

## **Recommended Books:**

- 1. Bimbhra P.S., Electric Machinery, Khanna Publisher,
- 2. G.K. Dubey, Fundamentals of electrical drives, Narosa Publications
- 3. Nagrath I.J., Kothari D.P., Electric Machines, TMH Publishcations
- 4. A.E. Fitzgerald, Kingsly, Stephen., *Electric Machinery*, McGraw Hill
- 5. M.G. Say and E. O. Taylor, Direct current machines, Pitman publication
- 6. Ashfaq Husain, Electric Machines, Dhanpat Rai and co. publications
- 7. M.V. Deshpande, *Electric Machines*, PHI
- 8. Smarajit Ghosh, *Electric Machines*, PEARSON

#### Internal Assessment (IA):

Two tests must be conducted which should cover at least 80% of syllabus. The average marks of both the test will be considered as final IA marks

- 1. Question paper will comprise of 6 questions, each carrying 20 marks.
- 2. The students need to solve total 4 questions.
- 3: Question No.1 will be compulsory and based on entire syllabus.
- 4: Remaining question (Q.2 to Q.6) will be selected from all the modules.
- 5: Weightage of marks will be as per Blueprint.

#### SE Electronics Engineering Semester IV Syllabus of Laboratory

Subject Code	Subject Name	Te	aching Sch	eme	Credits Assigned			
		Theory	Practical	Tutorial	Theory	TW	Tutorial	Total
EXL 401	Discrete		02			01		01
	Electronics							
	Laboratory							

Subject	Subject Name		Examination Scheme								
Code			,	Theory Marks		Term	Practical	Oral	Total		
		Int	ternal a	ssessment	End Sem.	Work	and				
		Test	Test	Ave. Of Test	Exam		Oral				
		1	2	1 and Test 2							
EXL 401	Discrete					25	50	-	75		
	Electronics										
	Laboratory										

Syllabus: Same as **EXC402** (Discrete Electronics)

#### Term Work:

At least 10 experiments based on the entire syllabus of Subject EXC402 (Discrete Electronics) should be set to have well predefined inference and conclusion. Computation/simulation based experiments are encouraged. Therefore, minimum of 05 simulation experiments be carried out (out of total 10 Expts.) The experiments should be students' centric and attempt should be made to make experiments more meaningful, interesting and innovative. Term work assessment must be based on the overall performance of the student with every experiment graded from time to time. The grades should be converted into marks as per the Credit and Grading System manual and should be added and averaged. The grading and term work assessment should be done based on this scheme.

The final certification and acceptance of term work ensures satisfactory performance of laboratory work and minimum passing marks in term work. Practical and Oral exam will be based on the entire syllabus.

#### **Suggested Experiments on Simulation:**

- 1. One SPICE simulations and implementation for BJT and FET DC biasing (Design and Testing)
- 2. One SPICE simulation and implementation for an Amplifier Design and Testing with measurement of input and output impedance.
- 3. One SPICE simulation and implementation for Frequency response of cascaded and single stage amplifiers.
- 4. One SPICE simulation and implementation for Oscillators.
- 5. One SPICE simulation and implementation for Negative feedback amplifiers.
- 6. One SPICE simulation for Differential amplifier with active load.
- 7. One SPICE simulation for power amplifier.
- 8. One SPICE simulation for Darlington/cascode amplifier.

Subject Code	Subject Name	Te	aching Sch	eme	Credits Assigned				
		Theory	Practical	Tutorial	Theory	TW	Tutorial	Total	
EXL 402	Microprocessor and Peripherals Laboratory		02			01		01	

Subject	Subject Name	Examination Scheme								
Code		Theory Marks				Term	Practical	Oral	Total	
		Int	ternal a	ssessment	Work	and				
		Test Test Ave. Of Test			Sem.		Oral			
		1	2	1 and Test 2	Exam					
EXL 402	Microprocessor and					25		25	50	
	Peripherals									
	Laboratory									

# Syllabus: Same as EXC 403 (Microprocessor and Peripherals)

# Term Work:

At least 10 experiments based on the entire syllabus of EXC 403 (Microprocessor and

**Peripherals**) should be set to have well predefined inference and conclusion. Computation/simulation based experiments are also encouraged. The experiments should be students' centric and attempt should be made to make experiments more meaningful, interesting and innovative. Term work assessment must be based on the **overall performance** of the student with **every experiment graded from time to time.** The grades should be converted into marks as per the **Credit and Grading System** manual and should be **added and averaged**. The grading and term work assessment should be done based on this scheme.

The final certification and acceptance of term work ensures satisfactory performance of laboratory work and minimum passing marks in term work. Practical and Oral exam will be based on the entire syllabus.

## **Suggested Experiments**

- 1. Write a program to arrange block of data in i) Ascending and (ii) Descending order.
- 2. Write a program to find out any power of a number
- 3. Write a programmable delay
- 4. Write a program to find out largest number in an array.
- 5. Experiment on String instructions (e.g Reversing of string & palindrome)
- 6. Write a programme to multiply 32 bit numbers
- 7. Menu driven programming
- 8. Write a program for code conversion
- 9. Programming the 8255 to read or write to port ( any one application)
- 10. Programming the 8259 to demonstrate rotating priority, Specific priority ,etc

Subject Code	Subject Name	Te	aching Sch	eme	Credits Assigned				
		Theory	Practical	Tutorial	Theory	TW	Tutorial	Total	
EXL 403	Control Systems and		02			01		01	
	Electrical Machines								
	Laboratory								

Subject	Subject Name	Examination Scheme								
Code			T	heory Marks		Term	Practical	Oral	Total	
		Int	ternal a	ssessment	End	Work	and			
		Test Test Ave. Of Test			Sem.		Oral			
		1	2	1 and Test 2	Exam					
EXL 403	Control Systems					25		25	50	
	and Electrical									
	Machines									
	Laboratory									

# Syllabus: EXC 404 (Principles of Control Systems) 07 Experiments and EXC 406 (Electrical Machines) 03 Experiments

## Term Work:

At least 03 experiments on EXC 406 (Electrical Machines) and 07 experiments on EXC 404 (Principles of Control Systems) based on the entire syllabus should be set to have well predefined inference and conclusion. Computation/simulation based experiments are also encouraged. The experiments should be students' centric and attempt should be made to make experiments more meaningful, interesting and innovative. Term work assessment must be based on the overall performance of the student with every experiment graded from time to time. The grades should be converted into marks as per the Credit and Grading System manual and should be added and averaged. The grading and term work assessment should be done based on this scheme. The final certification and acceptance of term work ensures satisfactory performance of laboratory work and

minimum passing marks in term work. Practical and Oral exam will be based on the entire syllabus.

Subject Code	Subject Name	Те	aching Sch	eme	Credits Assigned				
		Theory	Practical	Tutorial	Theory	TW	Tutorial	Total	
EXL 404	Communication		02			01		01	
	Engineering								
	Laboratory								

Subject	Subject Name	Examination Scheme							
Code		Theory Marks				Term	Practical	Oral	Total
		Internal assessment End Sem.				Work	and		
		Test Test Ave. Of Test			Exam		Oral		
		1	2	1 and Test 2					
EXL 404	Communication					25	50		75
	Engineering								
	Laboratory								

Syllabus: Same as **EXC 405 (Fundamentals of Communication Engineering)** 

#### Term Work:

At least 10 experiments based on entire syllabus of EXC 405 (Fundamentals of Communication Engineering) should be set to have well predefined inference and conclusion. Computation/simulation based experiments are also encouraged. The experiments should be students' centric and attempt should be made to make experiments more meaningful, interesting and innovative. Term work assessment must be based on the overall performance of the student with every experiment graded from time to time. The grades should be converted into marks as per the Credit and Grading System manual and should be added and averaged. The grading and term work assessment should be done based on this scheme.

The final certification and acceptance of term work ensures satisfactory performance of laboratory work and minimum passing marks in term work. Practical and Oral exam will be based on the entire syllabus.