Program: BE Electrical Engineering

Curriculum Scheme: Revised 2012

Examination: Third Year Semester VI

Course Code: EEC604 and Course Name: Control System-1

Time: 1hour

Max. Marks: 50

Note to the students:- All the Questions are compulsory and carry equal marks .

Q1.	The output signal is fed back at the input side from thepoint	
Option A:	Summing	
Option B:	Differential	
Option C:	Take-off	
Option D:	Take away point	
Q2.	Car is moving at a constant speed of 60 km/h, feedback element for the driver is	
Option A:	Clutch	
Option B:	Eyes	
Option C:	Steering wheel	
Option D:	Needle of the speedometer	
Q3.	The overall transfer function from block diagram reduction for cascaded blocks is	
Option A:	Sum of individual gain	
Option B:	Product of individual gain	
Option C:	Difference of individual gain	
Option D:	Division of individual gain	
Q4.	A node having only outgoing branches	
Option A:	Input node	
Option B:	Output node	
Option C:	Intermediate node	
Option D:	Terminal node	
Q5.	Signal flow graphs is used to obtain the	
Option A:	Stability of the system	
Option B:	Transfer function of the system	
Option C:	Controllability of the system	
Option D:	Observability of the system	
Q6.	Which among the following controls the speed of D.C. motor	
Option A:	Galvanometer	
Option B:	Gauss meter	
Option C:	Potentiometer	
Option D:	Tachometer	

Q7. The output signal is fed back at the input side from thepoint Option A: Summing Option B: Differential Option D: Saddle Q8. Steady state error of a 'type 0' unity feedback system for a unit step function is Option A: Zero Option B: infinity Option D: 1/(1+K _p) Q9. Addition of pole close to the origin on s-plane makes the system relatively Option A: More stable Option B: Less stable Option D: No effect Q10. Damping factor is a line on s-plane Option A: Radial line Option C: Vertical line Option C: Vertical line Option C: Grid Q11. Open-loop transfer function G(s)=4(1+2s)/s(s+2) with unity ramp input ,steady-state error will Option A: zero Option A: zero </th <th></th> <th></th>			
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Q14. Type of system with steady state error 0.4 for unit ramp input is Option A: zero	Option D:	Every where	
Q14.Type of system with steady state error 0.4 for unit ramp input isOption A:zero			
Option A: zero	Q14.	Type of system with steady state error 0.4 for unit ramp input is	
	Option A:	zero	

Option B:	One	
Option C:	Тwo	
Option D:	Any type	
Q15.	Which point on root locus specifies the meeting or collision of two poles?	
Option A:	Centroid	
Option B:	Break away point	
Option C:	Stability point	
Option D:	Anti-break point	
Q16.	In frequency response, the resonance frequency is basically a measure of	
Option A:	Speed	
Option B:	Distance	
Option C:	Angle	
Option D:	Curvature	
•		
Q17.	What is the number of the root locus segments which do not terminate on	
	zeroes?	
Option A:	The number of poles	
Option B:	The number of zeroes	
Option C:	The difference between the number of poles and zeroes	
Option D:	The sum of the number of poles and the number of the zeroes	
018.	The characteristic equation is $s^3+14s^2+(45+K)s+K=0$. centroid is located at (-x.0)	
- • -		
	then the value of x is	
Option A:	then the value of x is1	
Option A: Option B:	then the value of x is 1 2	
Option A: Option B: Option C:	then the value of x is 1 2 3	
Option A: Option B: Option C: Option D:	then the value of x is 1 2 3 4	
Option A: Option B: Option C: Option D:	then the value of x is 1 2 3 4	
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Option A: Option B: Option C: Option D: Q19. Option A: Option B: Option C: Option D:	then the value of x is 1 2 3 4 In accordance to relative stability, the settling time exhibits inversely proportional nature to parts of roots Real positive Real negative Imaginary positive Imaginary negative	
Option A: Option B: Option C: Option D: Q19. Option A: Option B: Option C: Option D:	then the value of x is 1 2 3 4 In accordance to relative stability, the settling time exhibits inversely proportional nature to parts of roots Real positive Real negative Imaginary positive Imaginary negative	
Option A: Option B: Option C: Option D: Q19. Option A: Option A: Option B: Option C: Option D: Q20.	then the value of x is 1 2 3 4 In accordance to relative stability, the settling time exhibits inversely proportional nature to parts of roots Real positive Real negative Imaginary positive Imaginary negative Due to an addition of pole at origin, the polar plot gets shifted by at ω = 0?	
Option A: Option B: Option C: Option D: Q19. Option A: Option A: Option B: Option C: Option D: Q20. Option A:	then the value of x is 1 2 3 4 In accordance to relative stability, the settling time exhibits inversely proportional nature to parts of roots Real positive Real negative Imaginary positive Imaginary negative Due to an addition of pole at origin, the polar plot gets shifted by at ω = 0? -45°	
Option A: Option B: Option C: Option D: Q19. Option A: Option B: Option C: Option D: Q20. Option A: Option A: Option B:	then the value of x is 1 2 3 4 In accordance to relative stability, the settling time exhibits inversely proportional nature toparts of roots Real positive Real negative Imaginary positive Imaginary negative Due to an addition of pole at origin, the polar plot gets shifted by at ω = 0? -45° -60°	
Option A: Option B: Option C: Option D: Q19. Option A: Option A: Option C: Option D: Q20. Option A: Option A: Option B: Option C:	then the value of x is 1 2 3 4 In accordance to relative stability, the settling time exhibits inversely proportional nature to parts of roots Real positive Real negative Imaginary positive Imaginary negative Due to an addition of pole at origin, the polar plot gets shifted by at ω = 0? -45° -60° -90°	
Option A: Option B: Option C: Option D: Q19. Option A: Option A: Option B: Option C: Option A: Option A: Option A: Option B: Option B: Option C: Option D:	then the value of x is	
Option A: Option B: Option C: Option D: Q19. Option A: Option A: Option C: Option D: Q20. Option A: Option A: Option B: Option B: Option C: Option D:	then the value of x is	
Option A: Option B: Option C: Option D: Q19. Option A: Option A: Option B: Option C: Option C: Option A: Option B: Option B: Option C: Option D:	then the value of x is	
Option A: Option B: Option C: Option D: Q19. Option A: Option A: Option B: Option C: Option A: Option A: Option A: Option B: Option C: Option C: Option D:	then the value of x is	
Option A: Option B: Option C: Option D: Q19. Option A: Option A: Option C: Option D: Q20. Option A: Option A: Option B: Option C: Option C: Option D: Q21.	then the value of x is	

Option B:	-0.3	
Option C:	-30	
Option D:	-0.03	
Q22.	Which among the following constitute the state model of a system in addition	
	state equations	
Option A:	Input equations	
Option B:	Output equations	
Option C:	State trajectory	
Option D:	State vector	
Q23.	Conventional control theory is applicable to systems	
Option A:	SISO	
Option B:	MIMO	
Option C:	Time varying	
Option D:	Non-linear	
Q24.	The minimum number of states require to describe the two degree differential	
	equation	
Option A:	1	
Option B:	2	
Option C:	3	
Option D:	4	
Q25.	A transfer function of control system does not have pole-zero cancellation.	
	Which one of the following statements is true	
Option A:	System is neither controllable nor observable	
Option B:	System is completely controllable and observable	
Option C:	System is observable but uncontrollable	
Option D:	System is controllable but unobservable	

Program: BE Electrical Engineering

Curriculum Scheme: Revised 2012

Examination: Third Year Semester VI

Course Code: EEC604 and Course Name: Control System-1

Time: 1hour

Max. Marks: 50

Question	Correct Option (Enter either 'A' or 'B' or
	'C' or 'D')
Q1.	C
Q2.	D
Q3.	В
Q4	А
Q5	В
Q6	D
Q7	C
Q8.	D
Q9.	В
Q10.	А
Q11.	С
Q12.	А
Q13.	С
Q14.	В
Q15.	В
Q16.	А
Q17.	D

Q18.	В
Q19.	В
Q20.	С
Q21.	В
Q22.	В
Q23.	В
BQ24.	В
Q25.	В