

## Specification for the book of courses

<b>Study program</b>		Electrical Engineering and Computer Science		
<b>Module</b>		Electrical Power Engineering		
<b>Type and level of studies</b>		Undergraduate Academic Studies		
<b>The name of the course</b>		Automatic Control Systems		
<b>Lecturer (for lectures)</b>		Nikolić S. Saša, Perić Lj. Staniša		
<b>Lecturer/associate (for exercises)</b>		Spasić D. Miodrag		
<b>Lecturer/associate (for OFE)</b>		Spasić D. Miodrag		
<b>Number of ECTS</b>	5	<b>Course status (obligatory/elective)</b>	Elective	
<b>Prerequisites</b>				
<b>Course objectives</b>	Acquiring knowledge of non-linear, discrete, and optimal control systems and applications in professional courses and in practice.			
<b>Course outcomes</b>	Knowledge of the methods of analysis, modeling, simulation and synthesis of control systems..			
<b>Course outline</b>				
<b>Theoretical teaching</b>	Historical overview of automatic control systems (ACS). Nonlinear Systems. Discrete systems. The structure of a digital system and process of discretization. Discrete transfer functions. Stability of discrete ACS. Synthesis of discrete ACS. Examples of non-linear systems. Typical nonlinearities and their characteristics. Linearization of nonlinear systems. System analysis in the phase plane. Stability of nonlinear ACS. Optimal systems. Criteria functions. Design of Kalman regulator. Kalman regulator with pre-defined degree of exponential stability. Poles placement of multivariable systems with feedback. Design of the observer. Simulation of ACS. Application of simulation in the analysis and synthesis of ACS. Simulation software for ACS.			
<b>Practical teaching (exercises, OFE, study and research)</b>	Discrete transfer functions. Stability of discrete ACS. Z-transform, inverse Z-transform. Jury stability criterion. Nyquist criterion for discrete systems. Method of root locus. Design of digital compensators and controllers. Methods for analysis of nonlinear ACS. Stability of nonlinear ACS. The definition of stability, indirect and direct method of Lyapunov. Examples of non-linear systems. Parameter optimization. Kalman regulator. Design of the observer.			
<b>Textbooks/references</b>				
1	Č. Milosavljević, Basic of automatics, Part I and II (in Serbian), Faculty of Electronic Engineering, Niš, 2003.			
2	M. Stojić, Automatic Control Systems (in Serbian), Faculty of Electronic Engineering, Niš, 2004.			
3	Č. Milosavljević, Basic of automatics - workbook (in Serbian), Faculty of Electronic Engineering, Niš, 1995.			
4	D. Antić, Č. Milosavljević, G. Golo, D. Mitić, P. Vuković, Automatic Control Systems - workbook (in Serbian), Faculty of Electronic Engineering, Niš, 1995,			
5				
<b>Number of classes of active education per week during semester/trimester/year</b>				
<b>Lectures</b>	<b>Exercises</b>	<b>OFE</b>	<b>Study and research work</b>	<b>Other classes</b>
2	2	1	0	0
<b>Teaching methods</b>	Lectures; Auditory exercises; Computer exercises; Consultations			
<b>Grade (maximum number of points 100)</b>				
<b>Pre-exam duties</b>	<b>Points</b>	<b>Final exam</b>	<b>Points</b>	
<b>Activity during lectures</b>	10	<b>Written exam</b>	20	
<b>Exercises</b>	20	<b>Oral exam</b>	20	
<b>Colloquia</b>	30			
<b>Projects</b>				