

SRI MANAKULA VINAYAGAR ENGINEERING COLLEGE

(An Autonomous Institution)

Puducherry

DEPARTMENT OF ELECTRICAL AND ELECTRONICS ENGINEERING

B.TECH. HONOURS / MINOR PROGRAMME ELECTRIC VEHICLES

ACADEMIC REGULATIONS 2023 (R-2023)

CURRICULUM AND SYLLABI



B. Tech Honours / Minor Programme - ELECTRIC VEHICLES

CURRICULUM

			COUR	RSE DETAI	LS								
SI.	Semest	Course Code	e Course Title	Course	Catagony	P	erio	ds	Credits	Ма	x. Marl	ks	
No.	er	Course Cour	e Course rille	Type**	Category	L	Т	Р	Credits	CAM	ESM	Total	
1	IV	U23VXT401	Electrical Vehicles: Design, Dynamics and Testing	Т	PC / IC	3	-	-	3	25	75	100	
2	>	U23VXT502	Energy Storage and Battery Management System	Т	PC / IC	3	-	-	3	25	75	100	
3	VI	U23VXB603	Electric Drives and Controls	В	PC / IC	3	-	2	4	50	50	100	
4	VII	U23VXB704	Modelling and Simulation of EHV	В	PC / IC	3	-	2	4	50	50	100	
5	VIII	U23VXT805	Autonomous and Connected Vehicles	Т	PC / IC	3	-	-	3	25	75	100	
6	VIII	U23VXW806	Project Work	PA	PC / IC	-	-	4	2	50	50	100	
			Total						19	225	375	600	
			Equivalent	ent NPTEL courses##									
1	IV	U23VXT401	Electrical Vehicles: Design, Dynamics and	Vehicle Dive	ctric	3							
2	IV	023771401	Testing	Vehicles ar	'	3		WEEK OURSI	_				
3	V	U23VXT502	Energy Storage and Battery Management System	Electroche	emical Ener	gy S	tora	ge	3				

^{##} The student shall be given an option to earn 3 credits through one 12-week NPTEL course (Equivalent) instead of any one theory course listed for Honour / Minor degree programme and shall be completed before the commencement of eighth semester. The equivalent courses are subject to change based on its availability as per NPTEL course list.



^{**} T – Theory, B – Theory cum Practical, PA – Project Work

Department	EEE			Program	me: B.	Tech Ho	onours / Mi	nor – Elect	ric Vehicl	es
Semester	IV			Course	Categor	y Code	: PC/ IC End	d Semester	Exam Typ	e: TE *
C C	1100\7	VT 404		Perio	ds/Wee	k	Credit	Max	imum Mar	ks
Course Code	UZSV	XT401		L	Т	Р	С	CAM	ESE	TM
Course Name			VEHICLES: DESIGN, ND TESTING	3	-	-	3	25	75	100
	<u> </u>		Commor	to ALL Br	anches		<u>.</u>	i.		
Prerequisite	Engine	eering M	echanics							
	On co	ompletio	n of the course, the stu	dents will b	e able	to			BT Ma (Highest	
	CO1	Summa	rize the basic functions of bo	oth Electric a	nd Hybrid	d vehicle	s and their p	erformance.	K	2
Course	CO2	1	e the automobile configuration emand, etc.,	ons, packagi	ng, struc	ctural sys	stems, aerod	ynamics and	K	3
Outcomes	CO3	FWD, R	the vehicle resistance and WD, and multi-wheel drive s	systems.			•		K	3
	CO4	Examin enginee	e the vehicle testing, homolo ring.	gation, and s	tandard	s complia	ance for safe	automotive	K	3
	CO5	d regulations	gulations K3							
UNIT- I	Introd	duction					Periods:	9		
Hybrid vehicle -	- advant	tages- dis	and Disadvantages of EV. advantages- Architecture a vehicle operating modes. mics	ind energy f	ow- ser	ries, para	allel, series- Periods:		e train for	CO1
Backbone Const Automotive Aero	ruction- o-dynam	Body and ics- Vehi	bille- Body and Chassis Fu Chassis Materials. cle Power Demand Analysi cle handling and stability- Au	s- Types of	suspens	sion and				CO2
UNIT- III	Vehic	le Desig	n				Periods:	9		· .
Acceleration For and gearbox- Bra	ce- max aking pe	timum spe erformance	ng Resistance- grading res eed- Total Tractive Effort-To e. ains- Rear-Wheel Drive Pow	rque Require	d on dri	ve Whee	el- Transmiss	sion- Differen	tial- clutch	CO3
UNIT- IV	·		g and Homologation				Periods:			<u>L</u>
Need of vehicle component appr test- side impact	testing	and hor ting- Syst	nologation- testing organiza em level approval and Whol Impact test- Track testing							CO4
UNIT- V	Vehic	ular Saf	ety and Government no	rms			Periods:	9		
			stems- Active and passive es- Government Norms- Reg						occupant	CO5
Lecture Period	ds:45		Tutorial Periods:-	Practic	al Perio	ods:-	1	Total Perio	ds: 45	
Press, 2018.	on, John		tefano Longo, Kambiz Ebral ouse, "Automotive Chassis E			-			hicles", CR	C
			als of Vehicle Dynamics", SA Automotive Safety Handbool							
Web Reference		,	Lasmouro Caloty Harlabook	., 5, 12 1110111						

3. https://www.opal-rt.com/automotive-overview/ * TE – Theory Exam, LE – Lab Exam

https://www.nhtsa.gov/
 https://www.ais.gov.in/



COs/POs/PSOs Mapping

	5/1 	. 003	шаррі	9														
COs		Program Outcomes (POs)												Program Specific Outcomes (PSOs)				
	PO1	PO2	PO3	PO4	PO5	PO6	P07	PO8	PO9	PO10	PO11	PO12	PSO1	PSO2	PSO3			
1	3	2	3	2	1	2	1	-	-	-	-	1	3	3	2			
2	3	2	3	2	1	2	1	-	-	-	-	1	3	3	2			
3	3	2	3	2	1	2	1	-	-	-	-	1	3	3	2			
4	3	2	3	2	1	2	1	-	-	-	-	1	3	3	2			
5	3	2	3	2	1	2	1	-	-	-	-	1	3	3	2			

Correlation Level: 1 - Low, 2 - Medium, 3 - High

Evaluation Methods

		Continuo	ous Asses	sment Marks (C	AM)	End Semester	Total Marks
	CAT 1	CAT 2	Model##	Assignment#	Attendance##	Examination##	(CAM+ESM)
Portion for Test	2 Units	2 Units	All 5 Units			All 5 Units	
Assessment	MCQ Test	MCQ Test	NA/::: 44	Individual			
Assessment Methodology Duration of	Analytica	stions for I Course stions for ourse	Exam	Task#		Written Exam	
Duration of the Test	1 hour 30 Minutes	1 hour 30 Minutes	3 hours			3 hours	
Test Marks	50	50	75	20	5	75	
Weightage for CAM	5	5	5	5	5		
CAM / ESE Marks			CAM Ma	arks = 25		ESE Marks = 75	100

[#] Open Book Analytical Exam/Analyse Real world problems and propose solutions/ Tool or Subject Proficiency Analysis – Test the Students skill by giving individual task/ Paper Presentation/Micro Project Presentation/Idea Presentation for the Societal Problem;(Questions standard shall be of level 3 or more in Blooms Taxonomy)

Distribution of Marks for Attendance, the Question Paper Pattern for Model and ESE are same as given in B. Tech. Regulations R2023 for Theory Courses.



Department	EEE	Progra	nme: B.Te	ch Hono	ur / Minor	- Electri	c Vehicl	es			
Semester	V	Course	Category:	PC /IC	End Sem	nester Exa	ıт Туре	: TE *			
		F	eriods/We	=k	Credit	Maxi	mum Ma	arks			
Course Code	U23VXT502	L	Т	Р	С	CAM	ESE	TM			
Course Name	ENERGY STORAGE AND BATTE MANAGEMENT SYSTEM	RY 3	-	-	3	25	75	100			
		mon to ALL E	ranches					i			
Prerequisite	Physics, Electrical machines										
	On completion of the course, the						(Highe	lapping st Level			
	CO1 Explain electrical parameters voltage, power, efficiency, and	d lifecycle cha	racteristics				·	K2			
Course	CO2 Compare and evaluate batter storage, assessing their applic	cations, advar	tages, and	limitatio	ns in EVs.		l	K2			
Outcomes	Analyze the Battery Managen management, and balancing,	ensuring safe	and efficie	nt batter	y operation	1.	l	K3			
	CO4 Explain the different levels of technology behind fast charging	ng, comparing	their adva	ntages a	nd chargin	g speeds.	l	K3			
	CO5 Explain charging technologie smart grids (V to X, X to V), n their roles in EV charging infra	nicrogrids, and						K3			
UNIT – I Battery Parameters Periods: 9 Electrical parameter: Energy Capacity (E)- Nominal Voltage- Operating Voltage- Power Output (P)- C-Rate-											
Density- Spec Cut-Off Voltage of Discharge	arge Efficiency- Self-Discharge Rate cific Energy- Specific Power. Chargin ge- Discharge Cut-Off Voltage- Charg (DoD)- State of Charge (SoC)- State Range- Thermal Runaway Temperatu	g & Discharg Je Time . Lifec of Health (So	ing Param ycle & Ag	eters- Fara	ast Chargii imeters- C	ng Rate- (Cycle Life-	Charge Depth	CO1			
UNIT – II	Energy Storage Technologies to	EV			Periods	s: 9					
Phosphate (L Titanate (LTC Cylindrical Ce Fuel Cell Fu Limitations-	Li-lon) Battery Technology and Wo FP)- Lithium Nickel- Manganese Cob D)- Advantages of Li-lon Batteries- Colls-Prismatic Cells-Pouch Cells Indamentals & its Types. Hydroger Hydrogen fuel cell vs Battery Electratteries- Sodium-Ion Batteries. Introdu	ealt (NMC)- Li Challenges & n Fuel Cell- ric Vehicles.	hium Nicke Limitations Key Comp Alternative	el Cobalt -Compar onents- e Energy	: Aluminum rison. Batte Advantage y Storage	n (NCA)- I ery cell fo e-Challen Technol	ithium ormats- ges & ogies-	CO2			
UNIT – III	Battery Management System				Periods	s: 9					
Battery Man State of Healt	agement System (BMS) & Importa th (SoH) Calculation- Thermal Manag on & Safety. BMS Types - Centrali	ement- Overd	harge/Disc	harge Pr	Charge (Se otection- E	oC) Calcu Balancing	Cells -	CO3			
UNIT – IV	EV Charging Systems and Techn	ologies			Periods	s: 9					
Fechnologies Conductive C Chargers-Arrar	- EV Charging level 1-level 2-lev-Basic Charger Circuits-Microprocharging Systems-Principles of Congement of an Off-Board Conduct ging-Soft-Switching Power Converter	rel 3- Fast C cessor-Based nductive Cha ive Charger. for Inductive	Charger ging-Stand Inductive Charging. E	r Circu dard Pov Charg i	uits-Charge wer Levels ing Syste ndication	e Equali s of Conc ems-Princi and Mon	zation. ductive ple of	CO4			
	EV Charging and Power Manager	ment System	5		Periods	s: 9					
UNIT – V	LV Onlanging and I ower manager				······						
Charging Tec Charging with EV Charging I Hybridization-E	hnologies and Systems: Convention PV Systems-Fast/Rapid Charging. Confrastructure-Solutions to Charging Control Stattery Swapping-Advanced Charging on Charging Solutions and Systems.	t <mark>hallenges ar</mark> Challenges. A	d Solution dvanced (ns in EV Charging	/ Charginզ g Systems	g: Challer s Manag e	ges in ement:	CO5			
Charging Tec Charging with EV Charging I Hybridization-E	hnologies and Systems: Convention PV Systems-Fast/Rapid Charging. Confrastructure-Solutions to Charging Contractive Swapping-Advanced Charging on Charging Solutions and Systems.	challenges ar Challenges. A g Systems Ma	d Solution dvanced (ns in EV Charging . Case	Charging Systems Studies ir	g: Challer s Manag e	iges in ement: irging-	CO5			



Text Books

- 1. Alfred Rufer, "Energy Storage Systems and Components", CRC Press, 2018.
- 2. Ibrahim Dinçer, Halil S. Hamut and Nader Javani, "Thermal Management of Electric Vehicle Battery Systems", John Wiley& Sons Ltd., 2016.

Reference Books

- 1. James Larminie, John Lowry, "Electric Vehicle Technology Explained", John Wiley & Sons Ltd, 2012.
- 2. NITI Aayog, Handbook of Electric Vehicle Charging Infrastructure Implementation, Version 1, 2021.
- 3. TR Crompton, "Battery", Newnes-Reed Educational and Professional Publishing Ltd. 3rd Edition, 2000.
- 4. F. Beguin and E. Frackowiak, "Super capacitors- materials, Systems and Applications", Wiley-VCH & Company, 2013.
- 5. V.Hacker, S. Mitsushima, "Fuel Cells and Hydrogens: From Fundamentals to applied Research", Elsevier, 2018.
- 6. Fraunhofer IEE, IIT Bombay, DTU, and IIT Comillas, A Critical Review: Smart Charging Strategies and Technologies for Electric Vehicles, NDC-TIA, Nov. 2021.
- 7. D. Kettles, Electric Vehicle Charging Technology Analysis and Standards, Florida Solar Energy Center, Feb. 2015

Web References

- 1. https://archive.nptel.ac.in/courses/108/103/108103009/
- 2. https://www.nhtsa.gov/
- 3. https://www.ais.gov.in/
- 4. https://www.opal-rt.com/automotive-overview/
- 5. https://apem-journal.org/Archives/2019/APEM14-1 065-079.pdf
- 6. https://ouci.dntb.gov.ua/works/4rrWg5X4/
- 7. https://www.beny.com/challenges-and-solutions-in-electric-vehicle-charging-infrastructure-development/

COs/POs/PSOs Mapping

COs		Program Outcomes (POs)												gram Spec	cific SOs)
	PO1	PO2	PO3	PO4	PO5	PO6	PO7	PO8	PO9	PO10	PO11	PO12	PSO1	PSO2	PSO3
1	3	2	3	2	-	2	1	-	-	-	-	1	3	3	2
2	3	2	3	2	-	2	1	-	-	-	-	1	3	3	2
3	3	2	3	2	-	2	1	-	-	-	-	1	3	3	2
4	3	2	3	2	-	2	1	-	-	-	-	1	3	3	2
5	3	2	3	2	-	2	1	-	-	-	-	1	3	3	2

Correlation Level: 1 - Low, 2 - Medium, 3 - High

Evaluation Methods

•		Continuous	s Assessm	ent Marks (CAM)	End Semester	Total Marks
	CAT 1	CAT 2	Model##	Assignment#	Attendance##	Examination##	(CAM+ESM)
Portion for Test	2 Units	2 Units	All 5 Units			All 5 Units	
Assessment Methodology	MCQ Test	MCQ Test		Individual			
Methodology	Analytical	stions for Course ns for Theory	Written Exam	Task #		Written Exam	
Duration of the Test	1 hour 30 Minutes	1 hour 30 Minutes	3 hours			3 hours	
Test Marks Weightage for CAM CAM / ESE Marks	50	50	75	20	5	75	
	5	5	5	5	5		
			CAM Mark		ESE Marks = 75	100	

[#] Open Book Analytical Exam/Analyse Real world problems and propose solutions/ Tool or Subject Proficiency Analysis – Test the Students skill by giving individual task/ Paper Presentation/Micro Project Presentation/Idea Presentation for the Societal Problem; (Questions standard shall be of level 3 or more in Blooms Taxonomy)

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^{*} TE – Theory Exam, LE – Lab Exam

	EEE		Fiogram	ime. D. 1 e	cn non	ours/ Min	or – Elec	,uic veii			
Semester	VI		Course (Category:	PC/IC	End Sen	nester Ex	am Type	e: TE *		
Course Code	11231/	XB603	Per	riods/We	ek	Credit	Max	imum M	arks		
Course Coue	0200		L	Т	Р	С	CAM	ESE	TM		
Course Name	ELECT	RIC DRIVES AND CONTROLS	3	0	2	4	50	50	100		
		Common t	o ALL Brar	nches							
Prerequisite	Electr	ical Machines									
	On co	empletion of the course, the stud	lents will b	e able to)				Ларріng est Leve		
	CO1	Comprehend the types, design, and speed characteristics and role in EV	•		e motors	including t	their torque	e-	K2		
Course	CO2	Analyze the operation and performatechniques.	ance of DC	and AC n	notor driv	es with sp	eed contr	ol	K2		
Outcomes	СОЗ	Apply the various control techniq performance optimization.	ues for PM	/ISM and	BLDC	motor driv	es for th	ne	КЗ		
	CO4	Analyze and implement DC and AC r	notor control		K4						
CO5 Implement control techniques for PMSM, and BLDC motor drives, optimizing performance and minimizing torque ripple.											
UNIT – I Introduction to EV Drives Periods:10											
Overview of E Design: Design constant-torque Comparison fo JNIT – II	principle and con r EVs: S DC D	rs: Types of motors used in electric es and sizing considerations for EV to stant-power modes in motor performa uitability analysis of motors for 2W, 3W rives and Induction Motor Drives rolled DC-Drives: Operation with con	raction motor ince. Selection V, 4-wheelers	rs. Torque on of Moto s, and larg	e-Speed or Power e vehicle	Character and conves. Periods	istics: An rter Ratino s:10	alysis of g. Motor	CO1		
Overview of E Design: Design constant-torque Comparison for UNIT – II DC Drives: Pha Drives, Multi-Qu Induction Motor	principle and con r EVs: S DC De ase cont uadrant or Drives control a	es and sizing considerations for EV to stant-power modes in motor performa uitability analysis of motors for 2W, 3W rives and Induction Motor Drives rolled DC-Drives: Operation with con Operation, harmonics control in cho s: Speed control techniques: Stator vo and Slip power recovery control schen	raction motor ince. Selection of, 4-wheelers intinuous and pper, speed coltage contro	rs. Torque on of Moto s, and larg discontine control not, Variable	e-Speed or Power e vehicle uous mo nethod, de frequer	Character and conve s. Periods des; Chopp closed loop acy control,	istics: An orter Rating s:10 per Control control of Control V/f control	alysis of g. Motor blled DC scheme. bl, Static	CO2		
Overview of E Design: Design constant-torque Comparison for UNIT – II DC Drives: Pha Drives, Multi-Qu Induction Motor rotor resistance direct torque cor	principle and con r EVs: S DC De ase content uadrant or Drives control a	es and sizing considerations for EV to stant-power modes in motor performa uitability analysis of motors for 2W, 3W rives and Induction Motor Drives rolled DC-Drives: Operation with con Operation, harmonics control in choos: Speed control techniques: Stator wand Slip power recovery control schen duction motors for EVs.	raction motor ince. Selection of, 4-wheelers intinuous and pper, speed coltage contro	rs. Torque on of Moto s, and larg discontine control not, Variable	e-Speed or Power e vehicle uous mo nethod, de frequer	Character and convers. Periods des; Chopp closed loop icy control, ue. Field-or	istics: An erter Rating s:10 per Contro control: V/f contro riented cor	alysis of g. Motor blled DC scheme. bl, Static			
Overview of E Design: Design constant-torque Comparison fo UNIT – II DC Drives: Pha Drives, Multi-Qu Induction Moto rotor resistance direct torque cor UNIT – III BLDC Motor D EMF control, an	principle and con r EVs: S DC De ase contuadrant or Drives control antrol of in BLDC rives: Pad design	es and sizing considerations for EV to stant-power modes in motor performa uitability analysis of motors for 2W, 3W rives and Induction Motor Drives rolled DC-Drives: Operation with con Operation, harmonics control in cho s: Speed control techniques: Stator vo and Slip power recovery control schen	raction motor ince. Selection of, 4-wheelers in tinuous and pper, speed coltage control mes, Slip control verter switch	rs. Torque on of Moto s, and larg disconting control in ol, Variable inpensation	e-Speed or Power e vehicle uous mo nethod, of frequer notechnique mes for A t Magnet	Character and convers. Periods des; Choppelosed loopelosed loopel	istics: An orter Rating s:10 per Control o control o V/f control riented con s:10 c, trapezoio ous Motor	alysis of g. Motor billed DC scheme. bl, Static ntrol and	CO2		
Overview of E Design: Design constant-torque Comparison for UNIT – II DC Drives: Pha Drives, Multi-Qu Induction Motor rotor resistance direct torque cor UNIT – III BLDC Motor D EMF control, an construction, bra UNIT – IV	principle and con r EVs: S DC De ase confusion as control and rol of in BLDC rives: P id design aking me	es and sizing considerations for EV to stant-power modes in motor performa uitability analysis of motors for 2W, 3W rives and Induction Motor Drives rolled DC-Drives: Operation with con Operation, harmonics control in choos: Speed control techniques: Stator voland Slip power recovery control schen duction motors for EVs. Stand PMSM Drives rinciples of BLDC motor operation, in a criteria for BLDC drives in EVs. PMS thods, field-oriented and flux-weakening control schen for Drives Practice -I	raction motor ince. Selection of, 4-wheelers in tinuous and pper, speed coltage control mes, Slip control verter switch	rs. Torque on of Moto s, and larg disconting control in ol, Variable inpensation	e-Speed or Power e vehicle uous mo nethod, of frequer notechnique mes for A t Magnet	Character and convers. Periods des; Choppelosed looper control, ue. Field-on Periods C and DC Synchronous.	istics: An orter Rating s:10 per Control o control o V/f control riented con s:10 c, trapezoio ous Motor	alysis of g. Motor billed DC scheme. bl, Static ntrol and	CO2		
Overview of E Design: Design constant-torque Comparison for UNIT – II DC Drives: Pha Drives, Multi-Qu Induction Motor rotor resistance direct torque cor UNIT – III BLDC Motor D EMF control, an construction, bra UNIT – IV 1. Demon 2. Speed 3. Speed 4. Perform 5. V/f Cor	principle and con r EVs: S DC De ase control and control of in BLDC rives: P d design aking me Electrol of control of control of control of principle and control of Control of Principle and control of Control of Control o	es and sizing considerations for EV to stant-power modes in motor performa uitability analysis of motors for 2W, 3W rives and Induction Motor Drives rolled DC-Drives: Operation with con Operation, harmonics control in choos: Speed control techniques: Stator voland Slip power recovery control schen duction motors for EVs. E and PMSM Drives rinciples of BLDC motor operation, in a criteria for BLDC drives in EVs. PMS thods, field-oriented and flux-weakening.	raction motor ince. Selection I, 4-wheelers intinuous and pper, speed oltage control nes, Slip control everter switch in a control, are stifier	rs. Torque on of Moto s, and larg discontine control n ol, Variable npensation ning scher Permanen and sensorle	e-Speed or Power e vehicle uous mo nethod, of frequer notechnique mes for A t Magnet	Character and convers. Periods des; Choppelosed loopelosed loopel	istics: An orter Rating s:10 per Control o control o V/f control riented con s:10 c, trapezoio ous Motor	alysis of g. Motor billed DC scheme. bl, Static ntrol and	CO2		
Overview of E Design: Design constant-torque Comparison for UNIT – II DC Drives: Pha Drives, Multi-Qu Induction Motor rotor resistance direct torque cor UNIT – III BLDC Motor D EMF control, and construction, bra UNIT – IV 1. Demon 2. Speed 3. Speed 4. Perform 5. V/f Cor 6. Simular	principle and con r EVs: S DC De ase control and control of in BLDC rives: P ad design aking me Electustration control of control of principle and control of P at ion of R and con the control of R and control o	es and sizing considerations for EV to stant-power modes in motor performa uitability analysis of motors for 2W, 3W rives and Induction Motor Drives rolled DC-Drives: Operation with con Operation, harmonics control in choos: Speed control techniques: Stator voland Slip power recovery control schemeduction motors for EVs. E and PMSM Drives Trinciples of BLDC motor operation, in a criteria for BLDC drives in EVs. PMS thods, field-oriented and flux-weakening in Control of Wiring Layout of electric vehicle. If DC drives using phase-controlled recomposition of Induction motor Drive. WM Inverter Based Three Phase Induction motors for EV to the standard of the phase Induction motor Drive.	raction motor ince. Selection I, 4-wheelers intinuous and pper, speed oltage control nes, Slip control everter switch in a control, are stifier	rs. Torque on of Moto s, and larg discontine control n ol, Variable npensation ning scher Permanen and sensorle	e-Speed or Power e vehicle uous mo nethod, of frequer notechnique mes for A t Magnet	Character and convers. Periods des; Choppelosed loopelosed loopel	istics: An order Rating s:10 per Control o control o V/f contro riented cor s:10 o, trapezoic ous Motor s:15	alysis of g. Motor billed DC scheme. bl, Static ntrol and	CO2		
Overview of E Design: Design constant-torque Comparison fo UNIT – II DC Drives: Pha Drives, Multi-Qu Induction Motor rotor resistance direct torque cor UNIT – III BLDC Motor D EMF control, an construction, bra UNIT – IV 1. Demon 2. Speed 3. Speed 4. Perforn 5. V/f Cor 6. Simular UNIT – V 1. Speed 2. Simular 3. Sensor 4. Torque 5. Regener	principle and con r EVs: S DC Do ase control and control of in BLDC rives: Pad design me Electron of Patrol of Patro	es and sizing considerations for EV to stant-power modes in motor performa uitability analysis of motors for 2W, 3W rives and Induction Motor Drives rolled DC-Drives: Operation with concept of DC-Drives: Operation with concept of DC-Drives: Operation with concept of Stator volume of Stator volume of Stator volume of Stator o	raction motor ince. Selection I/, 4-wheelers intinuous and pper, speed coltage control nes, Slip control verter switch in Motor switch in Motor determined from Motor inent Synchrol MSM motor determined from Motor determi	rs. Torque on of Moto s, and larg disconting control in ol, Variable inpensation ning scher Permanen ind sensorle Motor Motor ol method nous Moto lrives. nulation so	e-Speed or Power e vehicle uous mo nethod, of frequer in technique mes for A t Magnet ess opera	Character and conve s. Period: des; Chopp closed loop cy control, ue. Field-or Period: C and DC Synchrono ation. Period:	istics: An order Rating s:10 per Control o control o V/f contro riented cor s:10 o, trapezoic ous Motor s:15	alysis of g. Motor billed DC scheme. bl, Static ntrol and	CO2		

- 3. KT. Chau, "Electric Vehicle Machines and Drives: Design, Analysis, and Application," Wiley-IEEE Press, 1st Edition, 2015.
- 4. John G. Hayes, G. Abas Goodarzi, "Electric Powertrain: Energy Systems, Power Electronics and Drives for Hybrid, Electric and Fuel Cell Vehicles," Wiley-Blackwell, 1st Edition, 2018.



Reference Books

- 1. C.G. Hochgraf, M.J. Ryan, and H.L. Wiegman, "Engine Control Strategy for a Series Hybrid Electric Vehicle," Warrendale, PA, 2nd Edition, 2002.
- 2. Seth Leitman, Bob Brant, "Build Your Own Electric Vehicle," McGraw-Hill, 3rd Edition, 2013.
- 3. C.C. Chan, K.T. Chau, "Modern Electric Vehicle Technology," Oxford University Press, 1st Edition, 2001.

Web References

- 8. https://archive.nptel.ac.in/courses/108/104/108104140/
- 9. https://onlinecourses.nptel.ac.in/noc24_ee30/preview
- 10. https://www.slideshare.net/slideshow/electric-drives-and-controls-unit-1-introduction/250009052
- 11. https://www.mygreatlearning.com/academy/learn-for-free/courses/introduction-to-inverters-and-electric-drive
- 12. https://onlinecourses.swayam2.ac.in/ntr24_ed16/preview

COs/POs/PSOs Mapping

COs		Program Outcomes (POs)												gram Spe	cific SOs)
	PO1	PO2	PO3	PO4	PO5	PO6	PO7	PO8	PO9	PO10	PO11	PO12	PSO1	PSO2	PSO3
1	3	2	3	2	-	2	1	-	2	-	-	2	3	3	3
2	3	2	3	2	-	2	1	-	2	-	-	2	3	3	3
3	3	2	3	2	-	2	1	-	2	-	-	2	3	2	3
4	3	2	3	2	-	2	1	-	2	-	-	2	3	2	3
5	3	2	3	2	-	2	1	-	2	-	-	2	3	2	3

Correlation Level: 1 - Low, 2 - Medium, 3 - High

Evaluation Methods

				##End								
Assessment	Continu	ious Asse	ssment (T	heory)		Contin	uous As:	sessme	ent (Pra	ctical)	Semester Examinatio n (ESE) (Theory)	Total Marks (CAM+ESE)
	CAT 1	CAT 2	Model##	Attendance##	Total	Conduction of Practical	Report	Viva	Total	End Semester Examination (ESE) Marks (Practical)		
Portion for Test	1 ½ Units	1 ½ Units	All 3 Units								All 3 Units	
	MCQ Test	MCQ Test	Written Exam							Practical Exam	Written Exam	
Assessment Methodology	Ana Co 75 Que	stions for lytical urse stions for Course										
Duration of the Test	1 hour 30 Minutes	1 hour 30 Minutes	3 hours							3 hours	3 hours	
Marks	50	50	75	5		15	10	5	30*	30	75 (To be weighted for 50 Marks)	
Weightage of CAM	2.5	2.5	2.5	2.5	10	*To be we	eighted fo	r 10	10	30	,	
CAM / ESE Marks	CAM Marks =10+10+30=50										ESE Marks = 50	100

Distribution of Marks for Attendance, the Question Paper Pattern for Model and ESE are same as given in B.Tech. Regulations R2023 for Theory cum practical Courses



^{*} TE - Theory Exam, LE - Lab Exam

Course Name Prerequisite Course Course Outcomes UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra	CO1 CO2 CO3 CO4 CO5 Model Accele eration dodeling rt - Moc hicles - EV Dri haracteria	Common to all Machines In Mach	Period L 3 to All Bracets will be extric vehicle Power system for ameters, e- Aerody ycles - Coments - ristics -	anches anches able to alcle and ctric vehic gy manage train for the bat modeling namic dra nstant velo	oredictery property received in the context of a context or contex	nt technique alysis back Periods: 10 cceleration of I climbing force ange modeling Periods: 10 cce Character	mance. s an electric e- Accelerat g - Range mance, instics, Elect	BT Ma (Highes K K K c scooter, tion force-odeling of	pping t Level) 3 3 4
Course Name Prerequisite Course Outcomes UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	MODE Electric On co CO1 CO2 CO3 CO4 CO5 Model Accele eration of thicles - EV Dri haracterial	Common to all Machines In Mach	ts will be ectric vehics of electric vehics of electric vehics and energy experience ameters, e- Aerody voles - Components - ristics -	T - anches e able to nicle and etric vehice gy manage train for the bate modeling namic drainstant velocities and the control of the bate	P 2 corediales geme ne ana tery p of a g- Hill pocity re	C 4 ct the performant technique alysis pack Periods: 10 cceleration of ange modeling Periods: 10 cce Character	mance. s an electric e- Accelerat g - Range mance instics, Elect	BT Ma (Highes: K K K c scooter, tion force- odeling of	TM 100 pping t Level) 3 3 4 4
Course Name Prerequisite Course Outcomes UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	MODE Electric On co CO1 CO2 CO3 CO4 CO5 Model Accele eration of thicles - EV Dri haracterial	Common to all Machines In Mach	3 to All Brace ts will be extric vehicle of electric and energical energy energ	anches able to actric vehic gy manage train for the bat modeling namic dra nstant velo	prediction of a control of a co	at the performant technique alysis pack Periods: 10 cceleration of ange modeling Periods: 10 cce Character	mance. s or an electric e- Accelerate g - Range monotonic e- Control or Con	BT Ma (Highes K K K to scooter, tion force- odeling of	pping t Level) 3 3 3 4
Prerequisite E Course Outcomes UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	CO1 CO2 CO3 CO4 CO5 Model Accele eration dodeling rt - Moc hicles - EV Dri haracteria	Common to all Machines Impletion of the course, the student of the course of	to All Branch to	e able to nicle and etric vehice gy manage train for the or the bate modeling namic dra natant velo	oredictery properties of a contraction o	nt technique alysis back Periods: 10 cceleration of climbing force ange modeling Periods: 10 cce Character	mance. s o can electric e- Accelerat g - Range mo o istics, Elect	BT Ma (Highes) K K K K c scooter, tion force- odeling of	pping t Level) 3 3 3 4
Course Outcomes UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	On co CO1 CO2 CO3 CO4 CO5 Model Acceleration Modeling of - Mochicles - EV Driharacteriaracteriaking C	mpletion of the course, the student Apply the concept of modeling for ele Describe the drive train characteristic Analysis the vehicle dynamic control a Design and simulate the Electric Vehic Implement the battery management s ing of Electric Vehicles eration - Acceleration performance para of a small car Tractive Effort- Rolling resistance force deling Electric Vehicle Range - Driving cy fuel cell vehicles - hybrid electric vehicles ve Train Characteristics ristics of EV/HEV Power trains Compositics - Battery Performance Character	ts will be ectric vehors of elected and energical energy cle Power system for ameters, e- Aerody voles - Co	e able to nicle and etric vehice gy manage train for the or the bate modeling namic dra natant velo	les geme ne and tery p of a g- Hil pocity r	nt technique alysis back Periods: 10 cceleration of I climbing force ange modeling Periods: 10 cce Character	s o an electric e- Accelerat g - Range m o ristics, Elect	(Highes K K K K K K K C scooter, tion force-lodeling of tric Motor	t Level) 3 3 3 4 4
Course Outcomes UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	On co CO1 CO2 CO3 CO4 CO5 Model Acceleration Modeling of - Mochicles - EV Driharacteriaracteriaking C	Apply the concept of modeling for electric vehicles a small car. Tractive Effort- Rolling resistance force a small car. Tractive Effort- Rolling resistance force a small car. Tractive Effort- Rolling resistance force deling Electric Vehicle Range - Driving cyfuel cell vehicles - hybrid electric vehicles ve Train Characteristics Tractics of EV/HEV Power trains Compositics - Battery Performance Characteristics	ectric vehics of electric vehics of electric vehicle Power system for ameters, e- Aerody voles - Coments - ristics -	train for the bate modeling namic drainstant velocities of the bate of the bat	les geme ne and tery p of a g- Hil pocity r	nt technique alysis back Periods: 10 cceleration of I climbing force ange modeling Periods: 10 cce Character	s o an electric e- Accelerat g - Range m o ristics, Elect	(Highes K K K K K K K C scooter, tion force-lodeling of tric Motor	t Level) 3 3 3 4 4
Course Outcomes UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	CO1 CO2 CO3 CO4 CO5 Model Acceleration of Modeling of - Modeling of the Acceleration of of the Accelerati	Apply the concept of modeling for electric between the drive train characteristics. Analysis the vehicle dynamic control at Design and simulate the Electric Vehicles Implement the battery management strain of Electric Vehicles eration - Acceleration performance paralof a small car. - Tractive Effort- Rolling resistance force deling Electric Vehicle Range - Driving cyfuel cell vehicles - hybrid electric vehicles (ve Train Characteristics) ristics of EV/HEV Power trains Compositics - Battery Performance Characteristics	ectric vehics of electric vehics of electric vehicle Power system for ameters, e- Aerody voles - Coments - ristics -	train for the bate modeling namic drainstant velocities of the bate of the bat	les geme ne and tery p of a g- Hil pocity r	nt technique alysis back Periods: 10 cceleration of I climbing force ange modeling Periods: 10 cce Character	s o an electric e- Accelerat g - Range m o ristics, Elect	(Highes K K K K K K K C scooter, tion force-lodeling of tric Motor	t Level) 3 3 3 4 4
Course Outcomes UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	CO2 CO3 CO4 CO5 Model Acceleration of Modeling of the Modeling	Describe the drive train characteristic Analysis the vehicle dynamic control at Design and simulate the Electric Vehicles Implement the battery management sing of Electric Vehicles Peration - Acceleration performance paragraph as small car. - Tractive Effort- Rolling resistance force deling Electric Vehicle Range - Driving cyfuel cell vehicles - hybrid electric vehicles (ve Train Characteristics) ristics of EV/HEV Power trains Compositics - Battery Performance Characteristics	cs of electric and energy colors - Connents - ristics -	etric vehic gy manage train for the pr the bat modeling namic dra nstant velo	les geme ne and tery p of a g- Hil pocity r	nt technique alysis back Periods: 10 cceleration of I climbing force ange modeling Periods: 10 cce Character	s o an electric e- Accelerat g - Range m o ristics, Elect	K K K K c scooter, tion force- odeling of	3 3 4 4
UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	CO3 CO4 CO5 Model Acceleration of Modeling rt - Moor hicles - EV Dri haracteria	Analysis the vehicle dynamic control at Design and simulate the Electric Vehicles Implement the battery management sing of Electric Vehicles Peration - Acceleration performance part of a small car. - Tractive Effort- Rolling resistance force deling Electric Vehicle Range - Driving cyfuel cell vehicles - hybrid electric vehicles Ve Train Characteristics Performance Characteristics - Battery Performance Characteristics	and ener cle Power system for ameters, e- Aerody voles - Co soments - ristics -	gy manage train for the bate modeling namic drainstant velocities of the performance of t	geme ne ana tery p of a g- Hil pocity r	Periods: 10 cceleration of ange modeling Periods: 10 cce Character	on electric e- Accelerat g - Range m on	K K K K K K K K K K K K K K K K K K K	3 4 4
UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	Model Acceleration Modeling t - Mochicles - EV Dri haracteria	Design and simulate the Electric Vehic Implement the battery management sing of Electric Vehicles eration - Acceleration performance paraof a small car Tractive Effort- Rolling resistance force deling Electric Vehicle Range - Driving cyfuel cell vehicles - hybrid electric vehicles ve Train Characteristics ristics of EV/HEV Power trains Compositics - Battery Performance Characte	cle Power system for ameters, e- Aerody voles - Co s onents - ristics -	train for the bate modeling namic dranstant velo	of a ocity room	Periods: 10 cceleration of ange modeling Periods: 10 cce Character	on electric e- Accelerat g - Range m on	K. K. c. scooter, tion force-odeling of	4
UNIT - I Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Bi	Model Acceleration of Modeling Acceleration of	Implement the battery management sing of Electric Vehicles eration - Acceleration performance para of a small car Tractive Effort- Rolling resistance force deling Electric Vehicle Range - Driving cy fuel cell vehicles - hybrid electric vehicles ve Train Characteristics ristics of EV/HEV Power trains Compositics - Battery Performance Characte	ameters, e- Aerody vcles - Co conents - ristics -	modeling namic dra nstant velo	of a g- Hil ocity r	Periods: 10 cceleration of climbing force ange modeling Periods: 10 cce Character	an electric e- Accelerat g - Range m 0 ristics, Elect	c scooter, tion force- odeling of	4
Modeling Vehicle modeling of accele Electric Vehicle M Total tractive effort battery electric veh UNIT - II Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	Model Accele eration Modeling of - Modeling of - Modeling hicles - EV Dri haracteri aracteris aking C	ing of Electric Vehicles eration - Acceleration performance para of a small car Tractive Effort- Rolling resistance force deling Electric Vehicle Range - Driving cy fuel cell vehicles - hybrid electric vehicles ve Train Characteristics ristics of EV/HEV Power trains Compo- stics - Battery Performance Characte	ameters, e- Aerody cles - Co conents - ristics -	modeling namic dra nstant velo	of a g- Hil ocity r	Periods: 10 cceleration of I climbing force ange modeling Periods: 10 cce Character	an electric e- Accelerat g - Range m 0 ristics, Elect	tion force- odeling of	
Modeling Vehicle modeling of accele Electric Vehicle Modeling of accele Electric Vehicle Modeling electric vehicle UNIT - II Modeling and Charles Charles Eral Propulsion and Britannia Electric Vehicle Modeling and Charles Eral Propulsion and Britannia Electric Modeling Propulsion and Britannia Electric Modeling Vehicle Modeling and Electric Modeling Vehicle Modeling and Electric Vehicle Modeling Vehicle Modeling and Electric Vehicle Modeling and Charles Vehicle Modeling and Electric Vehicle Modeling and Charles Vehicle Ve	Acceleration of the Accele	ing of Electric Vehicles eration - Acceleration performance para of a small car Tractive Effort- Rolling resistance force deling Electric Vehicle Range - Driving cy fuel cell vehicles - hybrid electric vehicles ve Train Characteristics ristics of EV/HEV Power trains Compo- stics - Battery Performance Characte	ameters, e- Aerody cles - Co conents - ristics -	modeling namic dra nstant velo	of a g- Hil ocity r	Periods: 10 cceleration of I climbing force ange modeling Periods: 10 cce Character	an electric e- Accelerat g - Range m 0 ristics, Elect	tion force- odeling of	CO1
modeling of accele Electric Vehicle Marchine Marchine Marchine Marchine Marchine Marchine Modeling and Charles Brain Propulsion and Brain Electric Vehicle Marchine M	eration of the following of the followin	of a small car. - Tractive Effort- Rolling resistance force deling Electric Vehicle Range - Driving cy fuel cell vehicles - hybrid electric vehicles ve Train Characteristics ristics of EV/HEV Power trains Compositics - Battery Performance Characte	e- Aerody /cles - Co s onents - ristics -	namic dra nstant velo ICE Perfo Transmis	g- Hil ocity r	I climbing force ange modeling Periods: 10 Ince Character	e- Accelerat g - Range m 0 istics, Elect	tion force- odeling of	CO1
Modeling and Ch Performance Cha Regenerative Bra Propulsion and Br	haractei aracteri aking C	ristics of EV/HEV Power trains Compositics - Battery Performance Characte	ristics -	Transmis		ice Character	istics, Elect		
Performance Cha Regenerative Bra Propulsion and Br	aracteri: aking C	stics - Battery Performance Characte	ristics -	Transmis					
Ť		haracteristics - Driving Cycles - Model - Longitudinal Dynamics Equation of Mo alysis.				ectric and Hyl n Modeling a	orid Electric nd Analysis	Vehicles	CO2
		e Dynamic Control and Energy Ma				Periods: 10			
Implementation or Powered Vehicles. Handling Analysis	n Electr s. s of El	lybrid Electric Vehicle Dynamics - Fundaric and Hybrid Vehicles – Case Studies, ectric and Hybrid Electric Vehicles - nergy Management Controllers – Rule	Recharg Simplified	eable Bat I Handling	ery V Moo	ehicles, Hybr dels Energy/F	id Vehicles, Power Alloca	Fuel Cell ation and	СОЗ
······································	Model	ing of EHV Practice -l				Periods: 1	5		
1. Determination	n of So	C, DoD, Cell Cycle for battery							
2. Mathematical	l Modeli	ng of lithium ion cell and design of battery	y pack / fo	rmat.					
•	•	ment of Battery Pack for specified Rating							CO4
		er train Simulation using MATLAB/Simulir							
		ive train Simulation for EVs in MATLAB/S							
······································		Management for Hybrid Electric Vehicles in	n Simulini	(Periods: 1	T		
<u>L</u>		ing of EHV Practice -II		Cyatam (E	NAC)	renous. I	3		
•		iring Diagram for a 36V, 10S Battery Man	•	• `	,	ale			
		iring Diagram and Testing of Smart BMS t System using battery pack equalizer thro					nitorina		
•	•	rammable Battery Management System	Jugii aciiv	C Dalai ICE	vviui	Dideloon IIIO	intolling		CO5
		entation of Conductive Charging Setup							
•	•	Dynamic Control for Hybrid and Battery	Electric V	ehicles					
ecture Periods:		· · · · · · · · · · · · · · · · · · ·		l Period	s: 30		Total Perio	ods: 60	
ext Books						i			
2. Amir Khajepo	our, Sa Approac	n Lowry, "Electric Vehicle Technology Ex _l ber Fallah and AvestaGoodarzi, "Elec h", John Wiley & Sons Ltd, 1 st Edition, 20	tric and						ontrol: A



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- 4. https://www.academia.edu/1003352/A_Matlab_Based_Modeling_and_Simulation_Package_for_Electric_and_Hybrid_Electric_Vehicle_Design
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 - * TE Theory Exam, LE Lab Exam

COs/POs/PSOs Mapping

COs	Program Outcomes (POs)													ram Spe omes (P	
	PO1	PO2	PO3	PO4	PO5	PO6	P07	PO8	PO9	PO10	PO11	PO12	PSO1	PSO2	PSO3
1	3	3	3	3	3	2	2	-	2	2	-	2	3	3	3
2	3	3	3	3	3	2	2	-	2	2	-	2	3	3	3
3	3	3	3	3	3	2	2	-	2	2	-	2	3	3	3
4	3	3	3	3	3	2	2	-	2	2	-	2	3	3	3
5	3	3	3	3	3	2	2	-	2	2	-	2	3	3	3

Correlation Level: 1 - Low, 2 - Medium, 3 - High

Evaluation Methods

			Continuo	us Assessmen	t Marks	(CAM) – Max	cimum 50	Marks			##End	
Assessment	Continuous Assessment (Theory) Continuous Assessment (Practical)										Semester Examinatio n (ESE) (Theory)	Total Marks (CAM+ESE)
	CAT 1	CAT 2	Model##	Attendance##	Total	Conduction of Practical	Report	Viva	Total	End Semester Examination (ESE) Marks (Practical)		
Portion for Test	1 ½ Units	1 ½ Units	All 3 Units								All 3 Units	
	MCQ Test	MCQ Test	Written Exam							Practical Exam	Written Exam	
Assessment Methodology	Ana Co 75 Que	stions for lytical urse stions for Course										
Duration of the Test	1 hour 30 Minutes	1 hour 30 Minutes	3 hours							3 hours	3 hours	
Marks	50	50	75	5		15	10	5	30*	30	75 (To be weighted for 50 Marks)	
Weightage of CAM	2.5	2.5	2.5	2.5	10	*To be we	eighted for farks	r 10	10	30	,	
CAM / ESE Marks	CAM Marks =10+10+30=50								ESE Marks = 50	100		

Distribution of Marks for Attendance, the Question Paper Pattern for Model and ESE are same as given in B.Tech. Regulations R2023 for Theory cum practical Courses



Semester	EEE Programme: B.Tech Honours / Minor -									ehicles	
OGITICOLEI	VIII			Course (Category	/: PC/ IC	End Se	emester E	xam Typ	e : TE *	
C C	1122/7	/T00	E	Per	iods/We	ek	Credit	Credit Maximum I			
Course Code	U23VX	(180	5	L	Т	Р	С	CAM	ESE	TM	
Course Name	AUTO	MOM	OUS AND CONNECTED VEHICLE	S 3	-	-	3	25	75	100	
			Common to	All Branch	ies						
Prerequisite	Electric	al Ve	hicles: Design, Dynamics and T	esting							
	On co	mple	etion of the course, the studer	its will be a	ble to				1	lapping st Level)	
	CO1	Sun	nmarize the advanced driver ass	istance sys	tems for	connect	ed vehic	ele	K2		
Course Outcomes	CO2	Interpret the recent global navigation and Lidar technology for vehicle integration									
	СОЗ	Apply the Perception path, Deep Learning, planning for autonomous and connected vehicles									
	CO4	КЗ									
	CO5	Illus	trate the ECU evolution in archi	ecture by so	oftware o	defined v	ehicles		ŀ	√ 3	
UNIT – I	Auton	omo	us System Architecture				Periods	s: 9			
	h GNSS		ous Vehicle Integration ISS Overview- GNSS Error Anal	vsis- Satellite	e-based	Augment	Periods		ol Timo		
		- GN	ISS Overview- GNSS Error Anal	vsis- Satellite	e-based	Augment	ation Svs	stame- Re	ol Timo		
Localization wit	h LiDAR	and	S- Precise Point Positioning- GNSS High-Definition Maps- LiDAR Ov	INS Integraterview-High-I	ion. Definition	Maps C	verview-	Localizati	on with	CO2	
Localization with LiDAR and HD	h LiDAR Map- Vi	and sual	S- Precise Point Positioning- GNSS	INS Integrat erview-High-I y- Monocular	ion. Definition Visual (Maps C Odometry	verview- Visual	Localizati Inertial Od	on with	CO2	
Localization wit LiDAR and HD Dead Reckoning	h LiDAR Map- Vis g and Wh	and sual eel C ptio r	S- Precise Point Positioning- GNSS High-Definition Maps- LiDAR Ov Odometry- Stereo Visual Odometry Idometry- Wheel Encoders- Wheel	INS Integrat erview-High-l /- Monocular Odometry Err	ion. Definition Visual (ors- Red	Maps C Odometry	verview- Visual	Localizati Inertial Od dometry Er	on with	CO2	
Localization with LiDAR and HD Dead Reckoning UNIT – III Introduction – Date Autonomous Discourage in the production of the production o	h LiDAR Map- Vis g and Wh Perce Perce attasets-riving- C	and sual (eel Coption ption ption ption ption Dete onvol	S- Precise Point Positioning- GNSS High-Definition Maps- LiDAR Ov Odometry- Stereo Visual Odometry Idometry- Wheel Encoders- Wheel	INS Integraterview-High-Ing-Monocular Odometry Erromous Drivertical Flow-on-Semantic	ion. Definition Visual (ors- Red ring Scene For Segme	Maps C Odometry uction of V	Overview- Visual Wheel Oc Periods	Localizati Inertial Od dometry Er :: 9	on with lometry-rors	CO2	
Localization with LiDAR and HD Dead Reckoning UNIT – III Introduction – Date Autonomous Did Planning and Common Line Line Line Line Line Line Line Lin	h LiDAR Map- Vis g and Wh Perce Perce atasets- riving- Control Ove	and sual ceel Coption ption ption Dete	S- Precise Point Positioning- GNSS High-Definition Maps- LiDAR Ov Odometry- Stereo Visual Odometry Idometry- Wheel Encoders- Wheel In and Deep Learning in Auton In Cition- Segmentation- Stereo- Op Outional Neural Networks- Detection	INS Integraterview-High-Ing-Monocular Odometry Erromous Drivertical Flow-on-Semantic	ion. Definition Visual (ors- Red ring Scene For Segme	Maps C Odometry uction of V	Overview- Visual Wheel Oc Periods	Localizati Inertial Od dometry Er :: 9 Deep Lear and Optica	on with lometry-rors		
Localization with LiDAR and HD Dead Reckoning UNIT – III Introduction – Da Autonomous Di Planning and Co UNIT – IV Hardware platfor Resource Mana exploration – Autonomous Autonomous Di Planning and Co	Perce perce atasets- riving- Control Ove Client rm for au agement tonomous	and sual ceel Coption ption Detection Detection System And Detection And Detection Detecti	S- Precise Point Positioning- GNSS High-Definition Maps- LiDAR Ov Odometry- Stereo Visual Odometry Idometry- Wheel Encoders- Wheel In and Deep Learning in Autono In Cition- Segmentation- Stereo- Op Intional Neural Networks- Detection V- Architecture-Traffic Prediction - La	INS Integrate erview-High-ly- Monocular Odometry Erromous Drivetical Flow-tical Flow-on- Semanticane Level Roles overview-isting compu	ion. Definition Visual Cors- Red Ving Scene For Segmenting system realing soluting	Maps Condometry uction of Vertical Properties	Periods Periods Periods Periods	Localizati Inertial Od dometry Er :: 9 Deep Lear and Optica :: 9 nce improrrchitecture	on with lometry-rors rning in al Flow-vement-design		
Localization with LiDAR and HD Dead Reckoning UNIT – III Introduction – Da Autonomous Di Planning and Country UNIT – IV Hardware platfor Resource Mana exploration – Autonomous Autonomous Di Planning and Country – IV	Perce Perce atasets-riving- Control Over Client conomous control control control control conomous control conomous control con	and sual ceel Coption ption Dete convolution System and so Drive - Ve	S- Precise Point Positioning- GNSS High-Definition Maps- LiDAR Ov Odometry- Stereo Visual Odometry Idometry- Wheel Encoders- Wheel In and Deep Learning in Autonom In Cition- Segmentation- Stereo- Op Intional Neural Networks- Detection In Autonomous Priving The Matter Stereo Security- Computing Platform- exving on Mobile Processor- V2V-Sy	INS Integrate erview-High-ly- Monocular Odometry Erromous Drivetical Flow-tical Flow-on- Semanticane Level Roles overview-isting compu	ion. Definition Visual Cors- Red Ving Scene For Segmenting system realing soluting	Maps Condometry uction of Vertical Properties	Periods Periods Periods Periods	Localizati Inertial Od dometry Er S: 9 Deep Lear and Optica S: 9 nce improvement income improvement incom	on with lometry-rors rning in al Flow-vement-design	CO3	
Localization with LiDAR and HD Dead Reckoning UNIT – III Introduction- Da Autonomous Di Planning and Co UNIT – IV Hardware platfor Resource Mana exploration- Aut V2P- System Ar UNIT – V Infrastructure-disconnecting spar	Perce atasets-riving- Control Over Client Cloud Stributed k and RC	and sual (eeel Coption Detection on the convolution of the company	S- Precise Point Positioning- GNSS High-Definition Maps- LiDAR Ov Odometry- Stereo Visual Odometry Odometry- Wheel Encoders- Wheel on and Deep Learning in Automotical Company of the Automotical Company of the Autonomotical Company of the Autonomous Detection of the Autonomous Driving Tems for Autonomous Driving Tems for Autonomous Driving Computing Platform- exping on Mobile Processor- V2V-Synicle Warning Strategy	INS Integrate erview-High-ly- Monocular Ddometry Erromous Drive tical Flow-tical Flow-on- Semanticane Level Roll PS overview-isting computation of the Archite Espark-Train	ion. Definition Visual Cors- Red Ving Scene For Segme uting system ruting solu ecture-Sa	Maps Condensity uction of the content of the conten	Periods Periods Comparison of the comparison of	Localizati Inertial Od dometry Er E: 9 Deep Lear and Optical E: 9 nce improreditecture 21 overvieu E: 9 ion-BINPIF	on with lometry-rors rning in al Flow-vement-design w- BIM-	CO3	
Localization with LiDAR and HD Dead Reckoning UNIT – III Introduction – Date Autonomous Displanning and Company of the Library of the Librar	Perce atasets-riving- Control Over Client Cloud Stributed k and RC ving-Vehi	and sual (eeel Coption Detection on the convolution of the company	S- Precise Point Positioning- GNSS High-Definition Maps- LiDAR Ov Odometry- Stereo Visual Odometry Odometry- Wheel Encoders- Wheel on and Deep Learning in Automote and Neural Networks- Detection - Law Architecture-Traffic Prediction - Law Architecture-Traffic Prediction - Law Department of Processor- V2V-Synicle Warning Platform- expiring on Mobile Processor- V2V-Synicle Warning Strategy "form for Autonomous Driving puting framework-distributed storal processor of Model training-need of Puboard Architecture- ECU software	INS Integrate erview-High-ly- Monocular Ddometry Erromous Drive tical Flow-tical Flow-on- Semanticane Level Roll PS overview-isting computation of the Archite Espark-Train	ion. Definition Visual Cors- Red Ving Scene For Segme uting system ruting solutions ecture-Sa meous co- ing platfor- AUTOS	Maps Condensity of the condens	Periods Periods Comparison of the comparison of	Localizati Inertial Od dometry Er E: 9 Deep Lear and Optical E: 9 nce improreditecture 21 overvieu E: 9 ion-BINPIF	on with lometry-rors rning in al Flow-vement-design w- BIM-PERDD-peration.	CO3	

- 1. Shaoshan Liu, Liyun Li, Jie Tang, Shuang Wu, Jean-Luc Gaudiot, "Creating Autonomous Vehicle Systems", Morgan & Claypool Publishers, 1st Edition, 2018
- 2. Radovan Miucic, "Connected Vehicles: Intelligent Transportation Systems", Springer, 2018

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- 1. Domokos Esztergár-Kiss, Pierluigi Coppola, "Autonomous Vehicles and Future Mobility", Elsevier, 2019.
- 2. Mehrdad Ehsani, Yimin Gao, Ali Emadi, "Modern Electric, Hybrid Electric, and Fuel Cell Vehicles Fundamentals, Theory and Design", CRC Press, 2nd Edition, 2017.



Web References

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- 2. https://www.sciencedirect.com/science/article/pii/S2405896322014446
- 3. https://www.ais.gov.in/
- 4. https://www.opal-rt.com/automotive-overview/
 - * TE Theory Exam, LE Lab Exam

COs/POs/PSOs Mapping

COs		Program Outcomes (POs)											Program Specific Outcomes (PSOs)		
	PO1	PO2	PO3	PO4	PO5	PO6	P07	PO8	PO9	PO10	PO11	PO12	PSO1	PSO2	PSO3
1	3	3	3	2	3	-	-	-	-	-	-	2	3	3	3
2	3	3	3	2	3	-	-	-	-	-	-	2	3	3	3
3	3	3	3	2	3	-	-	-	-	-	-	2	3	3	3
4	3	3	3	2	3	-	-	-	-	-	-	2	3	3	3
5	3	3	3	2	3	-	-	-	-	-	-	2	3	3	3

Correlation Level: 1 - Low, 2 - Medium, 3 - High

Evaluation Methods

		Continuo	ous Asses	sment Marks (C	AM)	End Semester	Total Marks	
	CAT 1	CAT 2	Model##	Assignment#	Attendance##	Examination##	(CAM+ESM)	
Portion for Test	2 Units	2 Units	All 5 Units			All 5 Units		
Assessment	MCQ Test			Individual				
Methodology	Analytica	stions for I Course stions for ourse	Exam	Task#		Written Exam		
Duration of the Test	1 hour 1 hour 30 30 Minutes Minutes		3 hours			3 hours		
Test Marks	50	50	75	20	5	75		
Weightage for CAM	5	5	5	5	5			
CAM / ESE Marks			CAM Ma	arks = 25		ESE Marks = 75	100	

[#] Open Book Analytical Exam/Analyse Real world problems and propose solutions/ Tool or Subject Proficiency Analysis – Test the Students skill by giving individual task/ Paper Presentation/Micro Project Presentation/Idea Presentation for the Societal Problem; (Questions standard shall be of level 3 or more in Blooms Taxonomy)

Distribution of Marks for Attendance, the Question Paper Pattern for Model and ESE are same as given in B. Tech. Regulations R2023 for Theory Courses.



Department	EEE		Programme: B.Tech Honours / Minor - Electric Veh									
Semester	VIII		Course Category: PC/ IC End Semester Exa						ım Type : LE *			
Course Code	11221/	XW806	Per	iods/We	ek	Credit	Credit Maxim		um Marks			
Course Code	UZSV	A44000	L	Т	Р	С	CAM	ESI	E TM			
Course Name	Proje	ct Work	-	-	4	2	50	50	100			
	-	Common to	All Branch	nes				-	•			
Prerequisite			-									
	On completion of the course, the students will be able to											
	CO1	Apply literature survey techniques to identify and define the problem statement for the project										
Course	CO2	Comprehend, plan, and implement a project related to electric mobility										
Outcomes	соз	Develop a real-time application utilizing electric vehicle components, processes, or systems										
	CO4	Interpret and apply knowledge of publication and copyright processes in research										
	CO5	O5 Justify and present project findings through structured oral and written reports										

Course Description

Student must select a project topic either from published lists or propose a suitable topic in consultation with his/her supervisor. The objective of the project is to enhance understanding of fundamental principles by applying them to a new challenge, which may involve designing and manufacturing a device, conducting research, developing a computer or management project, or solving a design problem.

The project progress will be assessed through a minimum of two reviews. The project evaluation shall be carried out by a Project evaluation committee comprising the Head of the Department or his/her nominee (Chairperson), Project coordinator (Professor / Associate Professor) and the project supervisor(s). The End Semester Examination for the project work will include an evaluation of the final project report by an external examiner, followed by a viva-voce examination conducted by a panel comprising the external examiner and an internal examiner.

Lecture Periods: -	Tutorial Periods:-	Practical Periods: 60	Total Periods: 60

* TE – Theory Exam, LE – Lab Exam

COs/POs/PSOs Mapping

COs		Program Outcomes (POs)										Program Specific Outcomes (PSOs)			
	PO1	PO2	PO3	PO4	PO5	PO6	PO7	PO8	PO9	PO10	PO11	PO12	PSO1	PSO2	PSO3
1	3	3	3	2	3	-	-	-	3	3	-	2	3	3	3
2	3	3	3	2	3	2	2	2	3	3	2	2	3	3	3
3	3	3	3	2	3	2	-	-	3	3	2	2	3	3	3
4	3	3	3	2	3	-	2	-	3	3	-	2	3	3	3
5	3	3	3	2	3	-	2	2	3	3	-	2	3	3	3

Correlation Level: 1 - Low, 2 - Medium, 3 - High

Evaluation Methods

SI. No			Weightage		
1	Continuous Assessment M	larks			
-	Review 1	Review Committee	15	25	
а	Review I	Supervisor	10	25	
b	Review 2	Review Committee	15	25	
D	Review 2	Supervisor	10	25	
		•	Total CAM	50	
2	End Semester Marks				
а	Evaluation of project work	Report	15	F0	
	report and Viva-voce	Presentation and Viva	20	50	
		Demonstration	15		
			Total ESM	50	
			Total Marks	100	

