21CSE16	ROBOTICS	L	T	P	C
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Course Objectives

- To understand the functions of the basic components of a Robot.
- To study the use of various types of End of Effectors and Sensors
- To impart knowledge in Robot Kinematics and Programming
- To learn Robot safety issues and economics.

UNIT I	FUNDAMENTALS OF ROBOT	6 Hours

Robot - Definition - Robot Anatomy - Coordinate Systems, Work Envelope Types and Classification- Specifications-Pitch, Yaw, Roll, Joint Notations, Speed of Motion, Pay Load- Robot Parts and their Functions-Need for Robots-Different Applications.

UNIT II	ROBOT DRIVE SYSTEMS AND END EFFECTORS	9 Hours

Pneumatic Drives-Hydraulic Drives-Mechanical Drives-Electrical Drives-D.C. Servo Motors, Stepper Motors, A.C. Servo Motors-Salient Features, Applications and Comparison of all these Drives, End Effectors-Grippers-Mechanical Grippers, Pneumatic and Hydraulic- Grippers, Magnetic Grippers, Vacuum Grippers; Two Fingered and Three Fingered Grippers; Internal Grippers and External Grippers; Selection and Design Considerations.

UNIT III	SENSORS AND MACHINE VISION	12 Hours

Requirements of a sensor, Principles and Applications of the following types of sensors- Position sensors - Piezo Electric Sensor, LVDT, Resolvers, Optical Encoders, pneumatic Position Sensors, Range Sensors Triangulations Principles, Structured, Lighting Approach, Time of Flight, Range Finders, Laser Range Meters, Touch Sensors ,binary Sensors., Analog Sensors, Wrist Sensors, Compliance Sensors, Slip Sensors, Camera, Frame Grabber, Sensing and Digitizing Image Data-Signal Conversion, Image Storage, Lighting Techniques, Image Processing and Analysis-Data Reduction, Segmentation, Feature Extraction, Object Recognition, Other Algorithms, Applications-Inspection, Identification, Visual Serving and Navigation.

UNIT IV	ROBOT KINEMATICS AND ROBOT PROGRAMMING	13 Hours

Forward Kinematics, Inverse Kinematics and Difference; Forward Kinematics and Reverse Kinematics of manipulators with Two, Three Degrees of Freedom (in 2 Dimension), Four Degrees of freedom (in 3 Dimension) Jacobians, Velocity and Forces-Manipulator Dynamics, Trajectory Generator, Manipulator Mechanism Design-Derivations and problems. Lead through Programming, Robot programming Languages-VAL Programming-Motion Commands, Sensor Commands, End Effector commands and simple Programs.

UNIT V	IMPLEMENTATION AND ROBOT ECONOMICS	5 Hours

RGV, AGV; Implementation of Robots in Industries-Various Steps; Safety Considerations for Robot Operations - Economic Analysis of Robots.

UNIT VI	LATEST TRENDS	
Latest Trends		
		TOTAL PERIODS: 45

Course Outcomes:

- The students can be able to apply the basic engineering knowledge for the design of robotics.

Text Books:

1. Klafter R.D., Chmielewski T.A and Negin M., “Robotic Engineering - An Integrated Approach”, Prentice Hall, 2003.
2. Groover M.P., “Industrial Robotics -Technology Programming and Applications”, McGraw Hill, 2001.

Reference Books:

1. Craig J.J., “Introduction to Robotics Mechanics and Control”, Pearson Education, 2008.
2. Deb S.R., “Robotics Technology and Flexible Automation” Tata McGraw Hill Book Co., 1994.
3. Koren Y., “Robotics for Engineers", McGraw Hill Book Co., 1992.
4. Fu.K.S.,Gonzalz R.C. and Lee C.S.G., “Robotics Control, Sensing, Vision and Intelligence”, McGraw Hill Book Co., 1987.