VASAVI COLLEGE OF ENGINEERING (Autonomous)
IBRAHIMBAGH, HYDERABAD – 500 031
DEPARTMENT OF MECHANICAL ENGINEERING
SYLLABUS FOR B.E. V-SEMESTER
INTRODUCTION TO ROBOTICS (Open Elective-III)

L:T:P(Hrs./week):3	SEE Marks : 60	Course Code: U20OE510ME
Credits : 3	CIE Marks: : 40	Duration of SEE: 3 Hours

Course objectives	Course Outcomes
The objectives of this course are to: Identify robots and its peripherals for satisfactory operation and control of robots for industrial and non-industrial applications.	On completion of the course, the student will be able to 1. understand the anatomy of the robot and various robot configurations for it's selection depending on the task. 2. classify the end effectors , understand different types of joints, various types of robot drive systems for carrying out the assigned job effectively. 3. analyze a planar manipulator through forward kinematics and understand the control of robot manipulator for better reliability and efficiency using python programming. 4. Classify the various sensors used in robots for proper selection to an application. 5. summarize various industrial and non-industrial applications of robots for their selection to a particular task.

UNIT-I
ROBOT BASICS
Robot-Basic concepts, Definition, Need, Law, History, Anatomy, specifications.
Robot configurations-cartesian, cylindrical, polar ,articulated and SCARA, Serial manipulator &Parallel Manipulator
Robot wrist mechanism, Precision and accuracy of robot.

UNIT-II
ROBOT ELEMENTS

End effectors-Classification, Robot drive system types: Electrical, pneumatic and hydraulic. Robot joints and links-Types, Motion interpolation, Robot trajectories2D and 3D Transformation- Scaling, Rotation and Translation, Homogeneous transformation

UNIT-III
ROBOT KINEMATICS AND CONTROL
Robot kinematics – Basics of direct and inverse kinematics. D-H matrix. Forward kinematics for a 2-link RR planar manipulator.
Control of robot manipulators – Point to point and Continuous Path Control. Robot programming methods. Introduction to Solve any robotic kinematic problem using python programming.

UNIT-IV
ROBOT SENSORS
Sensors in robots – Touch sensors-Tactile sensors – Proximity and range sensors. Force sensors, Light sensors, Pressure sensors, position and velocity feedback devices.
Introduction to Machine Vision and Artificial Intelligence.

UNIT-V
ROBOT APPLICATIONS
Applications of robots in Industries, Medical, Household, Entertainment, Space, Underwater, Defense, and Disaster management.
Applications of Micro and Nanorobots, Future Applications of robots.

Learning Resources:
1. Mikell P. Groover, Mitchell Weiss, Roger N Nagel and Nicholas G Odrey, "Industrial Robotics   Technology, Programming and Applications", TataMcGraw-Hill Publishing Company Limited , 2008.
2. Deb.S.R and Sankha Deb, "Robotics Technology and Flexible Automation", Tata McGraw Hill Publishing Company Limited, 2010.
3. KlafterR.D, Chmielewski T.A, and Negin. M, "Robotic Engineering: An Integrated Approach",   Prentice Hall of India Pvt. Ltd.,1994.
4. K.S. Fu,R.C. Gonzalez and C.S.G.Lee , "Robotics control, sensing, vision and intelligence",TataMcGraw-Hill Publishing Company Limited, 2008
5. R.K. Mittal and I.J.Nagrath "Robotics and Control", Tata McGraw-Hill Publishing Company Limited, 2003.

The break-up of CIE: Internal Tests+ Assignments + Quizzes

1	No. of Internal Tests:	02	Max.Marks for each Internal Test:	30	
2	No. of Assignments:	03	Max. Marks for each Assignment:	05	
3	No. of Quizzes:	03	Max. Marks for each Quiz Test:	05	

Duration of Internal Test: **1 Hour 30 Minutes**