## 20ME2702B - ROBOTICS

7	ring B	ranches	]	ME										
Course Category:			(	Open Elective -IV							Credits:			3
C	ourse T	Type:	,	Theory	/					Le	cture-Tu Practic		3-	0-0
											Continu Evaluat	ion:	3	30
P	Prerequisites:			-							Semester End Evaluation:		70	
_										7	Total Ma	ırks:	1	00
	e Outc	omes ful com	nlati	on of t	ha cou	rea th	o ctudo	nt wil	l be ab	la to:				
										nd effec	tors rob	not conc	orc	
CO1	progr	amming	and	l applic	ations	i							015,	K2
CO2							es of r	obot a	ctuato	rs, end	effector	S		K2
CO3	Appl	y robot	prog	gramm	ing sk	ills								K3
CO4										tions in				K3
										nent of l				
CO1	PO1 3	PO2 1	203	PO4	PO5	PO6	PO7	PO8	PO9	PO10	PO11	PO12	PSO1 3	PSO2
CO2	3	3											3	1
CO3	3	3	2		2								3	1
CO4	3		2										3	1
Avg.	3	3	2		2								3	1
	1-	Low					2-Me					3-Hi	gh	
UNIT	cla				nation		obotics	s – Hi	istory	of robot				CO1 CO2 CO3 CO4 CO5
	Ro	hat aat	noto	rc_ Pn	eumati	ic, Hyd	Hydraulic actuators, electric & stepper motors effectors, grippers and tools, Requirements and							
UNIT	-2 Er	nd Effection allenges	ctors of e	s- type and effe	es of ectors.	end ef	fectors	s, grip	pers a	nd tool	, 1			CO2
UNIT	-2 Er ch Ro -3 off sir	allenges bot Pro f and or nple pro	of e of e ogra  -line gran	s- type end effe mming e prog ns.	es of ectors. g: - Ro	obot pr	ogram Lead th	ming l	anguaş meth	ges - pro od - Te	ogrammi ach pen	ng meth dent me	ods - ethod,	CO2
	-2 Er ch Ro off sir Se dis acc	allenges bot Pro f and or nple pro nsors us splaceme oustic se	of e ogram n-line gran sed i ent sensor	s- type end effe mming e prog ns. in rob sensors	es of ectors. g: - Rorammi ots: Se s, Force o senso	obot pring - I ensor coe and rs, Rol	ogram cead the devices torque	ming I mrough s, Type senso ion sys	anguage methodes of so	ges - pro od - Tea ensors - roximity	ogrammi ach pen contact,	ng meth dent me position	nods - ethod, n and sors -	CO3
UNIT	-2 Er ch Ro Ro Sir Se Ap pro	allenges bot Pro f and or nple pro nsors us splaceme oustic se	of e ogran n-line gran sed i ent s ensor	s- type and effer mming e prog ns. in rob sensors rs –slip of rob	es of ectors. g: - Rorrammi  ots: So, Force s senso  ots: As, asser	bbot pr ng - I ensor c e and rs, Rol applica nbly, a	ogram. Lead the devices torque bot visition on and ins	ming I mrough s, Type senso ion sys f robo pection	anguag methors of so es of so ors - Pr stems. ots in in	ges - pro od - Te- ensors - roximity industry ations.	ogrammi ach pen contact,	ng meth dent me position	nods - ethod, n and sors -	CO3
UNIT	-2 Er ch Ro Ro Sir Se Ap pro	nd Effect allenges bbot Profession of and or mple profession or nsors use splacement oustic se oplication	of e ogran n-line gran sed i ent s ensor	s- type and effer mming e prog ns. in rob sensors rs –slip of rob	es of ectors. g: - Rorrammi  ots: So, Force s senso  ots: As, asser	bbot pr ng - I ensor c e and rs, Rol applica nbly, a	ogram. Lead the devices torque bot visition on and ins	ming I mrough s, Type senso ion sys f robo pection	anguag methors of so es of so ors - Pr stems. ots in in	ges - pro od - Te- ensors - roximity industry ations.	ogrammi ach pen contact,	ng meth dent me position	nods - ethod, n and sors -	CO3 CO4 CO5 CO1 CO2 CO3 CO4
UNIT	-2 Er ch Ro Ro Sir Se Ap pro	ad Effectallenges both Prof. f and or nple pro nsors us splaceme oustic se oplicatio occessing	of edoration of ed	s- type end effe mming e prog ns. in rob sensors rs –slip of rob rrations  Mikell Applic	es of ectors. g: - Ro rammi  ots: So s, Forc o senso ots: A s, asser  Le P. Gro eations.	end ef bbot pr ng - I ensor ce e and rs, Rol applica mbly, a	ogramme and the devices torque bot visition of and insulation and	ming I mrough s, Type senso ion sys f robo pection Reso rial Ro	anguaga metholes of se o	ges - prod - Telensors - roximity industry ations.	ogrammi ach pen contact, and ra - mater	ng meth dent me positio nge sens rial hand	nods - ethod, n and sors -	CO3  CO4 CO5  CO1 CO2 CO3 CO4 CO5
UNIT UNIT UNIT	-2 Er ch Ro Ro Se dis acc Ap pro-5	ad Effectallenges both Prof. f and or nple pro nsors us splaceme oustic se oplicatio occessing	of e ogran-line gran seed in sensor one ope	s- type end effe mming e prog ns. in rob sensors rs -slip of rob rations  Mikell Applic Roboti	es of ectors.  g: - Rorrammi  ots: So, Force senso  ots: As, asser  Lorrammi	end ef bbot pr ng - I ensor ce e and rs, Rol applica mbly, a earn pover. , McGi neerin	ogramme devices torque bot visition ound insummer ling lindustraw Higg by R	ming lancough  s, Types senso ion sys f robo pection  Reso rial Ro il Co., ichard	anguage methodes of sees of se	ges - prood - Teeensors - roximity industry ations.	ogrammi ach pen contact, and ra - mater	ng meth dent me positio nge sens rial hand grammi	nods - ethod, n and sors -	CO3  CO4 CO5  CO1 CO2 CO3 CO4 CO5

E-Resources & other digital material	1. http://nptel.ac.in/downloads/112101098/	