INTRODUCTION TO INDUSTRIAL ROBOTICS

Course Code	**23ME2601**	**Year**	III	**Semester**	II
Course Category	Open Elective - II	**Branch**	ME	**Course Type**	Theory
Credits	3	**L-T-P**	3-0-0	**Prerequisites**	
Continuous Internal Evaluation:	30	**Semester End Evaluation:**	70	**Total Marks:**	100

Course outcomes: At the end of the course, the student will be able to:

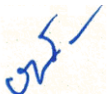
CO	**Statement**	**BTL**	**Units**
CO1	**Explain** the fundamental concepts of automation, robotics, and CAD/CAM integration, and **classify** industrial robots based on coordinate systems, control systems, and structural anatomy, including end-effectors	2	1
CO2	**Compare and analyse** various types of robot actuators such as pneumatic, hydraulic, and electric systems, and **explain** the working of feedback components like position and velocity sensors used in robotic control.	2	2
CO3	**Apply** homogeneous transformation matrices to model robot motion and **solve** problems related to manipulator kinematics using D-H parameters for both forward and inverse kinematics.	3	3
CO4	**Describe** robotic trajectories considering path planning, obstacle avoidance, and motion types using appropriate robot programming languages and tools.	2	4
CO5	**Describe** the basic concepts of machine vision systems and **explain** the image acquisition, digitization, and processing techniques used in robotic applications	2	5

Contribution of Course outcomes towards achievement of programme outcomes & Strength of correlations (High:3, Medium: 2, Low:1)

	PO1	PO2	PO3	PO4	PO5	PO6	PO7	PO8	PO9	PO10	PO11	PO12	PSO1	PSO2
CO 1	3	2											2	
CO 2	3	3								2			2	
CO 3	3	3	2										2	
CO 4	2	3	3	2	3								2	
CO 5	2				3					2			2	

Syllabus		
Unit	**Contents**	**Mapped CO**
1	**INTRODUCTION:** Automation and Robotics, CAD/CAM and Robotics – An overview of Robotics –present and future applications – classification by coordinate system and control system. **COMPONENTS OF THE INDUSTRIAL ROBOTICS:** Robot anatomy, work volume, components, number of degrees of freedom - robot drive systems, function line diagram representation of robot arms, common types of arms –-requirements and challenges of end effectors, determination of the end effectors.	**CO1**
2	**ROBOT ACTUATORS AND FEED BACK COMPONENTS:** **Actuators:** Pneumatic, Hydraulic actuators, electric& stepper motors. Comparison of Electric, Hydraulic and Pneumatic types of actuation devices. **Feedback components:** position sensors–potentiometers, resolvers, encoders–Velocity sensors.	**CO2**
3	**MOTION ANALYSIS:** Homogeneous transformations as applicable to rotation and translation – problems. **MANIPULATOR KINEMATICS:** Specifications of matrices, D-H notation joint coordinates and world coordinates Forward and inverse kinematics–problems.	**CO3**
4	**GENERAL CONSIDERATIONS IN PATH DESCRIPTION AND GENERATION:** Trajectory planning and avoidance of obstacles, path planning, Skew motion, joint integrated motion –straight line motion–Robot programming, languages and software packages-description of paths with a robot programming language.	**CO4**
5	**IMAGE PROCESSING AND MACHINE VISION:** Introduction to Machine Vision, Sensing and Digitizing function in Machine Vision, Training and Vision System, Robotic Applications.	**CO5**

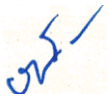
Learning Resources
Text Book(s): 1. Industrial Robotics/Groover MP/Pearson Edu. 2. Robotics and Control /Mittal R K &Nagrathi J /TMH.
References: 1. Robotics/Fu KS/ McGraw Hill. 2. Robotic Engineering /Richard D. Klafter, Prentice Hall 3. Robot Analysis and Control/ H. Asada and J.J.E. Slotine/BSP Books Pvt.Ltd. 4. Introduction to Robotics/John J Craig/PearsonEdu.



Course coordinator HOD

INTRODUCTION to INDUSTRIAL ROBOTICS-MICRO SYLLABUS		
Unit	**Contents**	**Mapped CO**
1	▪ introduction ▪ Automation and Robotics ▪ CAD/CAM and Robotics ▪ An overview of Robotics ▪ present and future applications ▪ classification by coordinate system and control system. ▪ Robot anatomy ▪ work volume ▪ degrees of freedom ▪ robot drive systems ▪ function line diagram representation of robot arms ▪ common types of arms ▪ requirements and challenges of end effectors ▪ determination of the end effectors.	**CO1**
2	▪ actuators: introduction ▪ Pneumatic actuators ▪ Hydraulic actuators ▪ electric& stepper motors. ▪ Comparison of Electric, Hydraulic and Pneumatic types of actuation devices. ▪ Feedback components: introduction ▪ position sensors ▪ potentiometers ▪ resolvers ▪ encoders ▪ Velocity sensors.	**CO2**
3	▪ MOTION ANALYSIS: introduction ▪ Homogeneous transformations as applicable to rotation and translation ▪ Simple problems. ▪ **MANIPULATOR KINEMATICS: introduction** ▪ Specifications of matrices ▪ D-H notation joint coordinates and world coordinates ▪ Forward and inverse kinematics ▪ Simple problems.	**CO3**
4	**GENERAL CONSIDERATIONS IN PATH DESCRIPTION AND GENERATION:** ▪ Trajectory planning ▪ avoidance of obstacles ▪ path planning ▪ Skew motion, ▪ joint integrated motion ▪ straight line motion ▪ Robot programming	**CO4**

	▪ languages and software packages ▪ description of paths with a robot programming language.	
5	**IMAGE PROCESSING AND MACHINE VISION:** ▪ Introduction to Machine Vision ▪ Sensing and Digitizing function in Machine Vision ▪ Training and Vision System ▪ Robotic Applications.	**CO5**



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