

ROBOTICS
(Professional Elective - III)

B.Tech. IV Year I Sem.

L T/P/D C

Course Code: ME733PE/NT743PE

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Pre-requisites: Basic principles of Kinematics and mechanics

Course Objectives: The goal of the course is to familiarize the students with the concepts and techniques in robotic engineering, manipulator kinematics, dynamics and control, chose, and incorporate robotic technology in engineering systems.

- Make the students acquainted with the theoretical aspects of Robotics
- Enable the students to acquire practical experience in the field of Robotics through design projects and case studies.
- Make the students to understand the importance of robots in various fields of engineering.
- Expose the students to various robots and their operational details.

Course Outcomes: At the end of the course, the student will be able to understand the basic components of robots. Differentiate types of robots and robot grippers. Model forward and inverse kinematics of robot manipulators. Analyze forces in links and joints of a robot. Programme a robot to perform tasks in industrial applications. Design intelligent robots using sensors.

UNIT – I

Introduction: Automation and Robotics, CAD/CAM and Robotics – An over view of Robotics – present and future applications.

Components of the Industrial Robotics: common types of arms. Components, Architecture, number of degrees of freedom – Requirements and challenges of end effectors, Design of end effectors, Precision of Movement: Resolution, Accuracy and Repeatability, Speed of Response and Load Carrying Capacity.

UNIT – II

Motion Analysis: Basic Rotation Matrices, Equivalent Axis and Angle, Euler Angles, Composite Rotation Matrices. Homogeneous transformations as applicable to rotation and translation – problems.

Manipulator Kinematics-H notation-H method of Assignment of frames-H Transformation Matrix, joint coordinates and world coordinates, Forward and inverse kinematics – problems on Industrial Robotic Manipulation.

UNIT – III

Differential transformation of manipulators, Jacobians – problems. Dynamics: Lagrange – Euler and Newton – Euler formations – Problems.

Trajectory planning and avoidance of obstacles, path planning, Slew motion, joint interpolated motion – straight line motion.

UNIT IV

Robot actuators and Feedback components:

Actuators: Pneumatic, Hydraulic actuators, electric & stepper motors, comparison of Actuators, Feedback components: position sensors – potentiometers, resolvers, encoders – Velocity sensors, Tactile and Range sensors, Force and Torque sensors.

UNIT V

Robot Application in Manufacturing:

Material Transfer - Material handling, loading and unloading- Processing - spot and continuous arc welding & spray painting - Assembly and Inspection.

TEXT BOOKS:

1. Industrial Robotics / Groover M P /Mc Graw Hill
2. Introduction to Industrial Robotics / Ramachandran Nagarajan / Pearson

REFERENCE BOOKS:

1. Robot Dynamics and Controls / Spony and Vidyasagar / John Wiley
2. Robot Analysis and control / Asada , Slotine / Wiley Inter-Science