SEMESTER S7

ROBOTICS

Course Code	PEMET748	CIE Marks	40
Teaching Hours/Week (L: T:P: R)	3:0:0:0	ESE Marks	60
Credits	3	Exam Hours	2 Hrs. 30 Min.
Prerequisites (if any)	None	Course Type	Theory

Course Objectives:

1. This course helps the student to the basic idea of Robots. Students are introduced to the basic design considerations of robots.
2. Concepts like trajectory planning and obstacle avoidance and kinematics of robots are introduced.
3. Discussion on various mobile robots and robotic manipulators are also included as part of the course to get an overall idea on robotics

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SYLLABUS

Module No.	Syllabus Description	Contact Hours
1	Definitions- Robots, Robotics; Types of Robots- Manipulators, Mobile Robots-wheeled & Legged Robots, Aerial Robots; Anatomy of a robotic manipulator-links, joints, actuators, sensors, controller; open kinematic vs closed kinematic chain; degrees of freedom; Robot configurations-PPP, RPP, RRP, RRR; features of SCARA, PUMA Robots. Classification of End effectors - mechanical grippers, special tools, Magnetic grippers, Vacuum grippers, adhesive grippers, Active and passive grippers, selection and design considerations of grippers in the robot.	9
2	Direct Kinematics- Rotations-Fundamental and composite Rotations, Homogeneous coordinates, Translations and rotations, Composite homogeneous transformations, Screw transformations, Kinematic parameters, The Denavit-Hartenberg (D-H) representation, The arm equation, direct kinematics problems (up to 3DOF). Inverse kinematics-general properties of solutions and problems (up to 3DOF).	10

	Inverse kinematics of 3DOF manipulator with concurrent wrist (demo/assignment only). Tool configuration Jacobian, relation between joint and end effector velocities.	
3	Manipulator Dynamics: Lagrange's formulation – Kinetic Energy expression, velocity Jacobian and Potential Energy expression, Generalised force, Euler-Lagrange equation, Dynamic model of planar and spatial serial robots up to 2 DOF, modelling including motor and gearbox.	**8**
4	Trajectory Planning. Joint space trajectory planning- cubic polynomial, linear trajectory with parabolic blends, trajectory planning with via points; Cartesian space planning, point-to-point vs. continuous path planning. Obstacle avoidance methods- Artificial Potential field, A* algorithms. Robot Control: The control problem, Single axis PID control-its disadvantages, PD gravity control, computed torque control	**9**

Course Assessment Method
(CIE: 40 marks, ESE: 60 marks)

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Continuous Internal Evaluation Marks (CIE):

Attendance	Assignment	Internal Examination-1 (Written)	Internal Examination- 2 (Written)	Total
5	**15**	**10**	**10**	**40**

End Semester Examination Marks (ESE)

In Part A, all questions need to be answered and in Part B, each student can choose any one full question out of two questions

Part A	Part B	Total
• 2 Questions from each module. • Total of 8 Questions, each carrying 3 marks **(8x3 =24marks)**	• Each question carries 9 marks. • Two questions will be given from each module, out of which 1 question should be answered. • Each question can have a maximum of 3 sub divisions. **(4x9 = 36 marks)**	**60**

Course Outcomes (COs)

At the end of the course students should be able to:

Course Outcome		Bloom's Knowledge Level (KL)
CO1	Familiarise with anatomy, specifications and types of Robots	**K2**
CO2	Obtain forward and inverse kinematic models of robotic manipulators	**K2**
CO3	Plan trajectories in joint space & Cartesian space and avoid obstacles while robots are in motion	**K2**
CO4	Develop a dynamic model and design the controller for robotic manipulators	**K2**
CO5	Choose the appropriate Robotic configuration and list the technical specifications for robots used in different application	**K2**

Note: *K1- Remember, K2- Understand, K3- Apply, K4- Analyse, K5- Evaluate, K6- Create*

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CO-PO Mapping Table:

	PO1	PO2	PO3	PO4	PO5	PO6	PO7	PO8	PO9	PO10	PO11	PO12
CO1	2	1	-	-	-	-	-	-	-	-	-	3
CO2	2	1	-	-	-	-	-	-	-	-	-	3
CO3	2	1	-	-	-	-	-	-	-	-	-	3
CO4	3	2	2	-	-	-	-	-	-	-	-	3
CO5	3	2	2	-	-	-	-	-	-	-	-	3

Text Books				
Sl. No	**Title of the Book**	**Name of the Author/s**	**Name of the Publisher**	**Edition and Year**
1	Fundamentals of Robotics – Analysis and Control	Robert. J. Schilling	Prentice Hall of India	1996
2	Introduction to Robotics (Mechanics and Control)	John. J. Craig	Pearson Education Asia	2002
3	Introduction to Robotics	S K Saha,	McGraw Hill Education	
4	Robotics and Control	R K Mittal	Tata McGraw Hill, New Delhi	2003
5	Robotics-Fundamental concepts and analysis	AshitavaGhosal	Oxford University Press	
6	Modern Robotics Mechanics Planning and Control	Kevin M.Lynch, Frank.C.Park	Cambridge University Press	1, 2017
7	Statics and Kinematics with Application to Robotics	Joseph Duffy	Cambridge University Press	1, 2007

Reference Books				
Sl. No	**Title of the Book**	**Name of the Author/s**	**Name of the Publisher**	**Edition and Year**
1	Handbook of Robotics	Siciliano, Khatib	Springer	
2	, Introduction to Robotics – Mechanics and Control	John J. Craig		
3	Modern Robotics Mechanics, Planning and Control	. Kevin M. Lynch, Frank C. Park,		
4	Robotics Modelling, Planning and Control	Bruno Siciliano, Lorenzo Sciavicco, Luigi Villani, Giuseppe Oriolo	Springer	

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Video Links (NPTEL, SWAYAM…)	
Module No.	**Link ID**
1	https://archive.nptel.ac.in/courses/112/105/112105249/
2	https://archive.nptel.ac.in/courses/112/105/112105249/
3	https://archive.nptel.ac.in/courses/112/105/112105249/
4	https://archive.nptel.ac.in/courses/112/105/112105249/