	marks	question	A	B	C	D	ans
0	1	Unit of network is-	Neuron	Neural dendrites	ANN	Fibers of nerves	Neuron is the most basic and fundamental unit of network
1	1	Depth First search algorithm is equvalent to-	Pre-Order Traversal	In-Order Traversal	Post-Order Traversal	All of the above	DFS is equivalent to Pre-Order Traversal.
2	1	Chemical rection in Neuron is called-	Synapses	Chemial process	Axon	None	Because of biological fact.
3	1	The dendrites shape look like-	Tree	Rectangular	Square	Circle	Dendrites are like projections function is only to recive impulse.
4	1	The cell is said to be fired?	if potential of body reaches a steady threshold value	if potential of body do not show any threshold value	if potential of body reaches a high threshold value	All of the above	Cell is said to be fired when potential of body reaches a certain steady threshold value.
5	1	Problem in search space is defined by	Initial state	Final State	Current State	None	Initial state defines the problem in search space.
6	1	which strategy is used for problem specific knowledge-	All	BFS	Heuristic Search	Informed Search	BFS, Heuristic Search and Informed search is used for problem specific knowledge.
7	2	What is Artificial Intelligence?	Making a machine intellligent	Making a machine durable	Making a machine operatable	Making a machine.	This is an explaination.
8	2	Application of breadth first search-	All	Finding shortest path between two nodes	In Peer to Peer Networks	In Social Media Platforms	This is an explaination.
9	2	What algorithm of data structure used in standard implementation of breadth first search-	Queue	Stack	Both a and b	None	Queue is used to implement BFS.
10	2	Write the work of Axon-	Transmission	Replicate	Control	Both transmission and replicate	Axon is the body of neron and thus cant be at ends of it so can not recive and transmit singnals
11	2	What is used to improve the performance of heuristic search?	Quality of heuristic funtion	Functional Dependency	Data set	None	Quality of the function is used to improve the performance.
12	2	Hill climbing algorithm stops when-	No neighbour has higher value	All neighbour has higher values	No neighbour has lower values	All neighbour has lower values	Hill Climbing algorithms stops as no neighbours has higher values.

	marks	question	A	B	C	D	ans
13	2	Removing detail from a given state representation is called-	Abstraction	Extraction	Absorbtion	All	Removing detail from a given state representation is called Abstraction.
14	2	Hill climbing approach stuck for the following reasons-	Both	Local maxima	Ri-dges	None	Hill Climbimg approach stucks because of local maxima and ridges
15	2	Representing your problem with variable & parameter is defined as-	State Space	Search Space	Both a and b	None	Representing your problem with variable & parameter is defined as State Space.
16	2	A search algorithm takes_____as an input & return solution as an output.	Problem	Data	Initial state	All	A search algorithm takes problem as an input & return solution as an output.
17	2	which method is used to expand the node that is closest to the goal?	Greedy BFS	Hill Climbing	DFS	BFS	Greedy BFS is used to expand the node that is closest to the goal.
18	2	What is the general formula that is used to calculate the leas number of moves required to solve a Tower of Hanoi with 3pegs and n dishes? (Eg-> 1,3,7,15.....)	(2<^n)-1	(2^n)+1	(2^n)-2	(2^n)+2	This is an explaination.
19	2	What is used in mapping sentence plan into sentence structure	Text Realization	Text Proofing	Text Rooting	All of the above	Text Realization is used in mapping sentence plan into sentence structure.
20	2	Which of the following search is complete &optimal when h(n) is consistent	A* search	Heuristic Search	BFS search	DFS search	A* Search is complete and optimal when h(n) is consistent.
21	2	In greedy approach, function of evalution is-	Path cost from start node to current node+heuristic cost	Path cost from last node +heuristic cost	Heuristic cost	None	Function of evaluation in a greedy approach is path cost from start node to current node+heuristic cost
22	2	Which is not a backtracking algorithm?	Tower of Hanoi	Travelling Salesman Problem	N Queen problem	Knight Tour problem	Tower of Hanoi is not a back tracking algorithm.
23	2	A* algorithm is-	BFS	DFS	Both a and b	None	This is an explaination.

	marks	question	A	B	C	D	ans
24	2	Main component of neural liquified?	Potassium	Sodium	Iron	Nickle	Potassium is the main constituent of neuron liquid and responsible for potential on neuron body
25	3	Types of informed search method are-	4	3	2	5	This is an explaination.
26	3	Complexity of DFS is (v=vertices, E = edges):	o(V+E)	o(V)	o(E)	None	This is an explaination.
27	3	The result of breadth first search traversal is-	Tree	Rectangle	Graph with back edge	All of the above	The result of a BFS traversal is a tree.
28	3	A problem solving approach works well for-	Mars hoves	8 puzzle	8 queen	Hill Climbing	A problem solving approach works well for Mars Hoves.
29	3	Heuristic function h(n) is-	Estimated cost of cheapest path from root to goal node	The function h(n) is an admissible heuristic	Estimated cost of highest path from goal to root node	All	This is an explaination.
30	1	8- Queen problem domination number is	5	6	4	2	8- Queen problem domination number is 5
31	1	backtracking approch is used to solve:	Combinational problems	NP problems	NP hard problems	Arithmetic Problems	Backtracking approach is used to solve complax problems which cannot be solved by exhaustive serach algoritham.
32	1	Divide and Conquer algoritham will work on:	Subgoal independence	Supergoal independence	Both a and b	None	This is an explaination.
33	1	Queens can attack each other in how many ways?	3	2	4	5	Queens can attack each other in 3 ways
34	1	How many states are available in state space approch:	4	3	2	5	There are four states available in state space search. They are initial state, actions, goal test and step cost.
35	2	Placing n Queen in a chess board here no 2 Queen can attack each other is called as:	N Queen	Hypothesis	8 Queen problem	All	This is an explaination.
36	2	Who published the eight queen puzzle:	Max Bezzel	Franz Nauck	carl	Friedrich	The first Eight Queen Puzzle was published by Max Friedrich william Bezzel.

	marks	question	A	B	C	D	ans
37	2	What are the components of partial order planning:	All	Goal	Casual links	Binding	This is an explaination.
38	2	Brute force technique is not slower than:	Backtracking algorithm	8-Queen's Problem	Knapsack Problem	All	Brute force technique is not slower than back tracking problem.
39	2	Which of the following is an application of Backtracking?	All	Crossword	Puzzles	N-Queens Problem	This is an explaination.
40	2	Initial state + goal stack in search terminology for:	Problem Instance	Space complexity	Time Instance	All	Initial state + goal stack in search terminology for problem instance
41	2	A constructive approach in which no commitment is made unless it is necessary to do:	Least commitment approach	High commitment approach	No commitment approach	None	This is an explaination.
42	2	Rule-based systems are also called?	Expert System	Constraint systems	Fact System	None	This is an explaination.
43	2	Total order planning is opposite of:	Partial order planning	No order planning	Null order planning	Half-order planning	Total order planning is opposite of partial order planning.
44	2	How many types of rule based system are there?	2	3	4	1	There are 2 types of Rule based systems.
45	2	Who coined the term "Backtrack"?	Lehmer	Ravin Russo	Bell	None	The term "backtrack" was coined by American mathematician D. H. Lehmer in the 1950s.
46	2	Rule based system was developed in?	1917	1920	1900	1915	This is an explaination.
47	2	How many solutions does a 10-Queen problem has:	724	756	512	256	This is an explaination.
48	2	In how many ways, we can solve state-space search:	2	3	5	4	We can solve state space search using two ways.
49	3	Rules are expressed by a set of:	If then statement	If then else statement	For statement	While Statement.	Rules are expressed as a set combination of if and then statemtn.
50	3	Which of the following is a drawback of planning system:	A lot of computation is needed	Space complexity	Time complexity	All	Main drawback of planning system is that it requires a lot of computation at each node.
51	3	Backward state space search is also called :	Reqression planning	Regresssion Conntrol	ML algorithm	ML Planning	This is an explaination.

	marks	question	A	B	C	D	ans
52	3	Space complexity of DFS is:	O(h)	O(nlogh)	O(n)	O(h^2)	Space complexity of DFS is O(h) where h is the height of the tree.
53	3	Time complexity of Backtracking Algorithm is	O(NK)	O(N)	O(K)	O(1)	Time complexity of Backtracking Algorithm is O(NK).
54	3	Constraint propogation works using _____ variables?	3	2	4	6	Constraint propogation works using 3 variables i.e. y, t and z.
55	3	The most number of possible solutions for 8-queen problem is:	92	56	70	64	This is an explaination.
56	3	Time complexity of Breadth first search algorithm:	b^d	O(n)	O(nlogn)	O(1)	This is an explaination.
57	3	What is the application of backtracking algoritham:	Crossword	Puzzles	Knapsack Problem	Travelling Salesman problem	Crossword puzzle are based on backtracking approch whereas the rest are travelling slesman problem, knapsack problem and dice game.
58	3	The most straight forward approach for plannig algorithm:	State space search	Dijikstra algorithm	Greedy approach	Divide and conquer technique	This is an explaination.
59	3	To which depth , Alpha - Beta pruning can be applied:	Any depth	Half Depth	NO depth	Least depth	To which depth , Alpha - Beta pruning can be applied to any depth
60	1	The face recognizition system is based on-	Applied AI approch	ML Approach	Regression approach	Cloud approach	Face recognizition system is based on applied AI approach.
61	1	Agents can improve its performance by-	Learning	Cloning	Fusion	None	This is an explaination.
62	1	Agents can select its external action by-	Performance	Learning	Prediction	All	Agents can select its external action by Performance.
63	1	Simple reflex agents action completely depends -	Current perception	Past Perception	Both a and b	None	Simple reflex agents action completely depends current perception.
64	1	A preposition is also known as	Declarative statement which is either true or false	Declarative statement which is yes	Declarative statement which is no.	Assumptive statement which is either yes or no.	A preposition is also known as declarative statement which is either true or false.

	marks	question	A	B	C	D	ans
65	2	Two propositions are said to be logically equivalent:	If and only if the columns in the truth table are identical to each other	If and only if the rows in the truth table are identical to each other	If and only if the columns in the truth table are not identical to each other	All	Two propositions are said to be logically equivalent if and only if the columns in the truth table are identical to each other.
66	2	What are the properties of Forward chaining-	All	It is a process of making a conclusion based on known facts or data	It is a down-up approch as it moves from bottom to top	Forward - chaining approach is commonly used in the expert system	This is an explaination.
67	2	what is Meronymy relation	A is part of B	B is a part of A	Both a and b	None	A meronym denotes a constituent part of or a member of something. That is,\n“X” is a meronym of “Y” if Xs are parts of Y(s), or\n“X” is a meronym of “Y” if Xs are members of Y(s)
68	2	How we can create compound prepositions:	With the help of logic connective	By the help of connective	Help of contradiction	Help of tautology	We can create compound prepositions with the help of logic connective
69	2	A propositional formula which is always false is called	Contradiction	Tautology	Both a and b	None	A propositional formula which is always false is called contradiction.
70	2	Limitaion of semantic networks :	Lack in expressing some of the properties	Lack in space complexity	Lack in time complexity	All	This is an explaination.
71	2	Backward chaining algorithm is same as	DFS algorithm	BFS algorithm	Regression algorithm	Hypothesis algorithm	It is depth first search algorithm because is space requirements are linear is the size f the proof
72	2	What are the basic element of propositional logic:	Both	Propositions	Connectives	None	This is an explaination.
73	2	A frame is also known as_____in artificial intelligence.	Slot filter knowledge representation	Slot representation	Filter representation	Slot filter representation	A frame is also known as Slot filter knowledge representation in artificial intelligence.

	marks	question	A	B	C	D	ans
74	2	Semantic network represents:	Semantic relation between concepts	Semantic relation between nodes	Semantic relation between arguments	Semantic relation between approaches	This is an explaination.
75	2	What is used in backward chaining algorithm	Composition of substitution	Composition of diffusion	Composition	Compostion of Predicate	Compostion of substitution is used in backward chaining algorithm.
76	2	What are syntaxes-	The rules which divides how we can contruct legal sentences in the logic	The rules which unites how we can destruct legal sentences.	The rules which divides how we can contruct the logic	All	The rules which divides how we can contruct legal sentences in the logic
77	2	what is Holonymy relation-	B is a part of A	A is a part of B	Both a and b	None	a hyponym is a word or phrase whose semantic field is included within that of another word, its hypernym
78	2	Production rules system consists of pairs which means	If condition then action	If condition	If then else condition	Eliff Condition	This is an explaination.
79	2	Logical representation can be divided into -	Both	Prepositional logics	Predicate logics	None	This is an explaination.
80	2	Semantic network are mojority used for-	Supporting conceptual edition	Supporting navigation	both a and b	None	This is an explaination.
81	2	A propositional formula which is always true is called	Tautology	Contradiction	Propositional Logic	All	A propositional formula which is always true is called Tautology
82	3	What are the types of propositions:	Both	Atomic	Compound	None	This is an explaination.
83	3	What are the limitations of propositional logic:	All	Necessity and possibilty are also not captured in propositional logic	Propositional logic has limited expressive power	Weak generalization power	This is an explaination.
84	3	Logic programming is mainly used to check the working process of which system-	Automated Reasoning	Artificial Intelligence	ML algorithm	Propositional Network	Logic programming is mainly used to check the working process of automated reasoning system-
85	3	What is known as infererece rules-	Templates for generating valid arguments.	Templates for generating arguments.	Templates for arguments.	Templates for generating non valid arguments.	Inference rules are templates for generating valid arguments.

	marks	question	A	B	C	D	ans
86	3	Forward chaining approach is also called-	Data driven approach	Logic driven approach	Argument driven approach	All	Forward-chaining approach is also called as data-driven as we reach to the goal using available data.
87	3	Directed graph gives the representation of which network-	Semantic network	ANN network	Logical Network	Propositional Netwrok	This is an explaination.
88	3	Hypothetical syllogism is a type of-	Inference rule	Predicate rule	Propositional rule	Chaining rule	Hypothetical syllogism is a type of Inference rule.
89	3	Semantic networks are alternative of:	Predicate logic	Pseudo code	Prepositional Logic	All	Semantic networks are alternative of predicate logics.
90	1	Another task can be performed by boltzman machine:	Pattern association	Speech recognition	Image preception	All	This is an explaination.
91	1	What is the full form of NLP:	Natural Language Processing	Neutral Language Processing	Nature Logic Process	Neural Logic Programming	This is an explaination.
92	1	What is the full from of NLG:	Natural Language Genration	Nature Language Genetic	Natural Logic Genetic	Nature Language Genration	NLG stands for Natural Language Generation
93	1	How many compoments are there in NLP:	2	3	6	4	There are 2 components in NLP
94	1	What is the result when mean field approximation is used with boltzmann learning:	It speed up	It slows down	No change	Equal	When mean field approximation is used with boltzmann learning, it speeeds up.
95	2	Rectifier is also known as:	Ramp Function	Activation Function	Axon	ANN	Rectifier is also known as Ramp function.
96	2	In which year, invention of first artificial neural network is:	1958	1856	1957	1959	First invention of ANN was done in 1958
97	2	Function of a real variable is a function whose domain is:	Real Number	Integers	Positive Numbers	All	function of a real variable is a function whose domain is the real numbers
98	2	In ANN feedforword , the flow of information is:	Unidirectional	Multidirectional	Equal	All the above	Feedforword ANN the informationflow is unidirectional
99	2	What is the classical example of unsupervised learning in the study of neutral network is:	Donald Hebb's Principle	Dijikstra's Algorithm	N-Queen Problem	NP problems	This is an explaination.

	marks	question	A	B	C	D	ans
100	2	What is the method used in unsupervised learning:	Principal component & Cluster analysis	Neural Networks	Regression	Classification	This is an explaination.
101	2	Neurocomputer was invented by:	Dr. Robert Heet-Nielsen	Dijikstra	J L Baird	None	This is an explaination.
102	2	What is the major test of NLP:	Automatic summarization	Information retrival	Automatic ques.- ans. System	All the above	Automatic summarization is the major test of NLP
103	2	which statement is true- (i) Neuro software is designed to aid experts in real world. (ii) Nero software is powerful and easy neural network:	(ii)	Both are correct	(i)	None are correct	This is an explaination.
104	2	What are the challenges with reinforcement learning:	Preparing the simulation environment	Data set	Data cleaning	Data Transformation	This is an explaination.
105	2	A unit employing the rectifier is also called:	Rectified Linear Unit(ReLu)	ANN	Robotics	Axons	A unit employing the rectifier is also called a rectified linear unit (ReLU)
106	2	The weighted sum in ANN is also called:	Activation	Weighted sum	ANN	Nonr	This is an explaination.
107	2	How many layers are there in "Shallow" :	Three	Two	Four	Six	There are 3 layers in shallow.
108	3	Elementary unit in ANN is:	Neurons	Edges	Activation function	All	This is an explaination.
109	3	Ising model of a neural network is called:	Hopfield Networks	ANN	Axon	Sigmoid	Ising model of a neural network is called Hopfield Networks.
110	3	Loops are allowed in which ANN:	Feedback ANN	Forward ANN	Both a and b	None	This is an explaination.
111	3	Feedforward and feedback are the type of which network:	ANN (Artifical Neural Network)	Regression	Classification	Hypothesis	This is an explaination.
112	3	Heavy side step function is also known as:	Unit step function	ANN	Activation function	Sigmoid	Heavy side step function is alsp called unit step function.
113	3	What is node value:	Output of each node	Input of node	Both a and b	None	This is an explaination.
114	3	The connections are also called_____ in ANN.	Edges	Neurons	Weights	Axons	The connections are also called Edges.
115	3	What is the main drowback of NLP:	Handling ambiguity of sentances	Linguistres	POS-Tagging handling	All the above	There are enormous ambiguity exists when processing natural language

	marks	question	A	B	C	D	ans
116	3	A_____ is an activation function defined as the positive part of its argument.	Rectifier	ANN network	Axon	Neuron	Rectifier is an activation function defined as the positive part of its argument:
117	3	Which is the most popular activation function for deep neural networks.	Rectifier	Axons	Neurons	All	The rectifier is, as of 2017, the most popular activation function for deep neural networks.
118	3	Boltzmann Machine is of How many types:	3	4	2	5	Boltzmann Machine is of 3 types.
119	3	Objective of feature maps :	To capture the features in space of input patterns	To capture the features in space of output patterns	To capture the features in time of input patterns	To capture the features in time of output patterns	Objective of feature map is to capture the features in space of input patterns
120	1	The message sent from robot sensors to robot controllers are known as:	Feedback	Acknowledment	Reciept	All	The message sent from robot sensors to robot controllers are known as Feedback.
121	1	Select the place where the the operation of the robots is least:	Privates homes	Industry	Medical	Research	This is an explaination.
122	2	Robotics intitute of American robotics center is located out :	CMU	LMU	UNR	All	This is an explaination.
123	2	Decision support program help managers in:	Business Decisions	Market visiting	Recognition	All	This is an explaination.
124	2	Which gas is used to drive the robot devices :	Pneumatic	Photosenstive	Noble	All	This is an explaination.
125	2	What is the application of robotics:	All	Medical	Military	Research	This is an explaination.
126	2	For hardware and software_____is not the advantages with a robotics implementation program :	Low cost	High cost	Programming	None	For hardware and software low cost is not the advantages with a robotics implementation program :
127	2	If a robot has k legs, number of possible events will be :	N= (2k-1)!	N=2k	N=k+1	N-=2k+1	This is an explaination.
128	2	Ultrasonic sensor is a type of :	Proximity sensor	Genomic Sensor	Neural Sensor	None	Ultrasonic sensor is a type of proximity sensor
129	2	Actuators are also known as:	Drives	Peripheral tools	Neurons	Axon	This is an explaination.
130	2	A robotic manipulator is also known as :	Robotic arms	Whell	Activation function	Sigmoid	This is an explaination.

	marks	question	A	B	C	D	ans
131	2	If a robot can change its trajectory with external condition , it is said to be :	Intelligent	Clever	Trained	All	If a robot can change its trajectory with external condition , it is said to be intelligent.
132	2	What do you understand by "humanoid" robot :	A robot which looks like overall as a human body	Human made robot	Human recognizing robot	All	Humanoid robot is a robot which looks like overall as a human body
133	2	Select the one that is not a basic part of robot :	Peripheral tools	Neurons	Axons	Machinery	Peripheral tools are not a basic part of robots.
134	2	Collaborative robots are also known as:	Cobots	Cola Robots	Human Robots	All	This is an explaination.
135	2	HRI stands for:	Human Robot Interface	Human Resource Interface	Human Robot Initialization	None	This is an explaination.
136	2	What are the basic aspect of robotics :	All	Electrical	Mechanical	Computer programs	This is an explaination.
137	3	Programming a robot by physically moving through projectory, it is called :	Continous path control	Discrete path control	Both a and b	None	This is an explaination.
138	3	is not an essential components for construction of robot :	Energy	ANN	Neurons	All	This is an explaination.
139	3	How many degrees of freedom would the robot have :	6	8	4	2	A robot has 6 degree of freedom
140	3	How many Laws of Robotics are there?	3	4	2	5	This is an explaination.
141	3	Which of the following is a type of "humanoid " robots :	Both	Android humanoid	Gynoids humanoid	None	This is an explaination.
142	3	Plug and Pray was released in:	2010	2009	2011	2013	This is an explaination.
143	3	Which wheel used to rotates around the wheel axle and contact :	Standard wheel	Rotatory Wheel	Frictive Wheel	None	This is an explaination.
144	3	Cobots were invented in which year?	1996	1998	2000	2004	Cobots were inventedbin the 1996 year
145	3	What was the first industrial robot :	Unimate	Kinztech	Both a and b	None	Unimate was first industrial robot.
146	3	Rotational motion of a robot arm refers to :	Roll	Sigmoid	Axon	Alll	Rotational motion of a robot arm refers to roll.

	marks	question	A	B	C	D	ans
147	3	A type of robot which can perform any task with autonomous is called :	Autonomous robot	Humanoid Robot	Electro Robot	All	A type of robot which can perform any task with autonomous is called Autonomous Robot.
148	3	Physical structure of robot which moves around is called :	Manipulator	Actuator	Arm	None	Physical structure of robot which moves around is called Manipulator
149	3	Ultrasonic actuators are designed to produce movements in a micrometer order at ultrasonic frequencies of:	20 kHz	40 kHz	30 kHz	50 kHz	Ultrasonic actuators are designed to produce movements in a micrometer order at ultrasonic frequencies (over 20 kHz).
150	1	Which of the following is not a programming language for computer controlled robot :	AMU	VAL	RAIL	HELP	This is an explaination.
151	1	The robot designed with cartesian co-ordinate system has :	Three linear movement	Four linear movement	Two linear movement	One linear movement	The robot designed with cartesian co-ordinate system has three linear movement.
152	1	Recursive Filtering is also called:	Infinite Impulsive Response	Impulsive Response	Infinite Response	None	Recursive filtering is also known as Infinite Impulsive Response.
153	1	The robot designed with cylindrical co-ordinate system has :	Two linear and one rotational movement	One linear and one rotational movement	Two linear and no rotational movement	NO linear and one rotational movement	The robot designed with cylindrical co-ordinate system has two linear and one rotational movement
154	2	The basic principle for the agriculture robot is :	Thestability factor	Linear Factor	Coordinate factor	All	This is an explaination.
155	2	Which person used the name "robot" first time in print :	Isaac asimov	Donald Heeb	Dijikstra	None	Issac Asimov used the name "robot" first time.
156	2	The .....used to provide autometed crop survey as well as to measure crop nutrients status :	Portal robot	Human Robot	Both	None	The Portal Robot used to provide autometed crop survey as well as to measure crop nutrients status :
157	2	Robot toy for kids was:	Furby	Roomba	Looj	RoboCup	Robot toy for kids was Furby
158	2	Servo motors are driven by	Signals	Voltage	Current	All	Servo motors are driven by signals

	marks	question	A	B	C	D	ans
159	2	The Space Robotics Technical Committee has _____ main areas of interest.	2	3	6	4	The Space Robotics Technical Committee has two main areas of interest
160	2	MF scamp robots are designed for	All	Harvesting and Picking	Scouting	Weeding	This is an explaination.
161	2	What form of renewable energy can some automove use :	Solar energy	Wind Energy	Hydra Energy	All	This is an explaination.
162	2	How many types of signal processing are available:	6	5	4	3	There are 6 types of sinal processing.
163	2	Icub was developed by which county	Italy	Japan	India	China	This is an explaination.
164	2	Brick Laying Robot was developed by;	Fast brick Robotics	Doxel	SafeAI	Steer	Brick Laying Robot was developed by Fast brick Robotics
165	2	What are the applications of agrecultural Robot :	All mentioned	Harvesting and Picking	Utility Platforms	Phenotyping	This is an explaination.
166	2	Automated drone seeders are mostly used in	Forestry Industry	Crop Industry	Farming	Mechanic Department	Automated drone seeders are mostly used in Forestry.
167	2	What does the "Ironing "robot look like :	Inflatable dummy	Humans	Both a and b	None	The "Ironing "robot look like inflatable dummy.
168	3	The_____platform is used for selective harvesting of fruits which detects fruits	CROP robotics	Crop mechanism	Robotics	All	The CROP Robotics platform is used for selective harvesting of fruits which detects fruits
169	3	Humanoid Robot developed by Honda in 2000 was:	ASIMO	Atlas	Roomba	RoboCup	Humanoid Robot developed by Honda in 2000 was ASIMO
170	3	.....is an multipurpose robotic plateform for applications in agriculture :	BoniRob	GIThub	ANM	All	This is an explaination.
171	3	Rice Planting Robot was developed by which country:	Japan	USA	India	China	Rice Planting Robot was developed by Japan.
172	3	Educational robot developed in 1980 was called:	HERO	Topo	Roomba	All	Educational robot developed in 1980 was called HERO
173	3	Furby was developed in	1998	2000	2002	2001	Furby was developed in 1998
174	3	Manual controls give home-owner..... with robot :	Two - way communication	One way communication	Both a and b	None	This is an explaination.

	marks	question	A	B	C	D	ans
175	3	Proprioception is the sense of self-movement and body position. It is also called	Kinesthesia	Prosthesia	Both	None	Proprioception also referred to as kinaesthesia (or kinesthesia), is the sense of self-movement and body position.
176	3	What do you people often put on a robot when it is going be repaired :	A mark	Mole	Credentials	All	people often put a mark on a robot when it is going be repaired
177	3	An autonomous modular multipurpose robot was developed by:	Saga Robotics	Bell Robotics	Both	None	An autonomous modular multipurpose robot was developed by Saga Roboticss.
178	3	Autonomous Robots are also called:	Autobot	Bot	No-Bot	All	Autonomous Robots are also called Autobot
179	3	Humanoid Robot developed by NASA was:	Valkyrie	Atlas	Icub	All	Humanoid Robot developed by NASA was Valkyrie