1. Robotics is a branch of AI, which is composed of \_\_\_\_\_\_\_\_\_\_\_.

A. Electrical Engineering  
B. Mechanical Engineering  
C. Computer Science  
D. All of the above

View Answer

Ans : A

Explanation: Robotics is a branch of AI, which is composed of Electrical Engineering, Mechanical Engineering, and Computer Science for designing, construction, and application of robots.

2. If a robot has k legs, then the number of possible events is :

A. N = (2k-2)  
B. N = (2k-1)!  
C. N = (2^k-1)!  
D. N = (2k-2)!

View Answer

Ans : B

Explanation: If a robot has k legs, then the number of possible events N = (2k-1)!.

3. Name the wheel which is used to rotates around the wheel axle and around the contact.

A. Castor wheel  
B. Standard wheel  
C. Swedish 45degree  
D. spherical wheel

View Answer

Ans : B

Explanation: Standard wheel : Rotates around the wheel axle and around the contact

4. What is the name for information sent from robot sensors to robot controllers?

A. temperature  
B. pressure  
C. feedback  
D. signal

View Answer

Ans : C

Explanation: feedback is the name for information sent from robot sensors to robot controllers.

5. For a robot unit to be considered a functional industrial robot, typically, how many degrees of freedom would the robot have?

A. 4  
B. 5  
C. 6  
D. 7

View Answer

Ans : C

Explanation: six degrees of freedom would the robot have.

6. Which of the following statements concerning the implementation of robotic systems is correct?

A. implementation of robots CAN save existing jobs  
B. implementation of robots CAN create new jobs  
C. robotics could prevent a business from closing  
D. All of the above

View Answer

Ans : D

Explanation: All Options are correct.

7. One of the leading American robotics centers is the Robotics Institute located at?

A. CMU  
B. MIT  
C. RAND  
D. SRI

View Answer

Ans : A

Explanation: One of the leading American robotics centers is the Robotics Institute located at CMU.

8. What is full form of OCR in tasks of Computer Vision?

A. Optimum Character Reader  
B. Optical Character Reader  
C. Optimum Castor Reader  
D. Optical Castor Reader

View Answer

Ans : B

Explanation: Optical Character Reader is the full form of OCR.

9. Which of the following is not application domains of Computer Vision?

A. Agriculture  
B. Biometrics  
C. Page control  
D. Transport

View Answer

Ans : C

Explanation: Page control is not application domains of Computer Vision.

10. computer vision plays vital role in the domains of \_\_\_\_\_\_\_\_\_\_.

A. safety  
B. security  
C. health  
D. All of the above

View Answer

Ans : D

Explanation: The computer vision plays vital role in the domains of safety, security, health, access, and entertainment.

11. Which of the following is not a type of Robot Locomotion?

A. Legged  
B. Wheeled  
C. Tracked deslip  
D. Tracked skid

View Answer

Ans : C

Explanation: Tracked deslip is not a type of Robot Locomotion.

12. If a robot has 3 legs, then the number of possible events is :

A. 24  
B. 720  
C. 120  
D. 240

View Answer

Ans : C

Explanation: The number of possible events N = 120

13. Which of the following is not an essential components for construction of robots?

A. Power Supply  
B. Actuators  
C. Sensors  
D. Energy

View Answer

Ans : D

Explanation: Engery is not an essential components for construction of robots.

14. Which of the following terms IS NOT one of the five basic parts of a robot?

A. peripheral tools  
B. end effectors  
C. controller  
D. drive

View Answer

Ans : A

Explanation: peripheral tools is not one of the five basic parts of a robot.

15. Decision support programs are designed to help managers make \_\_\_\_\_\_\_\_\_\_

A. budget projections  
B. visual presentations  
C. business decisions  
D. vacation schedules

View Answer

Ans : C

Explanation: Decision support programs are designed to help managers make business decisions.

16. In LISP, the function returns t if <object> is a CONS cell and nil otherwise

A. (cons <object>)  
B. (consp <object>)  
C. (eq <object>)  
D. (cous = <object>)

View Answer

Ans : B

Explanation: In LISP, the function returns t if <object> is a CONS cell and nil otherwise (consp <object>)

17. Which of the following terms refers to the use of compressed gasses to drive (power) the robot device?

A. pneumatic  
B. piezoelectric  
C. hydraulic  
D. photosensitive

View Answer

Ans : A

Explanation: pneumatic use of compressed gasses to drive (power) the robot device.

18. What is true about Robots?

A. They operate in real physical world  
B. Inputs to robots is analog signal in the form of speech waveform or images  
C. They need special hardware with sensors and effectors.  
D. All of the above

View Answer

Ans : D

Explanation: All Options are correct.

19. Which of the following is not application of Robotics?

A. Industries  
B. Military  
C. Medicine  
D. Hills

View Answer

Ans : D

Explanation: Hills is not Applications of Robotics.

20. Name the component of robot which is used to contract almost 40% when air is sucked in them.

A. Actuators  
B. Muscle Wires  
C. Pneumatic Air Muscles  
D. Sensors

View Answer

Ans : C

Explanation: Pneumatic Air Muscles : They contract almost 40% when air is sucked in them.