

Code: 15MC62T

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Register					
Number					

VI Semester Diploma Examination, Nov./Dec.-2018

ROBOTICS

Time	: 3 Hours]	[Max. Marks : 100			
Note .	(i) Answer any six questions from Part A. (ii) Answer any seven full questions from Part B.	y:			
	PART – A				
1.	Explain the work volume and accuracy of robot.	5			
2.	Explain the tactile sensors used in robot.	5			
3.	With sketch explain force sensing wrist.	FOXY ORO			
4.	Explain how image is stored in vision system.	5			
	BETA CONSOLE				
5.	Explain the robot vision system in inspection	5			
6.	Explain constants and variable in VAL language.	5			
7.	Explain speed control statement in VAL languages.	5			
8.	Explain ADD commands in lisp programming.	5			
9.	Explain list commands in lisp programming with example.	5			
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PART – B

. (a) Explain with neat sketch cylindrical configuration of a robot.	5
(b) Explain the types of joints used in robot.	5
Explain with sketch basic robot motions.	8
(b) Explain any two advantages of Industrial robot.	2
Explain with sketch the actuation of a gripper by using cam.	5
Explain with sketch proximity sensor using reflected light against sensor array.	5
(b) Explain the target of considered in selection and design of grippers.	6
- replain the types of grippers used in robot.	4
(a) Explain with abotals	
(b) Explain edge detection in the residue of vidicon camera.	7
read the defection in high level vision system.	3
Explain manual and power load at	3
and power lead through method of robot programming	10
(a) Explain MOVE and role 1	10
(b) Explain problem revisited statements in VAL language.	
proofern representation technique in Artificial Intelligen	5
Explain MIN and PLUG	5
and I LOS commands in Lisp programming with	
Explain pick and place at	10
rade place robot.	
Explain robots in automata 1.	10
automated inspections.	
	10
	(a) Explain with sketch the actuation of a gripper by using cam. (b) Explain with sketch the actuation of a gripper by using cam. (a) Explain with sketch the actuation of a gripper by using cam. (b) Explain with sketch proximity sensor using reflected light against sensor array. (a) Explain the factors considered in selection and design of grippers. (b) Explain the types of grippers used in robot. (a) Explain with sketch working principle of vidicon camera. (b) Explain edge detection in high level vision system. FOXY ORO Explain manual and power lead through method of robot programming. (a) Explain MOVE and related statements in VAL language. (b) Explain problem representation technique in Artificial Intelligence (AI). Explain MIN and PLUS commands in Lisp programming with example. Explain pick and place robot.