

Reg No.: \_\_\_\_\_

Name: \_\_\_\_\_

**APJ ABDUL KALAM TECHNOLOGICAL UNIVERSITY**  
Sixth semester B.Tech degree examinations (S), September 2020

**Course Code: EC368**

**Course Name: Robotics**

Max. Marks: 100

Duration: 3 Hours

**PART A**

*Answer any two full questions, each carries 15 marks*

Marks

- |   |    |  |      |
|---|----|--|------|
| 1 | a) | Compare spherical and cylindrical robot configurations   | (8)  |
|   | b) | How robots are classified according to JIRA?   | (7)  |
| 2 | a) | Write a short note on Force-Torque sensors.  | (5)  |
|   | b) | Compare the different drive technologies of a Robot.   | (10) |
| 3 | a) | Explain the principle of operation of Stepper Motor.   | (8)  |
|   | b) | Apply the concepts of speed and direction control of an electric motor using a microprocessor. | (7)  |

**PART B**

*Answer any two full questions, each carries 15 marks*

- |   |    |   |      |
|---|----|---|------|
| 4 | a) | What are the sources of noise? What are the different methods to reduce noise?  | (7)  |
|   | b) | What are the different levels of image processing? Mention different methods of image processing.                           | (8)  |
| 5 | a) | Explain about joint angle, joint distance, link length and link twist with the help of D-H representation.                  | (10) |
|   | b) | Compare Rotation matrix and Homogenous Transformation matrix.   | (5)  |
| 6 | a) | Derive the rotation matrix for a sequence of rotations: $\Psi$ about OX axis, $\theta$ about OY axis, $\phi$ about OZ axis. | (8)  |
|   | b) | Derive the matrix representing the orientation change with Euler angles.  | (7)  |

**PART C**

*Answer any two full questions, each carries 20 marks*

- |   |    |   |      |
|---|----|---|------|
| 7 | a) | What is meant by singularities in the context of velocity kinematics? | (5)  |
|   | b) | Explain about Mobile robots.  | (5)  |
|   | c) | Explain the structure of robot programming language.                  | (10) |

- 8 a) Write VAL commands for controlling end-effector motions of a robot. (5)  
b) Explain the use of robots in medical applications. (10)  
c) What is meant by manipulator Jacobian? (5)
- 9 a) Explain robot actuation and control methods with block diagrams (10)  
b) Which are the robot programming methods? (10)

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