REFERENCE BOOKS:
1. **O Levine Transitions to Agile Manufacturing,** Joseph C Moutigomery and Lawrurence – Staying Flexible for competitive advantage, ASQC quality press, Milwaukee. Wisconsiw, USA 1996
2. **Agile Development for Mass Customization,** David M Andeson and B Joseph Pine, Irwin Professional Publishing, Chicogo USa 1997

ROBOTICS

Subject Code	: 10ME766	IA Marks	: 25
Hours/Week	: 04	Exam Hours	: 03
Total Hours	: 52	Exam Marks	: 100

PART – A

UNIT - 1

Introduction and Mathematical Representation of Robots: History of Robots, Types of Robots, Notation, Position and Orientation of a Rigid Body, Some Properties of Rotation Matrices, Successive Rotations, Euler Angles For fixed frames X- Y -Z and moving frame ZYZ. Transformation between coordinate system, Homogeneous coordinates, Properties of A/BT, Types of Joints: Rotary, Prismatic joint, Cylindrical joint, Spherical joint, Representation of Links using Denvit - Hartenberg Parameters: Link parameters for intermediate, first and last links, Link transformation matrices, Transformation matrices of 3R manipulator, PUMA560 manipulator, SCARA manipulator

07 Hours

UNIT - 2

Kinematics of Serial Manipulators: Direct kinematics of 2R, 3R, RRP, RPR manipulator, puma560 manipulator, SCARA manipulator, Stanford arm, Inverse kinematics of 2R, 3R manipulator, puma560 manipulator.

06 Hours

UNIT – 3

Velocity and Static's of Manipulators: Differential relationships, Jacobian, Differential motions of a frame (translation and rotation), Linear and angular velocity of a rigid body, Linear and angular velocities of links in serial manipulators, 2R, 3R manipulators, Jacobian of serial manipulator, Velocity ellipse of 2R manipulator, Singularities of 2R manipulators, Statics of serial manipulators, Static force and torque analysis of 3R manipulator, Singularity in force domain.

07 Hours

UNIT - 4

Dynamics of Manipulators: Kinetic energy, Potential energy, Equation of motion using Lagrangian, Equation of motions of one and two degree freedom spring mass damper systems using Lagrangian formulation, Inertia of a link, Recursive formulation of Dynamics using Newton Euler equation, Equation of motion of 2R manipulator using Lagrangian Newton-Euler formulation.

06 Hours

PART-B

UNIT - 5

Trajectory Planning: Joint space schemes, cubic trajectory, Joint space schemes with via points, Cubic trajectory with a via point, Third order polynomial trajectory planning, Linear segments with parabolic blends, Cartesian space schemes, Cartesian straight line and circular motion planning

07 Hours

UNIT - 6

Control: Feedback control of a single link manipulator- first order, second order system, PID control, PID control of multi link manipulator, Force control of manipulator, force control of single mass, Partitioning a task for force and position control- lever, peg in hole Hybrid force and position controller.

08 Hours

UNIT - 7

Actuators: Types, Characteristics of actuating system: weight, power-to-weight ratio, operating pressure, stiffness vs. compliance, Use of reduction gears, comparision of hydraulic, electric, pneumatic actuators, Hydraulic actuators, proportional feedback control, Electric motors: DC motors, Reversible AC motors, Brushles DC motors, Stepper motors- structure and principle of operation, stepper motor speed-torque characteristics

06 Hours

UNIT - 8

Sensors: Sensor characteristics, Position sensors- potentiometers, Encoders, LVDT, Resolvers, Displacement sensor, Velocity sensor-encoders, tachometers, Acceleration sensors, Force and Pressure sensors piezoelectric, force sensing resistor, Torque sensors, Touch and tactile sensor, Proximity sensors-magnetic, optical, ultrasonic, inductive, capacitive, eddy-current proximity sensors.

05 Hours

TEXT BOOKS:
1. **Fundamental Concepts and Analysis,** Ghosal A., Robotics, Oxford,2006
2. **Introduction to Robotics Analysis, Systems, Applications**, Niku, S. B., Pearso Education, 2008

REFERENCE BOOKS:
1. **Introduction to Robotics: Mechanica and Control,** Craig, J. J., 2nd :J?:dition, Addison-Welsey, 1989.
2. **Fundamentals of Robotics, Analysis and Control**, Schilling R. J., PHI, 2006