S.NO	TOPICS	QUESTIONS	A	B	C	D	ANSWERS
1	Robot programming: Robot Languages, Classification of robot language	Which of the following is not a programming language for computer controlled robot?	AMU	VAL	RAIL	HELP	A
		Which of the following is not a programming method?	Manual method	Lead through method	Walkthrough method	GUI Method	D
		The _____ methods require the programmer to move the manipulator through the desired motion path	Manual method	Lead through method	Walkthrough method	GUI Method	B
		_____ programming is similar to that of computer programming	Manual method	Lead through method	Textual	GUI Method	C
		_____ leadthrough method makes use of a teach pendent to control the various joint motors	Powered	Manual	Textual	GUI Method	A
		_____ leadthrough method is more readily used for continuous path programming	Powered	Manual	Textual	GUI Method	B
2	Computer control and robot software	A small hand held control box used to control robot's physical movements is called _____.	Teach Pendent	Path Controller	CPU	Teaching device	A
		Which of the following is not a 'method of teaching'?	Tool coordinate motion	Joint movements	XYZ coordinate motion	Base control motion	C
		Reason for defining points: I. To define a working position for the end effector II. To avoid obstacle	I is correct	Only II is correct	Both I and II	None of these	C
		For many commercially available robots, _____ interpolation is the default procedure that is used by the controller.	Joint	Straight Line	Circular	Irregular	A
3	Val system and Languages	VAL Stands for _____	Varied Assembly Language	Validity Assembly Language	Variable Assembly Language	Value-Oriented Algorithmic Language	C
		Control programs are written on _____ computer that controls the robot.	a different	the same	the server	inbuilt	B
		A convenient feature or VAL is the ability to use _____ or manipulation _____.	database, loops	database, routines	libraries, routines	libraries, loops	C
		A _____ signifies the command can be performed when VAL is in its top-level monitor mode and no user program being executed	dot (.)	asterisk (*)	angle brackets (<>)	Square brackets ([ ])	A
		An _____ indicates the command can be performed at the same time VAL is executing the program	dot (.)	asterisk (*)	angle brackets (<>)	Square brackets ([ ])	B
4	Robot cell layout	Name the layout in which the robot is located at the approximate centre of the cell.	Robot centred	In line robot	Mobile robot	None of these	A
		Name the layout in which the robot is located along a moving conveyor or other handling system.	Robot centred	In line robot	Mobile robot	None of these	B
		Which of the transfer mechanisms cannot be used in In line cell configuration	Intermittent	Continuous	Non-synchronous	Batch	D
		_____ moves the part with a start-and-stop motion from one workstation along the line to the next.	Intermittent	Continuous	Non-synchronous	Batch	A
		_____ moves the work parts are moved continuously along the line at constant speed	Intermittent	Continuous	Non-synchronous	Batch	B
5	Work cell design and control	In which cell layout the robot is capable of moving to various pieces of equipment within the cell.	Robot centred	In line robot	Mobile robot	None of these	C
		At the pickup point the parts must be in a known _____ to enable the robot to grasp and hold it consistently and accurately	Position	Orientation	Angle	None of these	B
		Which of these is not a subset of a work cell control?	Sequence Control	Operator Control	Safety monitoring	Preventive Maintenance	D

		What is the primary function of the workstation controller during regular automatic operation of the work cell.	Sequence Control	Operator Control	Safety monitoring	Preventive Maintenance	A
		The purpose of _____ interface in workstation control is to provide a means for human operators to interact with the operation of the cell.	Sequence	Operator Interface	Safety monitoring	Preventive Maintenance	B
6	Robot cycle time analysis	Abbreviate MTM	Mean Time Measurement	Methods Time Measurement	Mark to Market	Methods Transport Management	B
		_____ is the period required to complete one cycle of an operation	Cycle time analysis	Time graph	Frequency	Speed analysis	A
		Abbreviate RTM	Ready time measurement	Robot time and motion	robot time management	None of these	B
		The elements which represent manipulator movements is _____	Motion	Sensing	End effector	Delay	A
		The element which relate to the action of the gripper or tool attached to the robot wrist	Motion	Sensing	End effector	Delay	C
7	Application : Humanoid Robot, Quad copter, Gecko Robot, LEGO kits	A _____ is a robot with its body shape built to resemble the human body.	Humanoid Robot	Quad copter	Gecko robot	Lego kits	A
		A _____ is a multirotor helicopter that is lifted and propelled by four rotors.	Humanoid Robot	Quad copter	Gecko robot	Lego kits	B
		Which of the following is a wall climbing robot?	Humanoid Robot	Quad copter	Gecko robot	Lego kits	C
		The _____ contain software and hardware to create customizable, programmable robots. They include an intelligent brick computer that controls the system, a set of modular sensors and motors to create a mechanical system	Humanoid Robot	Quad copter	Gecko robot	Lego kits	D