

These are sample MCQs to indicate pattern, may or may not appear in examination

University of Mumbai
Online Examination 2020

Program: BE Automobile Engineering

Curriculum Scheme: Revised 2012

Examination: Fourth Year Semester VII

Course Code: AEE7016 and Course Name: Industrial Robotics

Time: 1hour

Max. Marks: 50

Note to the students:- All the Questions are compulsory and carry equal marks .

Q1.	Which is not the part of Robots Definition?
Option A:	Reprogrammable
Option B:	Multifunctional
Option C:	Variable programmed
Option D:	Dynamic
Q2.	To lift heavy load which configuration of industrial robot is preferred?
Option A:	Cartesien
Option B:	Polar
Option C:	Cylindrical
Option D:	Articulated
Q3.	In _____ joint, motion is achieved by piston, a telescopic mechanism and a relative motion along a linear track or rail.
Option A:	Prismatic joint
Option B:	Rotational joint
Option C:	Twisting joint

Option D:	Revolving joint
Q4.	In order to use circular interpolation for programming, how many points need to lie along the circle?
Option A:	2
Option B:	3
Option C:	4
Option D:	6
Q5.	In AGVs, the magnetic field produced by the cable induces an alternating voltage in a pair of coils often in the _____.
Option A:	Powered wheel assembly
Option B:	Steered wheel assembly
Option C:	Unpowered wheel assembly
Option D:	Castor wheel assembly
Q6.	During introducing robotics into a firm, It is important that management provide continuous support and encouragement during _____ period.
Option A:	Study
Option B:	Application
Option C:	Startup
Option D:	installation
Q7.	In presence of robots, greater responsibility for the overall process may lead to _____ job stress.
Option A:	Less
Option B:	Greater
Option C:	Same
Option D:	Variable
Q8.	What is full form of SCARA?
Option A:	Selective Compliance Assembly Robot Arm

Option B:	Selective Complex Assembly Robotic Arm
Option C:	Selective Complex Assesmbly Robotic Armor
Option D:	Selective Compliance Angular Robot Arm
Q9.	In DH parameter "a" denotes_____.
Option A:	Link twist
Option B:	Link length
Option C:	Link offset
Option D:	Joint angle
Q10.	AML programming language was introduced by_____.
Option A:	Microsoft
Option B:	Google
Option C:	IBM
Option D:	Macintosh
Q11.	_____are means to high density hands free buffering of materials in distribution and manufacturing environments.
Option A:	Flexible system
Option B:	Automated guided vehicles
Option C:	Conveyors
Option D:	Automated storage and retrival system
Q12.	The operation that consists of a sequence of work elements that are performed over and over is called_____.
Option A:	Toxic operations
Option B:	Difficult operations
Option C:	Repetitive operations
Option D:	Critical operations
Q13.	Future robots will be mobile, able to move under their own power and _____systems.

Option A:	Navigation systems
Option B:	Engines
Option C:	Tyers
Option D:	Susspension systems
Q14.	_____ is inclined to leak oil which is a nuisance.
Option A:	Pneumatic drive system
Option B:	Hydraulic drive system
Option C:	Electric drive system
Option D:	Geared system
Q15.	To describe the _____ of the tool with respect to the base frame it is necessary to know and formulate the body attached co-ordinate frame along the joint axis for each links in the manipulator chain of the robot.
Option A:	Position and orientation
Option B:	Dynamics
Option C:	Range and Proximity
Option D:	Jerk
Q16.	_____ programming language was developed by General Electric company to control two robot at the same time.
Option A:	HELP
Option B:	VAL
Option C:	AML
Option D:	RAIL
Q17.	In AS/RS _____ are the unit load containers used to hold the inventory items.
Option A:	Storage structure
Option B:	Bay
Option C:	Storage module
Option D:	Asile unit

Q18.	For spray coating which configuration of robot is best?
Option A:	Polar configuration
Option B:	Cylindrical configuration
Option C:	SCARA
Option D:	Jointed arm
Q19.	Tasks in future will require higher levels of intelligence and _____ capabilities form the robot.
Option A:	Decision making
Option B:	Project management
Option C:	Decision tree
Option D:	Simple
Q20.	Any vision system apart from capturing images does two very important thing and these are _____.
Option A:	Image extraction and compression
Option B:	Image processing and image analysis
Option C:	Image capture and compression
Option D:	Image capture and storage
Q21.	_____ is used to find joint angle given the end effector position.
Option A:	Inverse kinematics
Option B:	Forward kinematics
Option C:	Inverse dynamics
Option D:	Forward dynamics
Q22.	During inspection which sensor is mostly used by inspection robots?
Option A:	Tectile sensor
Option B:	Vision sensor
Option C:	Laser sensor
Option D:	Infrared sensor

Q23.	Training in the _____ of robots is intended for engineers and managers who are responsible for implementing robot projects in the company.
Option A:	Awareness
Option B:	Justification
Option C:	Operations and maintenance
Option D:	Safety
Q24.	These are used today for simple transactions such as deposits and withdrawals.
Option A:	Flexible Tellers
Option B:	Automatic tellers
Option C:	Fixed tellers
Option D:	Soft tellers
Q25.	_____ programming uses an english like language to establish the logic and sequence of the work cycle.
Option A:	Lead through programming
Option B:	Powered lead through programming
Option C:	Manual lead through programming
Option D:	Textual programming