

STUDY MODULE DESCRIPTION FORM		
Name of the module/subject Robotics		Code 1010331251010332162
Field of study Automatic Control and Robotics	Profile of study (general academic, practical) (brak)	Year /Semester 3 / 5
Elective path/specialty -	Subject offered in: Polish	Course (compulsory, elective) obligatory
Cycle of study: First-cycle studies	Form of study (full-time, part-time) full-time	
No. of hours Lecture: 30 Classes: 30 Laboratory: - Project/seminars: -		No. of credits 5
Status of the course in the study program (Basic, major, other) (brak)		(university-wide, from another field) (brak)
Education areas and fields of science and art study effects leading to the acquisition of engineering qualifications technical sciences		ECTS distribution (number and %) 5 100% 5 100%
Responsible for subject / lecturer: dr inż. Jarosław Warczyński, doc. email: jaroslaw.warczyński@put.poznan.pl tel. 61 665 2374 Faculty of Electrical Engineering ul. Piotrowo 3A 60-965 Poznań		
Prerequisites in terms of knowledge, skills and social competencies:		
1	Knowledge	Knowledge from the field of mathematics necessary for analysis and simulation of dynamical systems in time domain. Knowledge from the selected fields of physics necessary to understand basic physical phenomena encountered in elements, devices and systems of control and robotics and their environment. Systematized theoretical background from the field of analytical mechanics necessary to understand issues of modelling and construction of mechanical systems.
2	Skills	K_U01: Student is able to gain information from literature, data basis and other springs. Has skills in selfeducation aimed in leveraging and actuation of professional competences. K_U03: Student can elaborate documentations and presentations of results achieved in solving engineering tasks. Student can elaborate algorithms for solving simple engineering tasks, implement, test and deploy them in chosen programming environment under selected operation systems on the PC computer.
3	Social competencies	K_K04: Student is aware of the necessity of professional approach to technical tasks, closely reading documentations, taking in account environmental conditions for elements and devises to function in. Student is also aware of the necessity of preserving principles of professional ethics, paying regard to different opinions and cultures.
Assumptions and objectives of the course: Acquaintance of knowledge about robot control algorithms and about controlling robot interactions with environment .		
Study outcomes and reference to the educational results for a field of study		
Knowledge:		
1. [K_W07] - [-] 2. [K_W16] - [-] 3. [K_W19] - [-] 4. [K_W21] - [-]		
Skills:		

1. [K_U05] - [-]
2. [K_U08] - [-]
3. [K_U17] - [-]
4. [K_U21] - [-]

Social competencies:
1. [K_K02] - [-]
2. [K_K06] - [-]

Assessment methods of study outcomes

Examinations and exercises.

Course description

Statics of robots. Robot control systems: Independent joint control. Point-to-point motion control. Path motion control. Inverse dynamics control. Computed torque feedforward control Manipulator interaction with environment: Compliance control. Force control with inner position loop. Force control with inner velocity loop. Hybrid position/force control. Impedance control. Adaptive robot control. Basics of the trajectory planning and robot programming.

Basic bibliography:

1. Buratowski, T.: Podstawy robotyki. AGH Uczelniane Wydawnictwa Naukowo-Dydaktyczne, Kraków, 2006.
2. Craig, J.J.: Wprowadzenie do robotyki. Mechanika i sterowanie, WNT 1993.
3. Fu, K.S R.C. Gonzalez, C.S.G. Lee: Robotics: Control, Sensing, Vision, and Intelligence, McGraw-Hill Book Comp.1989.
4. Jezierski, E.: Dynamika robotów. WNT, Warszawa, 2006.

Additional bibliography:

1. McKerrow, Ph. J.: Introduction to Robotics, Addison-Wesley 1991.
2. Morecki, A., Knapczyk, J.: Podstawy robotyki. Teoria i elementy manipulatorów. WNT, Warszawa, 1999.
3. Paul, R.P: Robot Manipulators: Mathematics, Control, and Programming, Boston MIT Press 1981.
4. Spong, M. W., M. Vidyasagar: Dynamika i sterowanie robotów WNT Warszawa 1997.

Result of average student's workload

Activity	Time (working hours)

Student's workload

Source of workload	hours	ECTS
Total workload	120	5
Contact hours	65	3
Practical activities	30	2